

# EECS 370 - Lecture 12

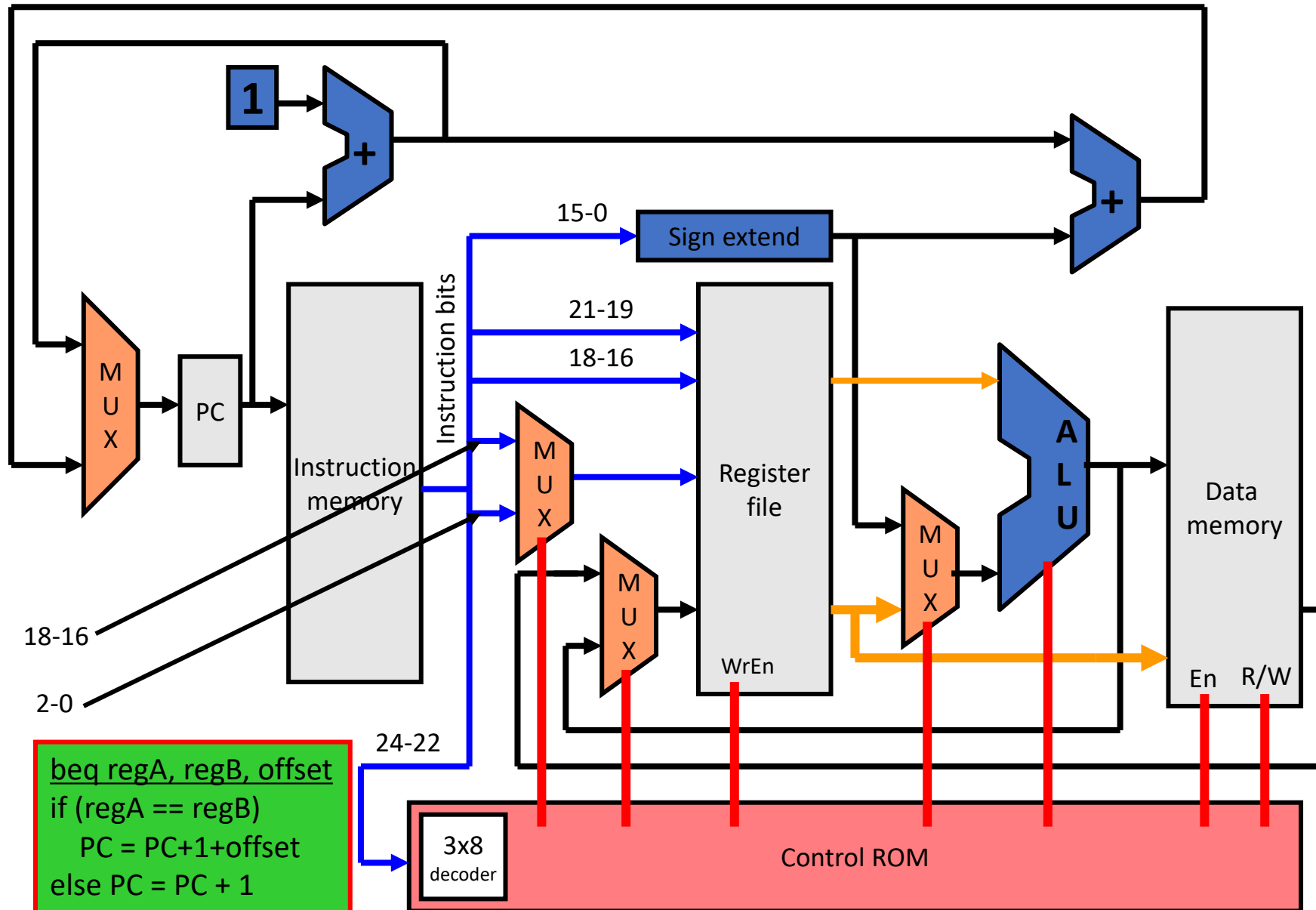
## Multi-cycle + Introduction to Pipelining



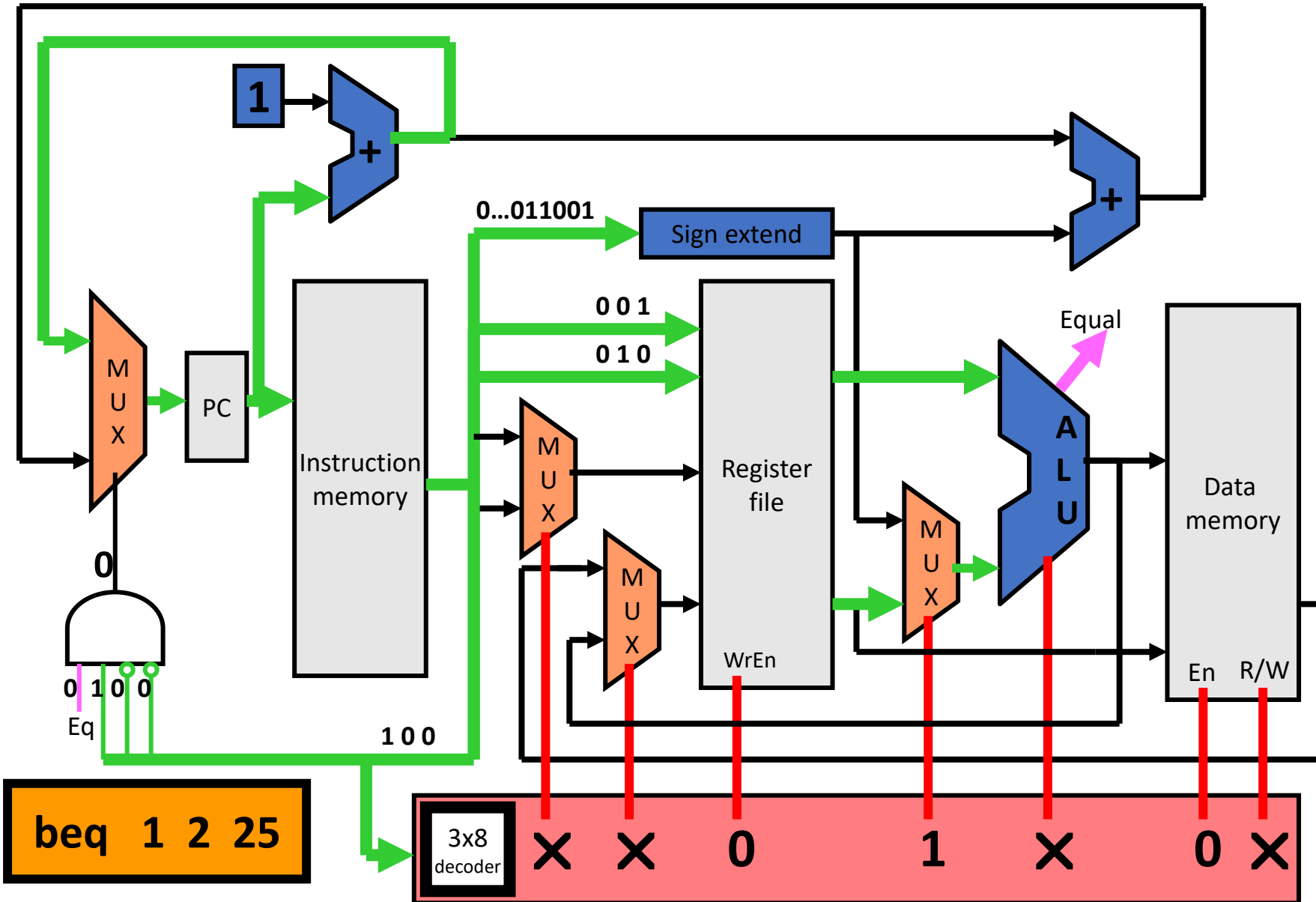
# Announcements

- P2
  - Three parts: part a is due **today**
- HW 2
  - Posted on website, due next **Mon**
- Midterm exam **Thu 6-8 pm**
  - Sample exams on website
  - You can bring 1 sheet (double sided is fine) of notes
  - We will provide LC2K encodings + ARM cheat sheet
  - Calculator that doesn't connect to internet is recommended
- Staff led review session on Sunday
  - Will be recorded, see Ed post
- Lecture on Tuesday will also be review

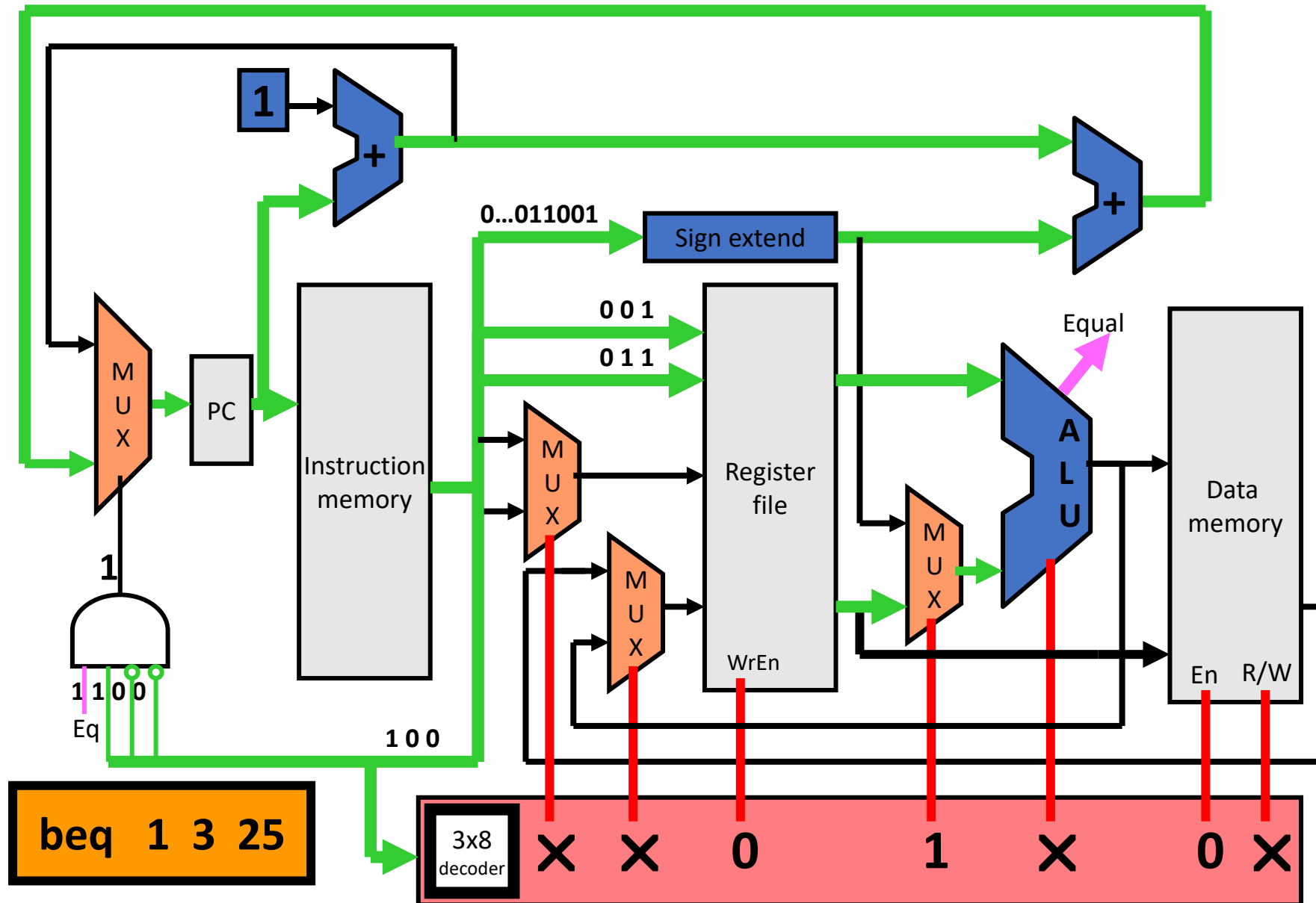
## Executing a **BEQ** Instruction



# Executing “not taken” BEQ Instruction on LC2K Datapath



# Executing a “taken” **BEQ** Instruction on LC2K Datapath



# So Far, So Good

- Every architecture seems to have at least one "ugly" instruction
  - Something that doesn't elegantly fit in with the hardware we've already included
- For LC2K, that ugly instruction is JALR
  - It doesn't fine into our nice clean datapath
- To implement JALR we need to:
  - Write PC+1 into regB
  - Move regA into PC
- Right now there is:
  - No path to write PC+1 into a register
  - No path to write a register to the PC
- Won't cover here (you don't need to know it explicitly)
  - Studio recordings go over it if you are curious



# What's Wrong with Single-Cycle?

- **All instructions run at the speed of the slowest instruction.**
- Adding a long instruction can hurt performance
  - What if you wanted to include multiply?
- You cannot reuse any parts of the processor
  - We have 3 different adders to calculate  $PC+1$ ,  $PC+1+offset$  and the ALU
- No benefit in making the common case fast
  - Since every instruction runs at the slowest instruction speed
    - This is particularly important for loads as we will see later

# Clock Period Example

- 1 ns – Register read/write time
- 2 ns – ALU/adder
- 2 ns – memory access
- 0 ns – MUX, PC access, sign extend, ROM

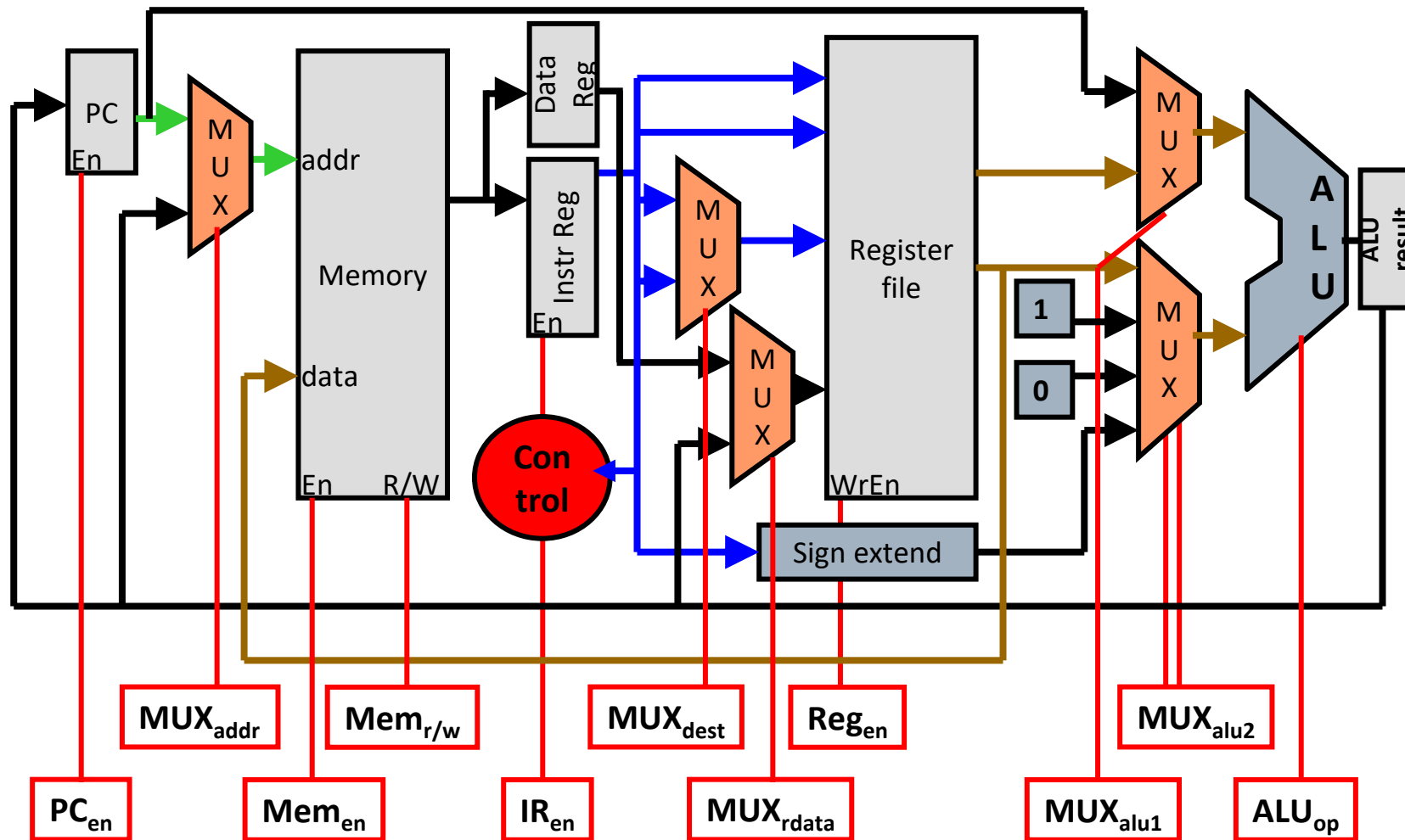
	Get Instr	read reg	ALU oper.	mem	write reg	
• add:	2ns	+ 1ns	+ 2ns		+ 1 ns	= 6 ns
• beq:	2ns	+ 1ns	+ 2ns			= 5 ns
• sw:	2ns	+ 1ns	+ 2ns	+ 2ns		= 7 ns
• lw:	2ns	+ 1ns	+ 2ns	+ 2ns	+ 1ns	= 8 ns



# Multiple-Cycle Execution

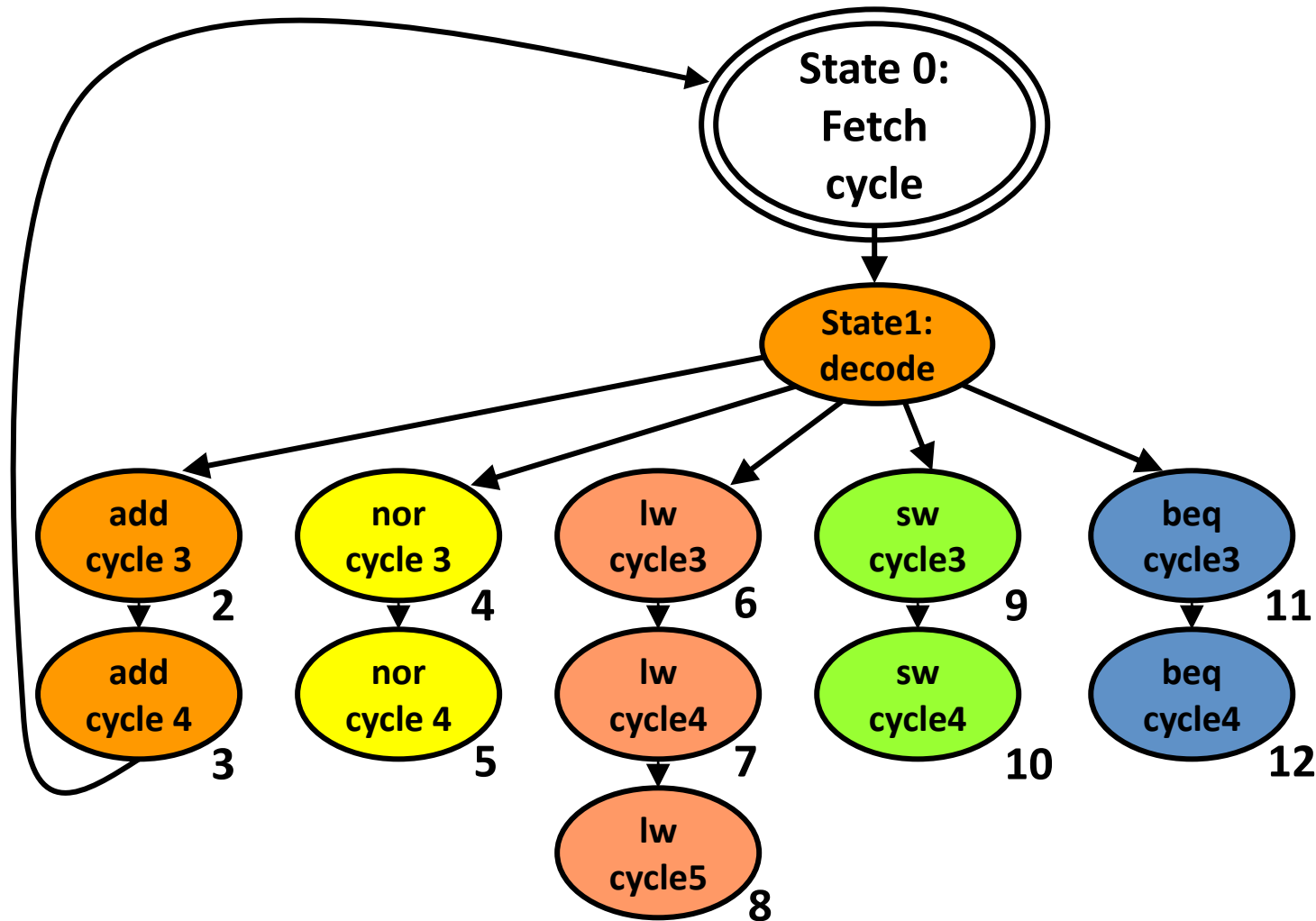
- Each instruction takes multiple cycles to execute
  - Cycle time is reduced
  - Slower instructions take more cycles
  - Faster instructions take fewer cycles
    - We can start next instruction earlier, rather than just waiting
  - Can reuse datapath elements each cycle
- What is needed to make this work?
  - Since you are re-using elements for different purposes, you need more and/or wider MUXes.
  - You may need extra registers if you need to remember an output for 1 or more cycles.
  - Control is more complicated since you need to send new signals on each cycle.

# Multi-cycle LC2 Datapath



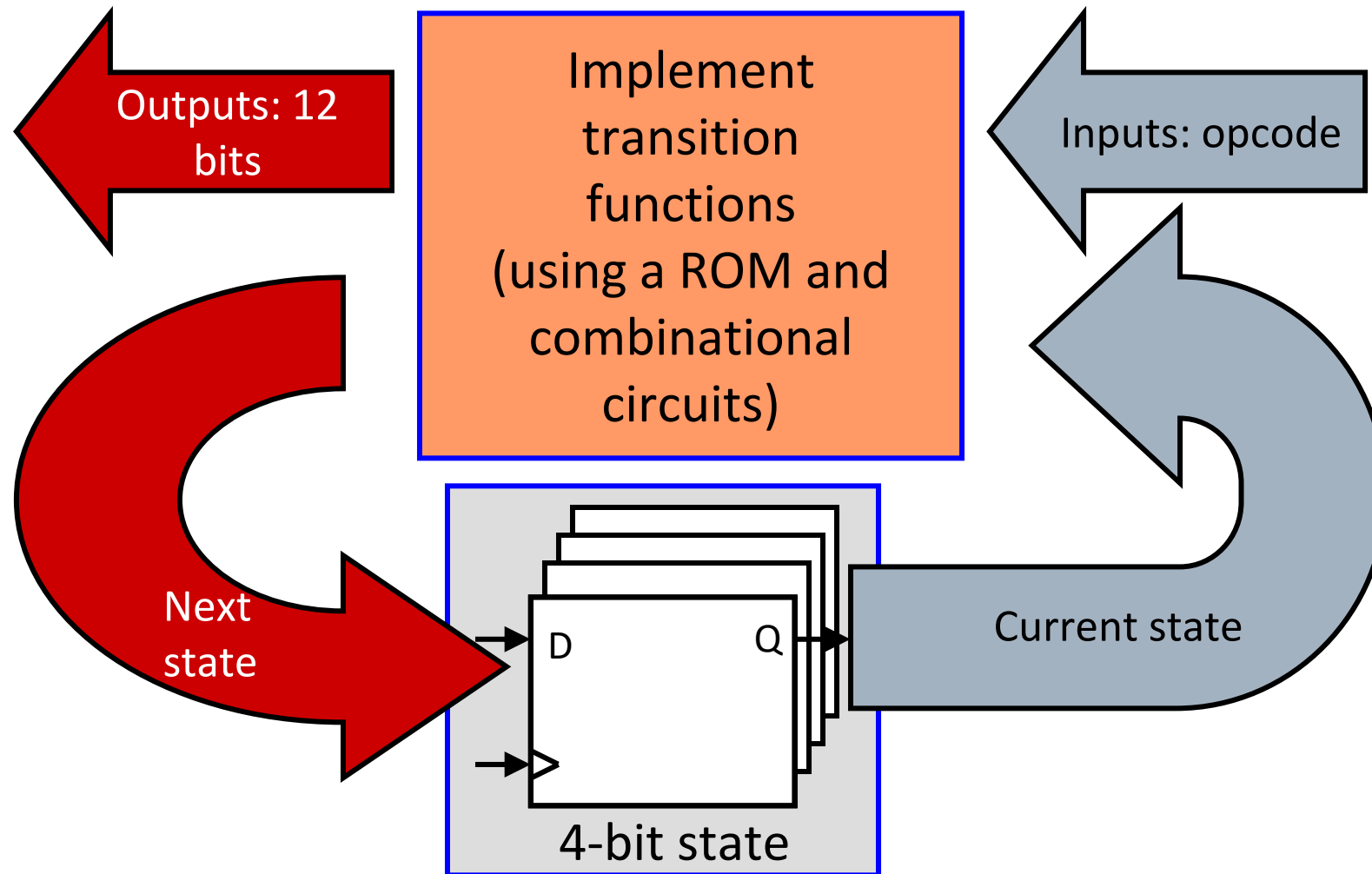
Each red signal comes from "Control"  
(implemented via ROM as before)

# State machine for multi-cycle control signals (transition functions)

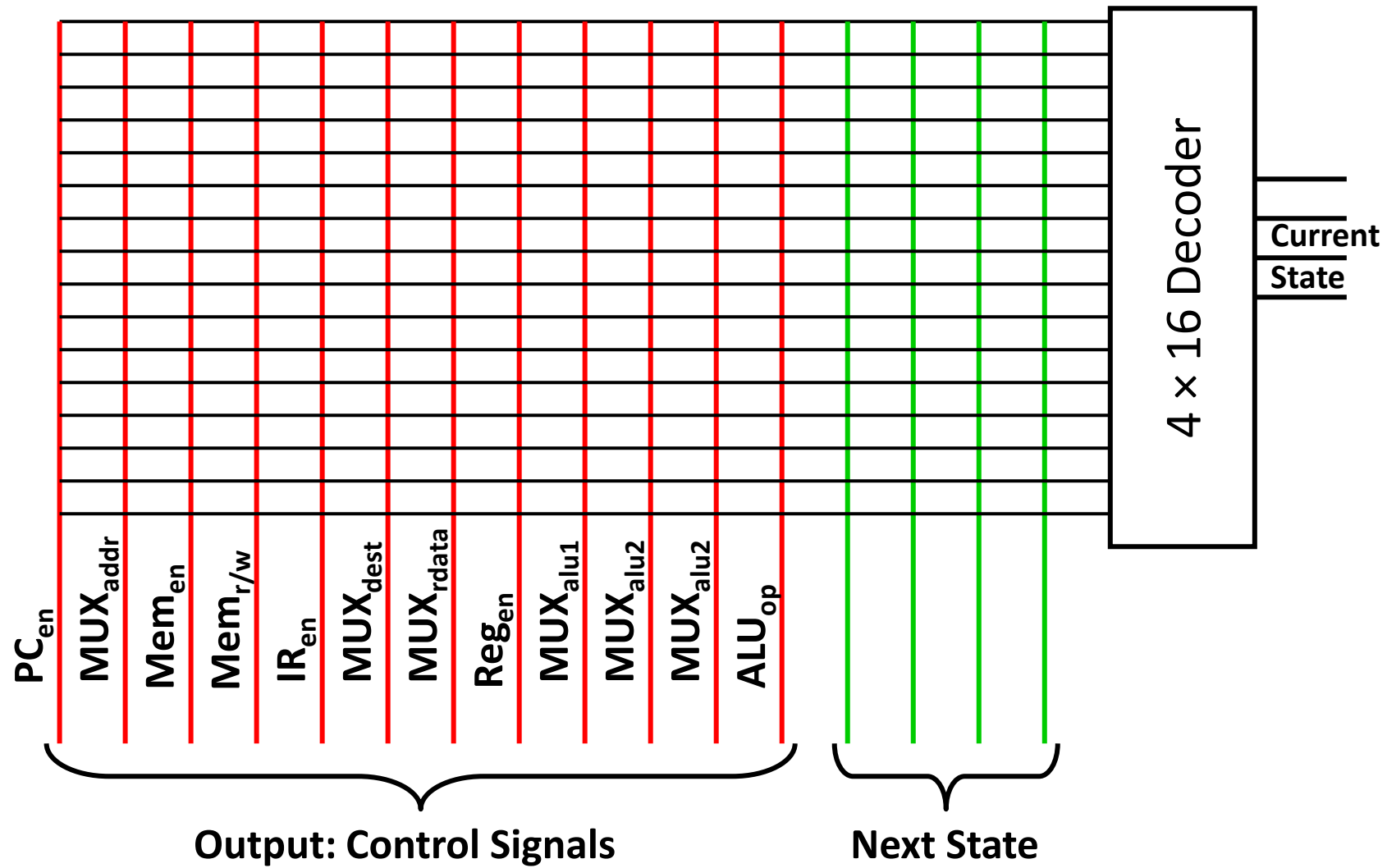


Note: we aren't worrying about JALR instruction in hardware going forward

# Implementing FSM



# Building the Control ROM

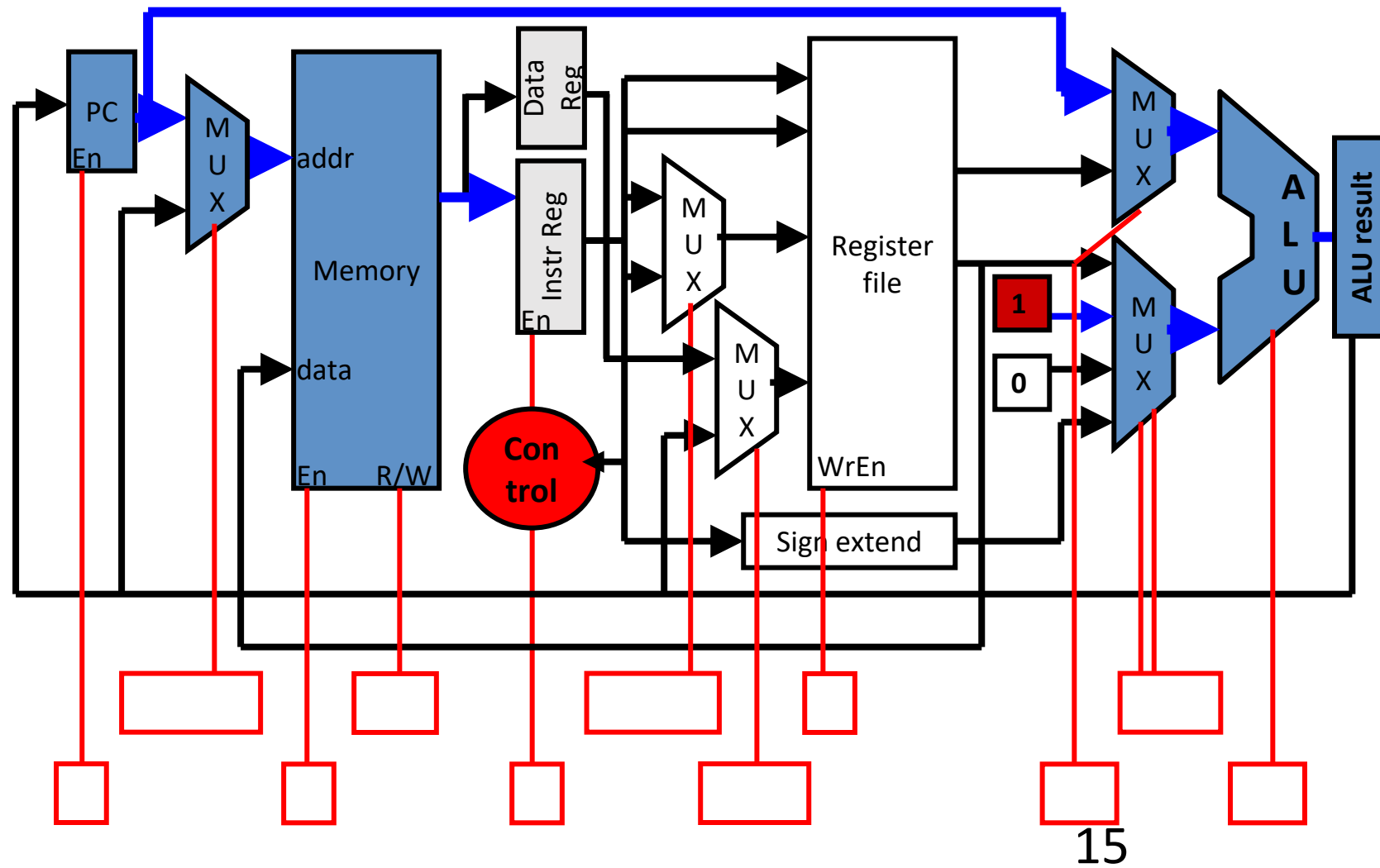


# First Cycle (State 0) Fetch Instr

- What operations need to be done in the first cycle of executing any instruction?
  - Read memory[PC] and store into instruction register.
    - Must select PC in memory address MUX ( $MUX_{addr} = 0$ )
    - Enable memory operation ( $Mem_{en} = 1$ )
    - R/W should be (read) ( $Mem_{r/w} = 0$ )
    - Enable Instruction Register write ( $IR_{en} = 1$ )
  - Calculate PC + 1
    - Send PC to ALU ( $MUX_{alu1} = 0$ )
    - Send 1 to ALU ( $MUX_{alu2} = 01$ )
    - Select ALU add operation ( $ALU_{op} = 0$ )
  - $PC_{en} = 0$ ;  $Reg_{en} = 0$ ;  $MUX_{dest}$  and  $MUX_{rdata} = X$
- Next State: Decode Instruction

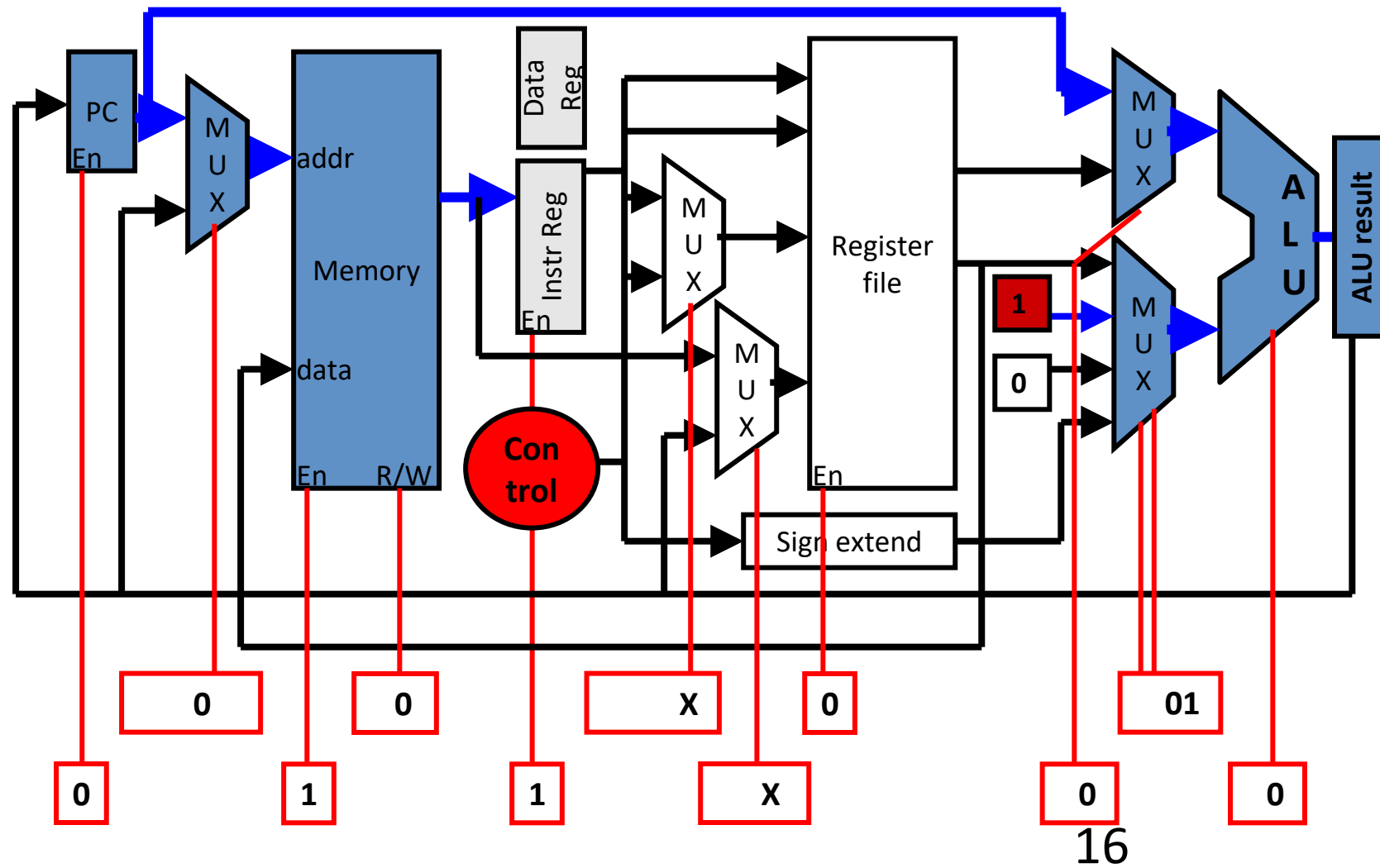
# First Cycle (State 0) Fetch Instr

This is the same for all instructions  
(since we don't know the instruction yet!)



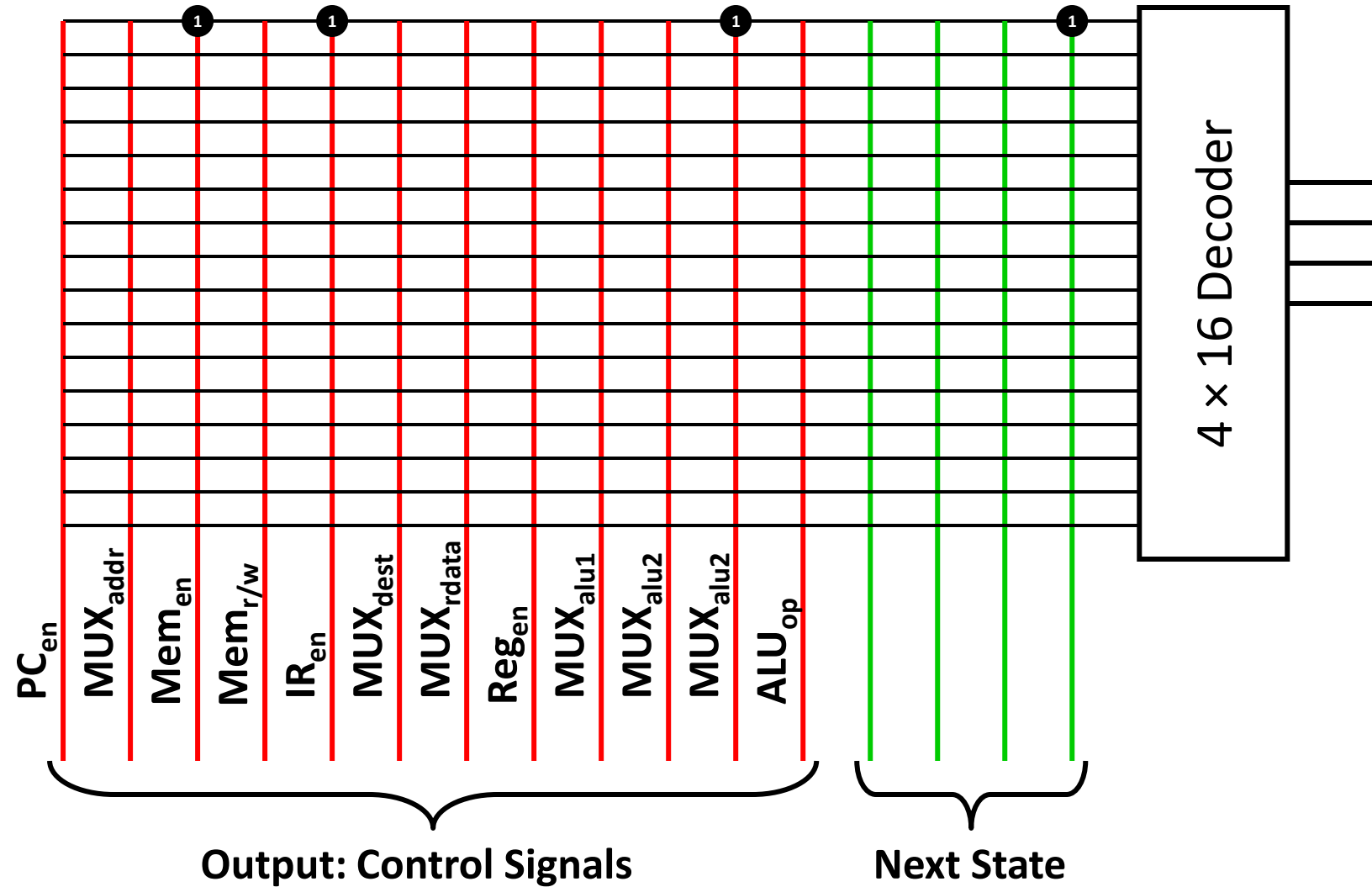
# First Cycle (State 0) Fetch Instr

This is the same for all instructions  
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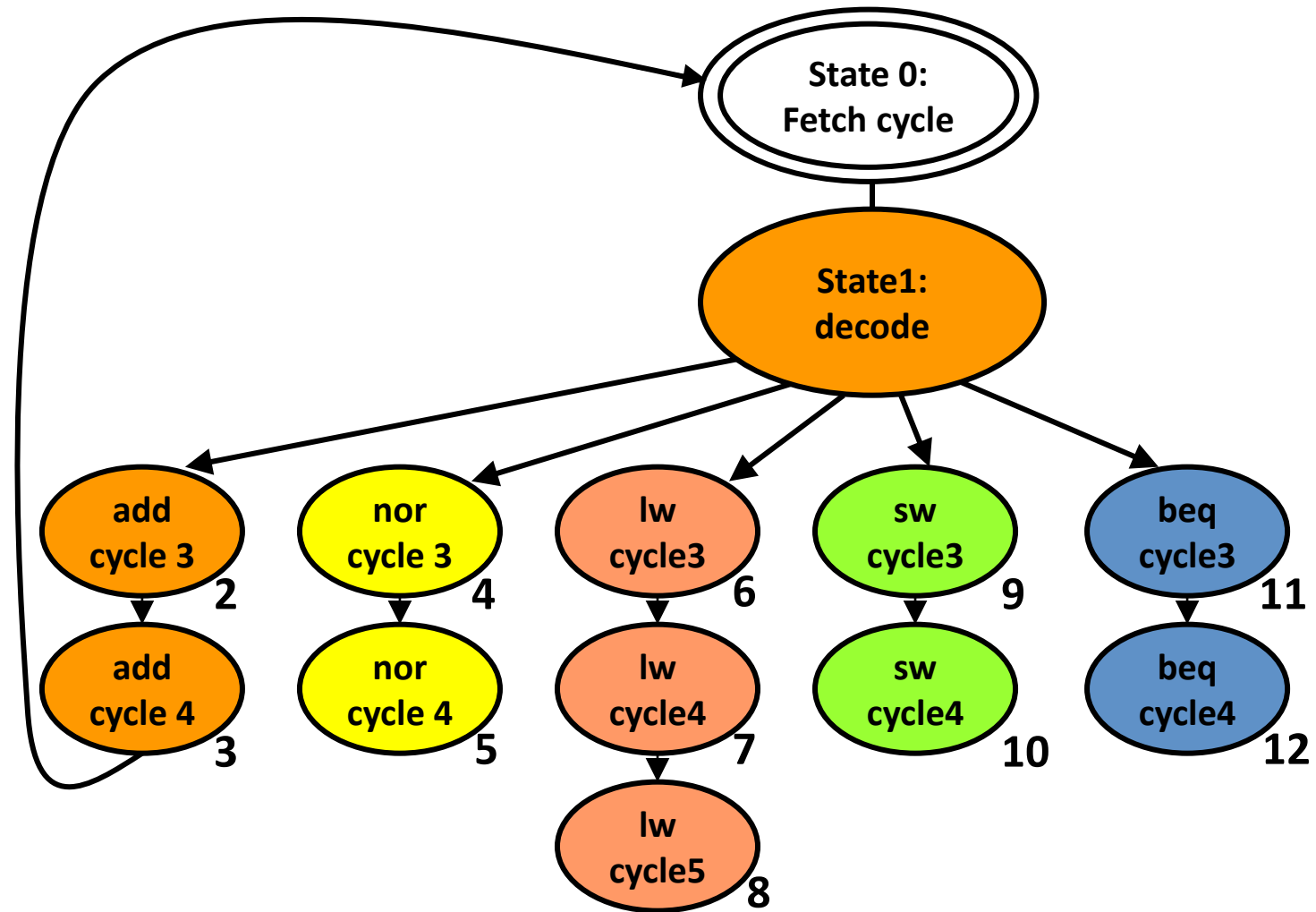




# Building the Control ROM



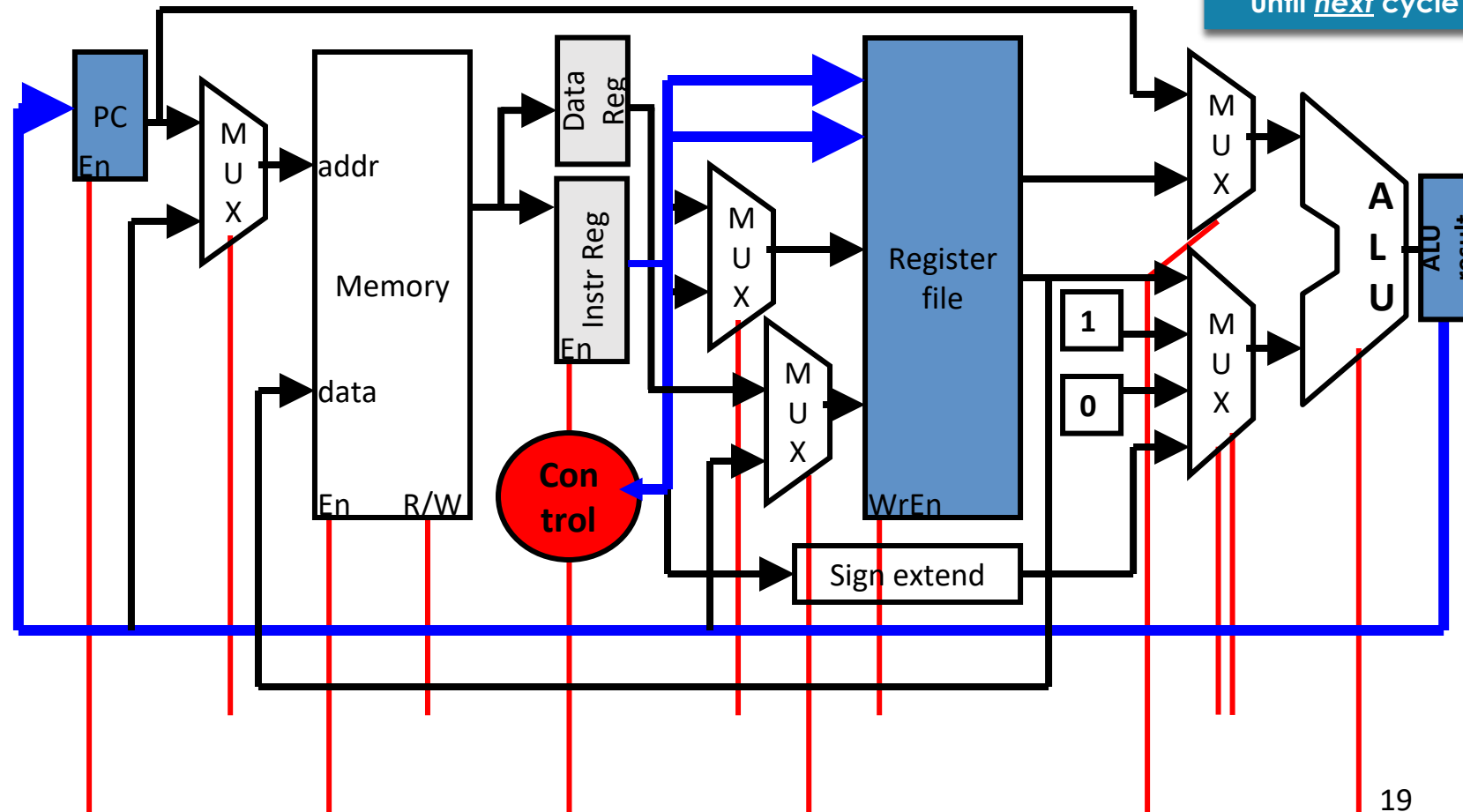
## State 1: instruction decode



# State 1: output function

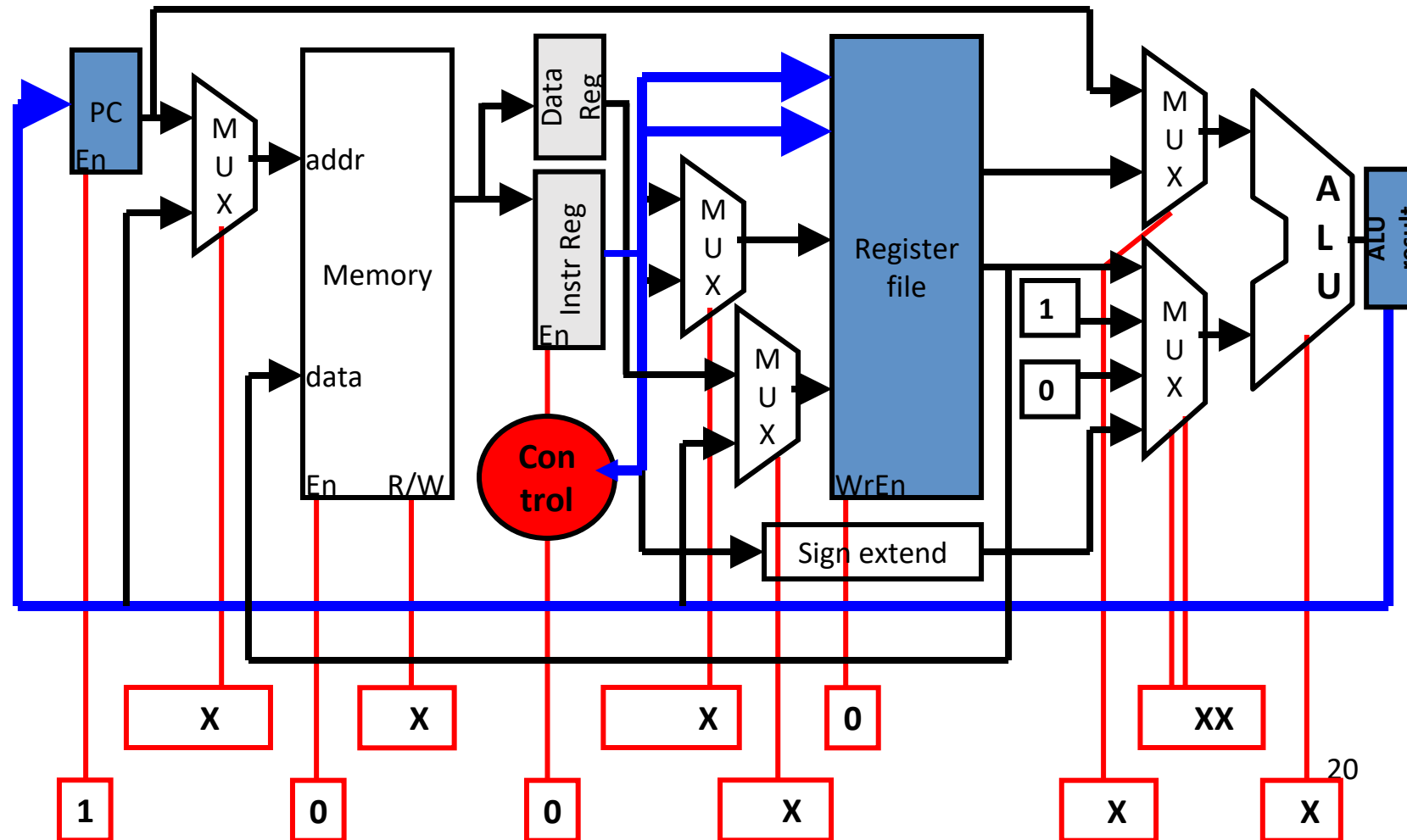
Update PC; read registers (regA and regB);  
use opcode to determine next state

Note: since RF read  
latency is same as  
clock period, RF  
data isn't available  
until next cycle



# State 1: output function

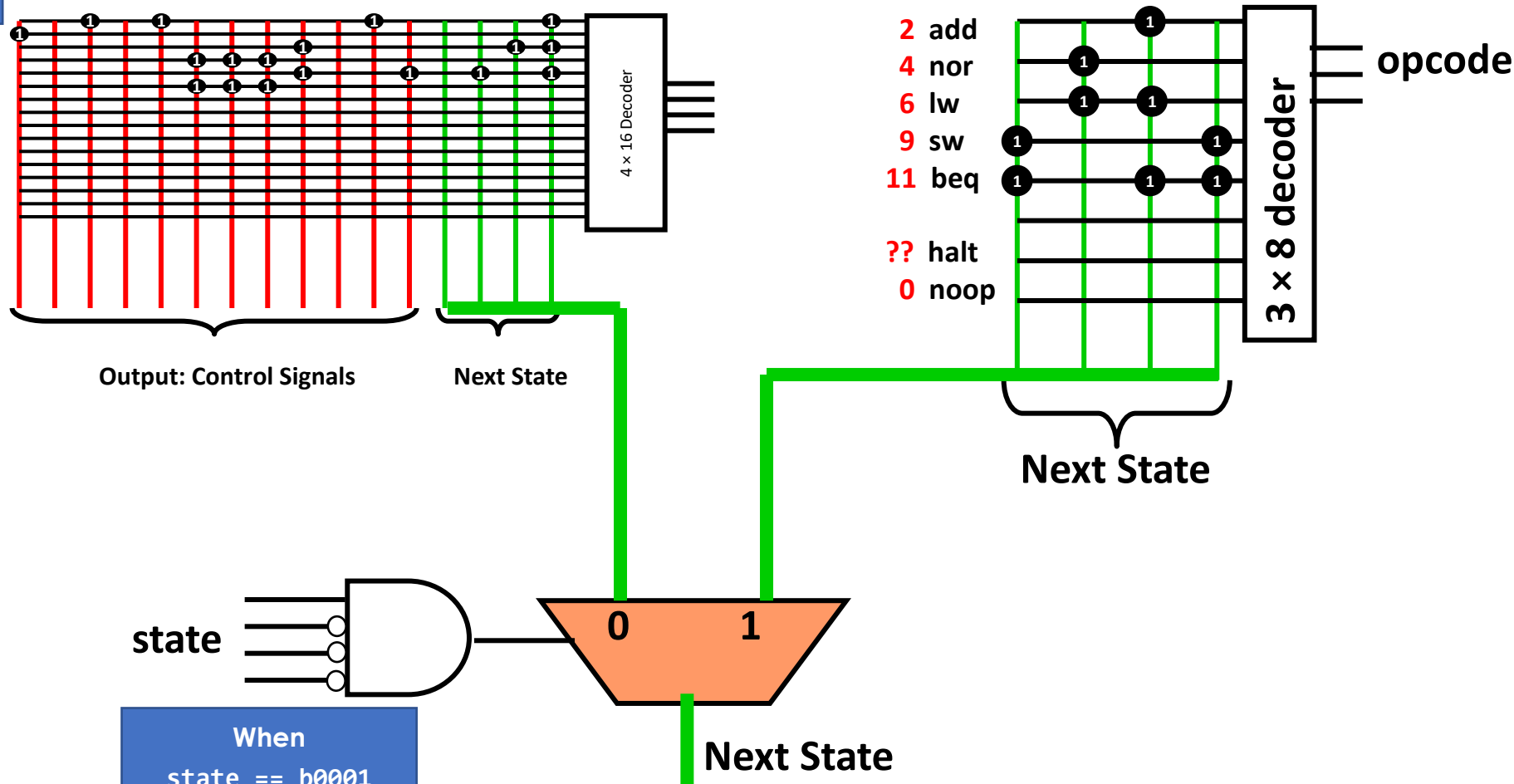
Update PC; read registers (regA and regB);  
use opcode to determine next state



# Transitioning from Decode State

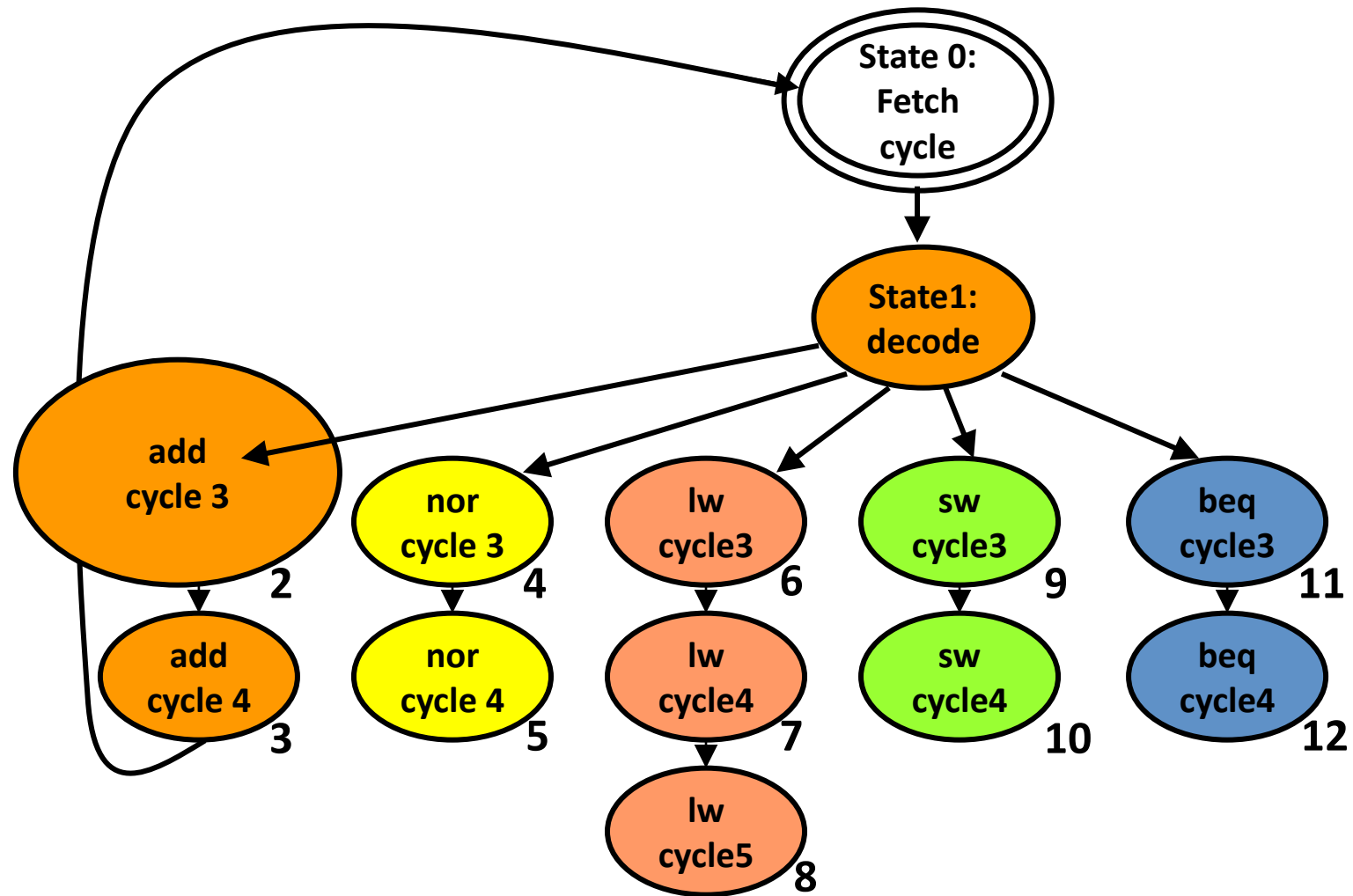
Which state we go to depends on opcode, can't just look at current state like before

Secondary ROM stores which state we should branch to after decode for each opcode



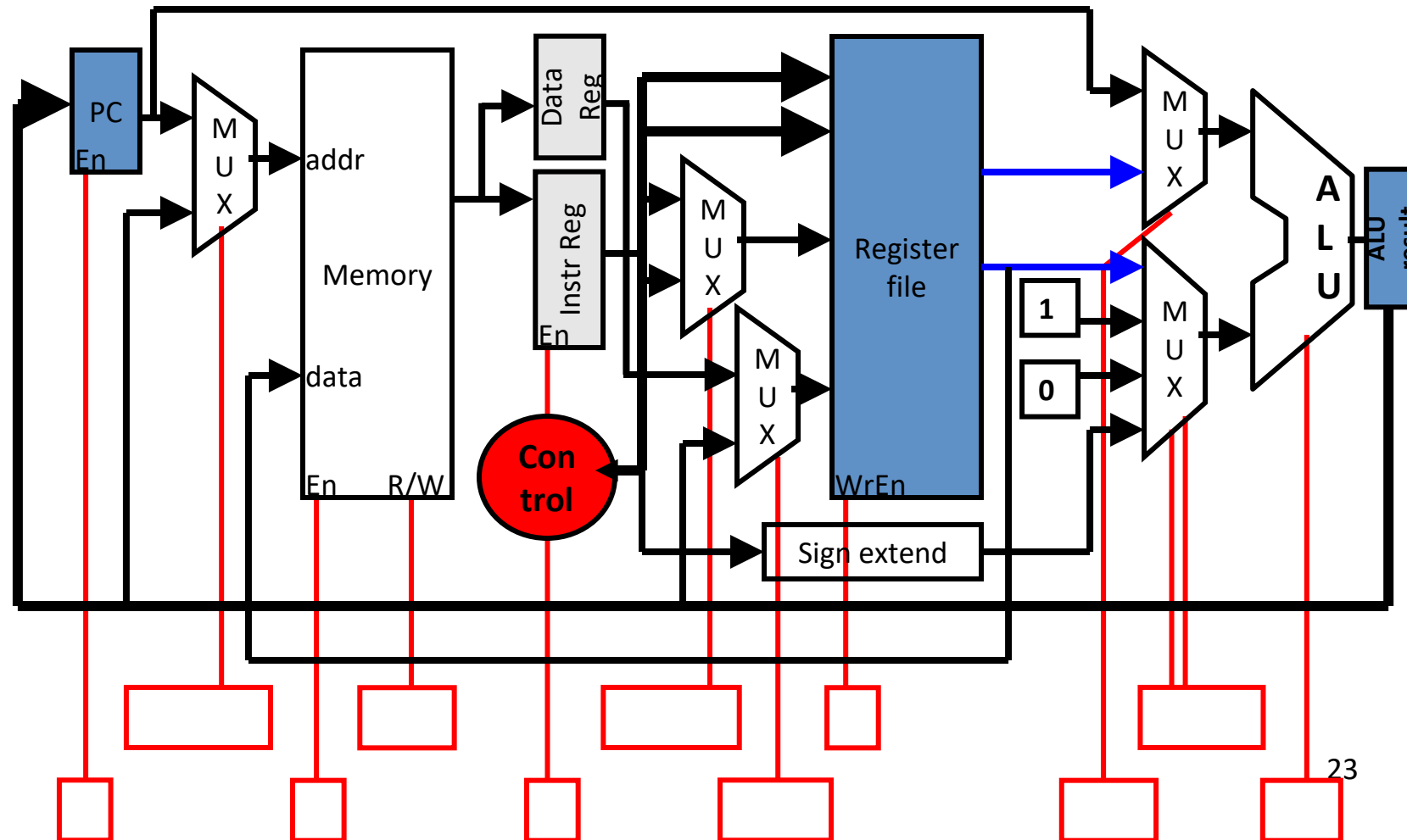
When  
state == b0001  
choose secondary  
ROM for next state  
logic

## State 2: Add cycle 3



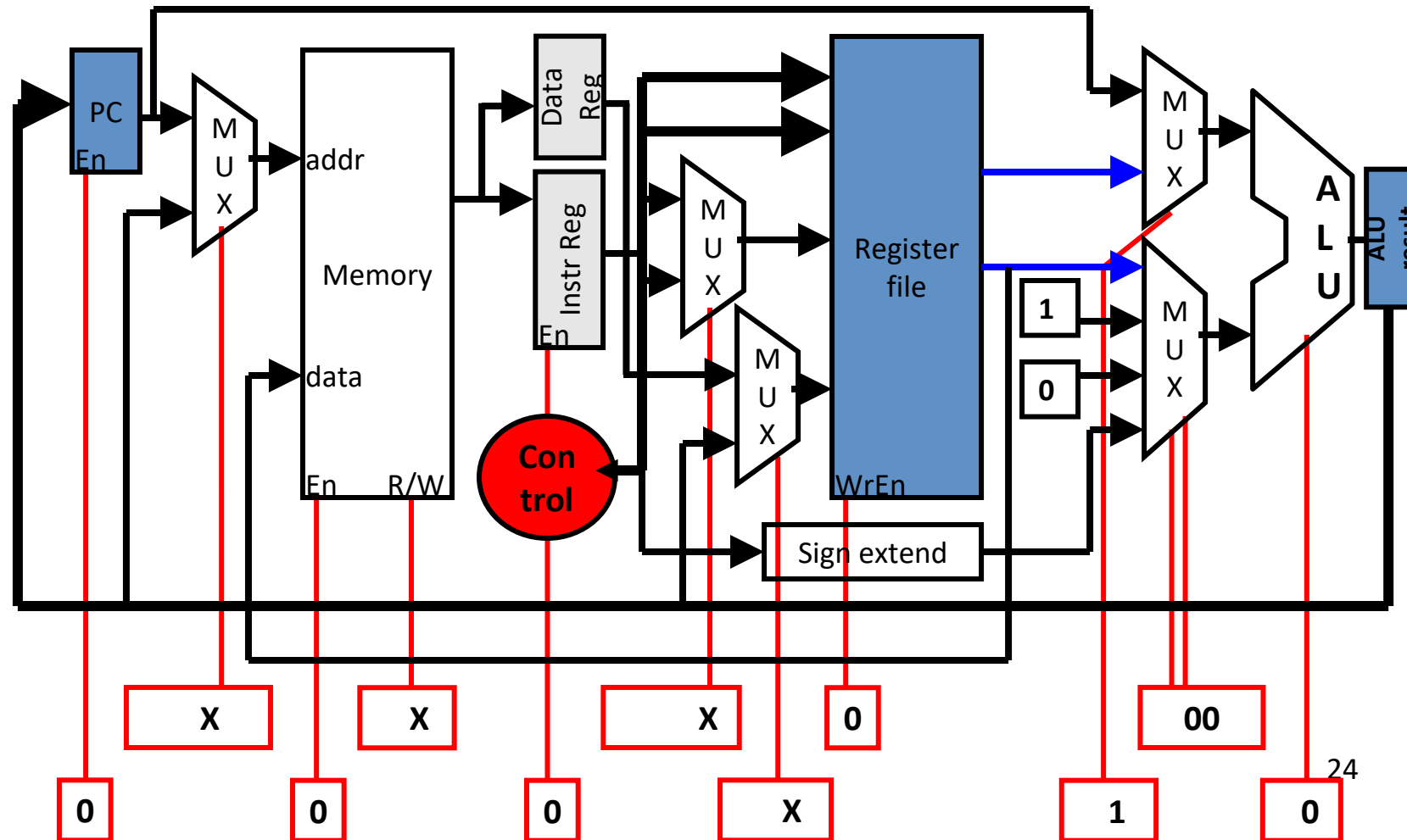
## State 2: **Add** Cycle 3 Operation

Send control signals to MUX to select values of regA and regB and control signal to ALU to add



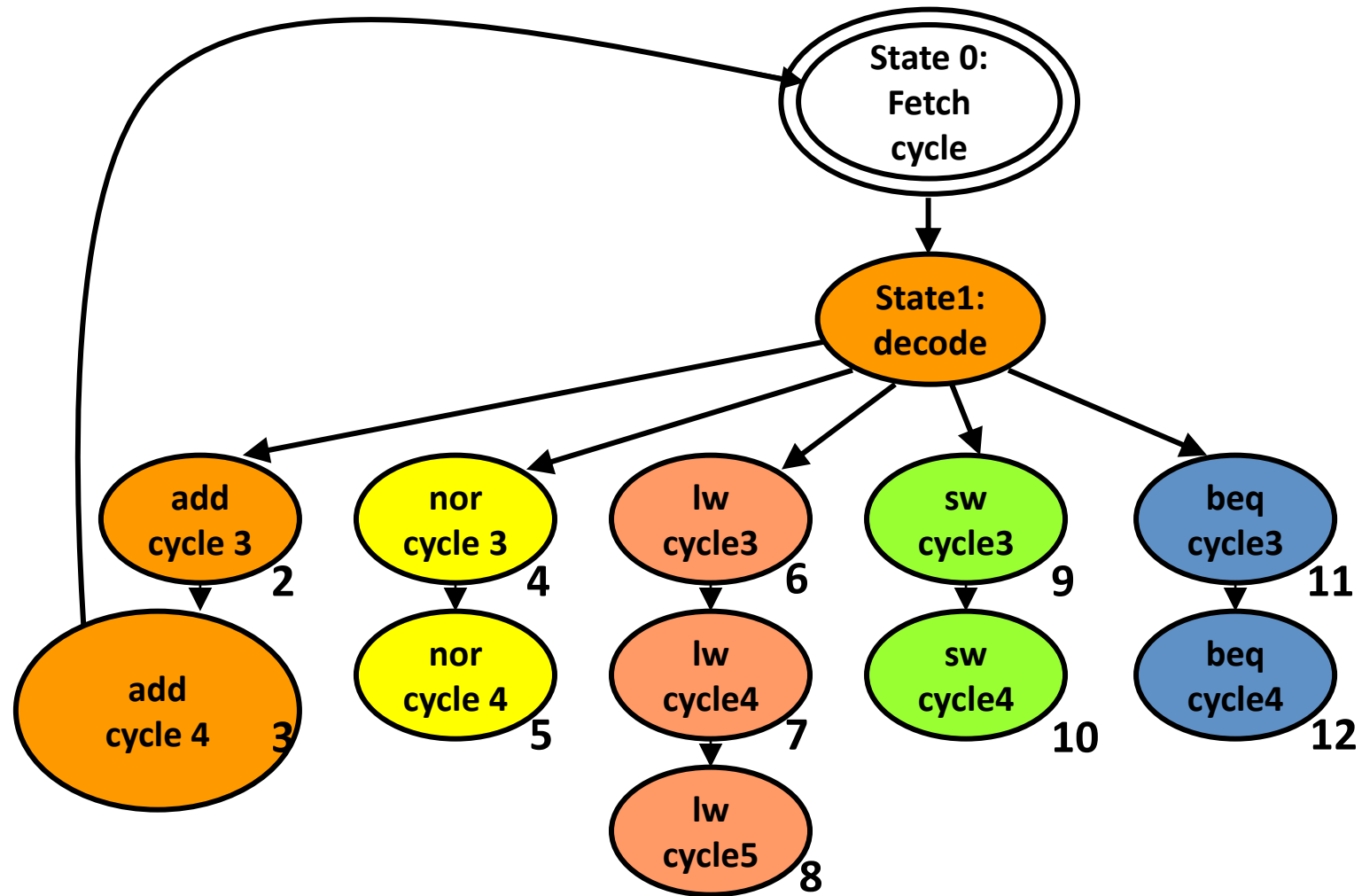
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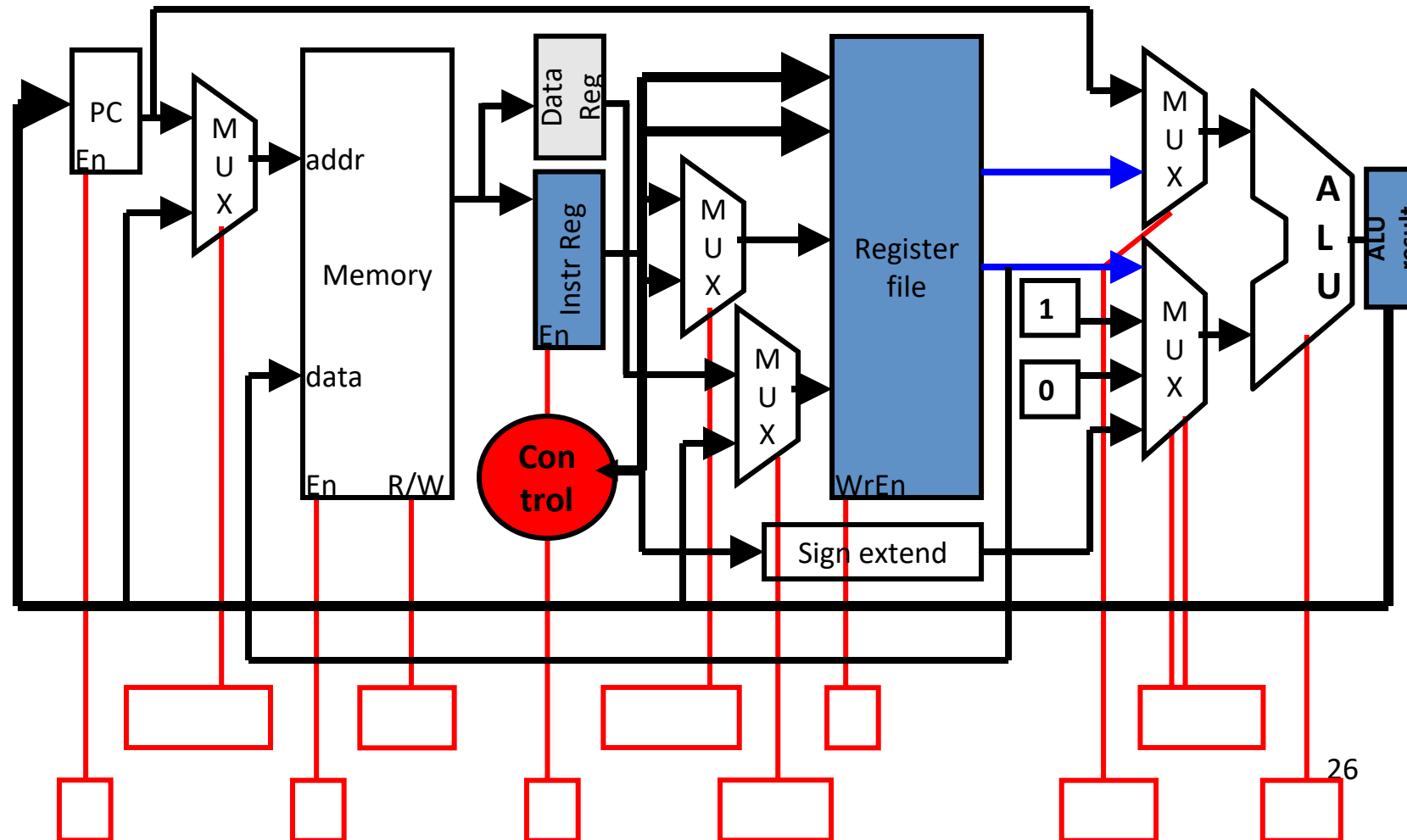


## State 3: Add cycle 4



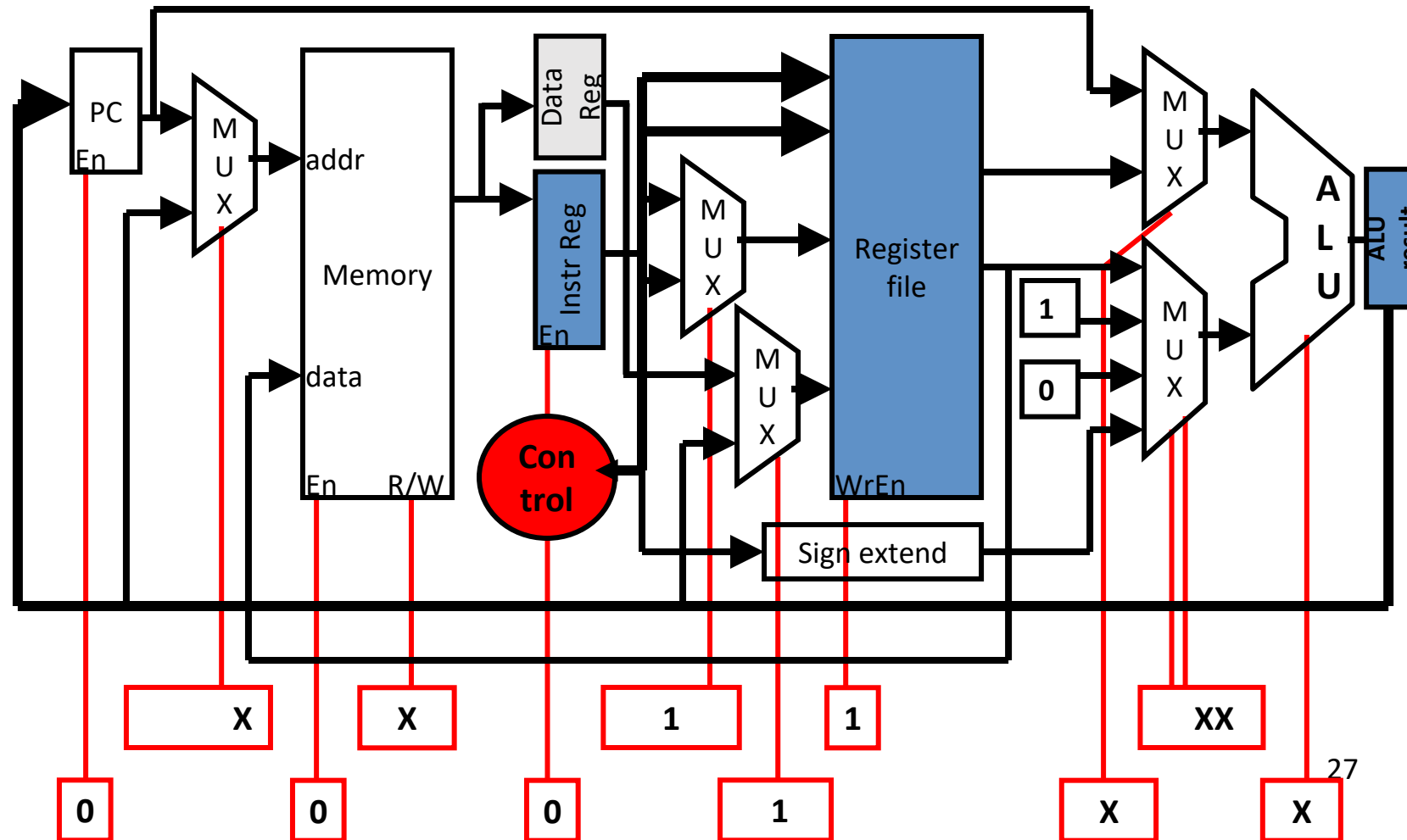
# Add Cycle 4 (State 3) Operation

Send control signal to address MUX to select dest and to data MUX to select ALU output, then send write enable to register file.

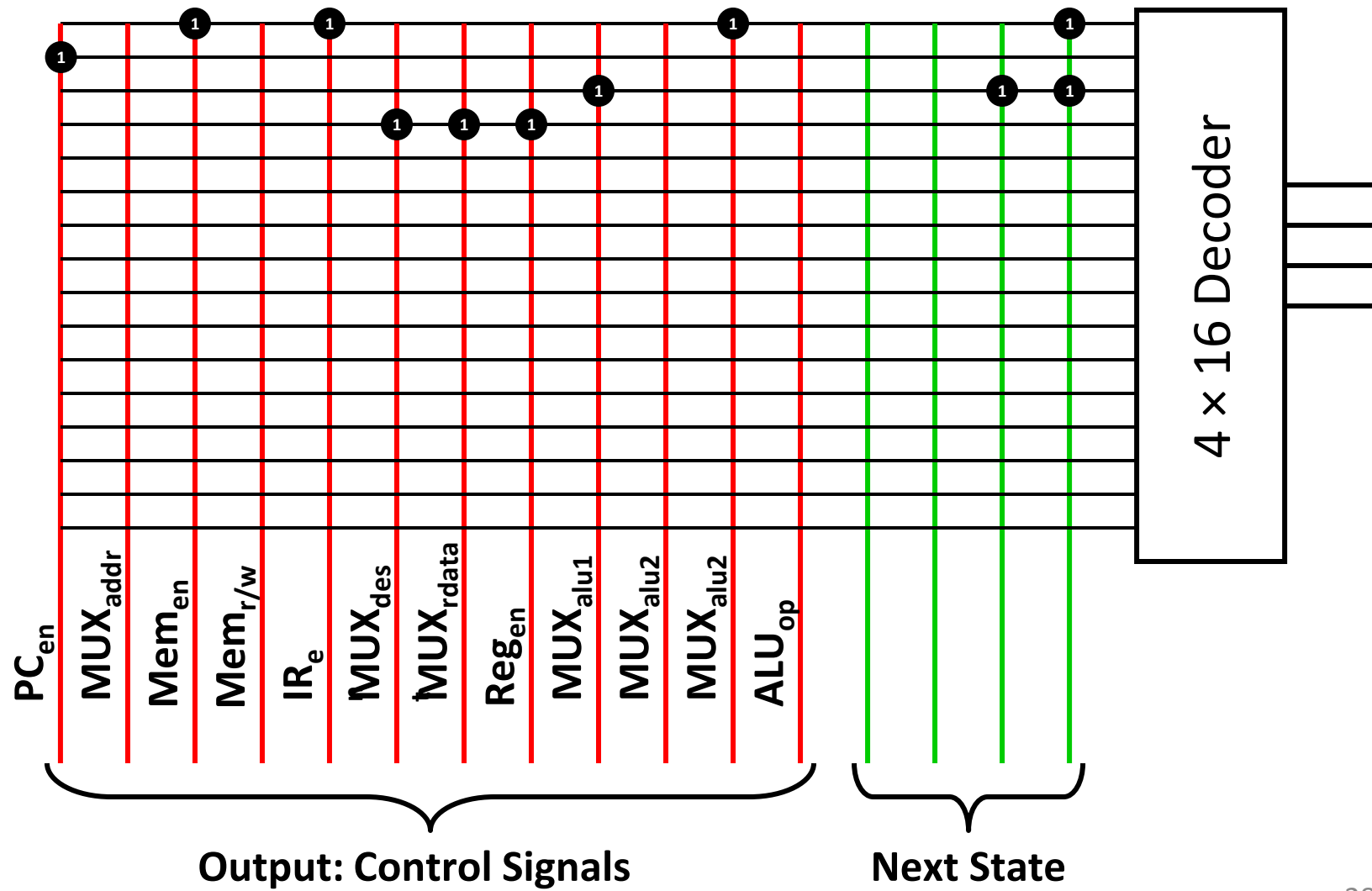


# Add Cycle 4 (State 3) Operation

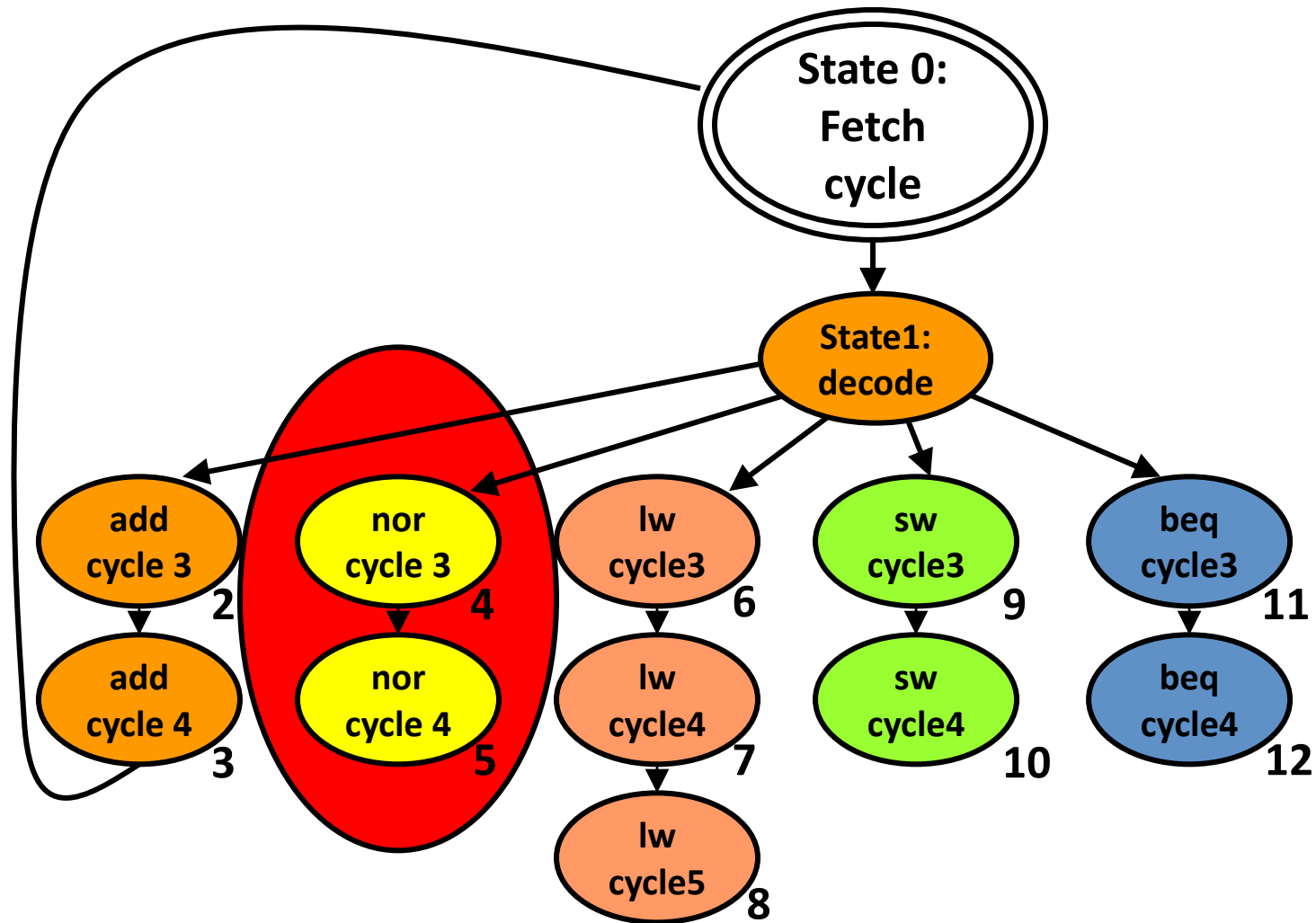
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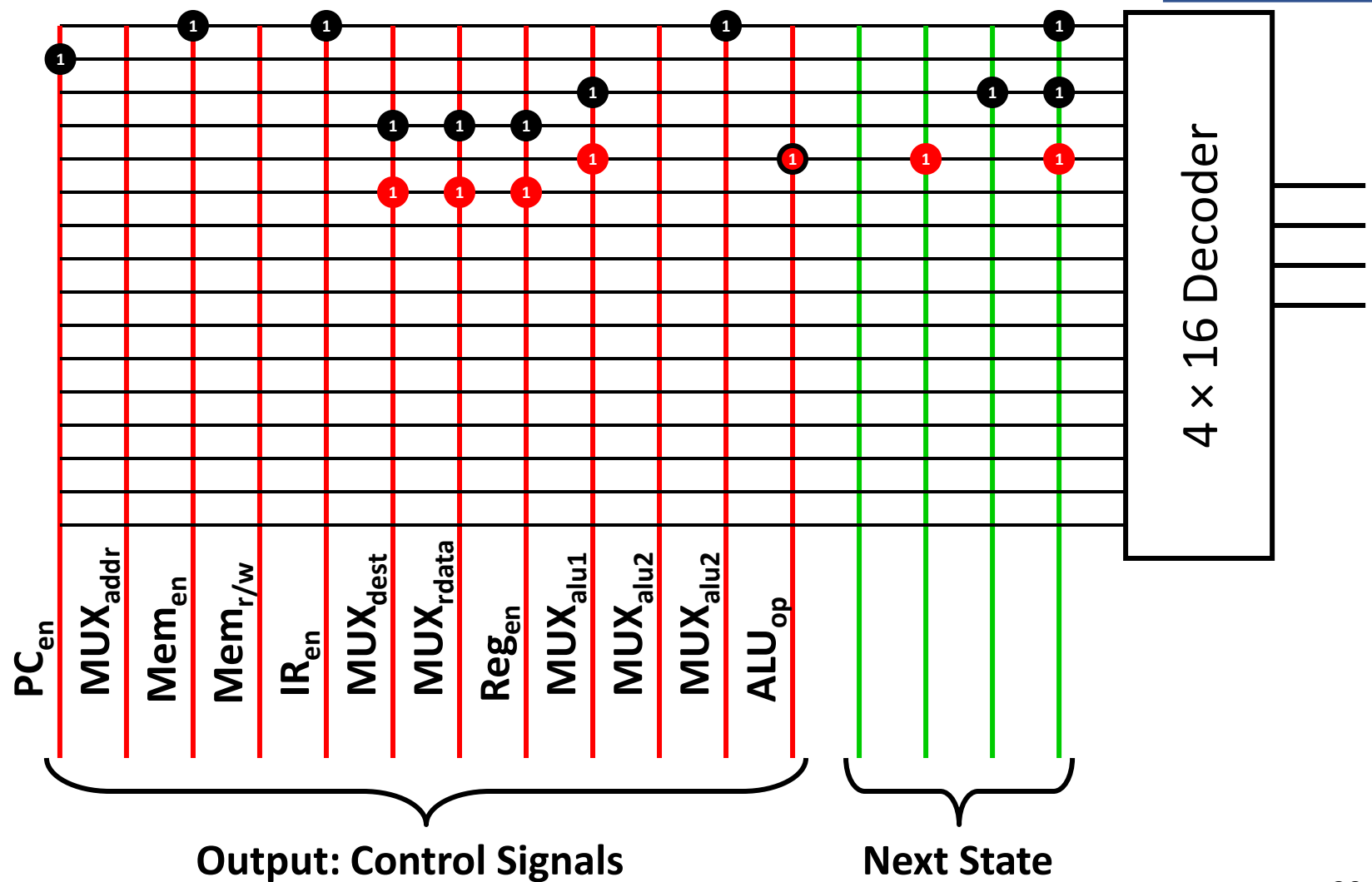
# Building the Control Rom



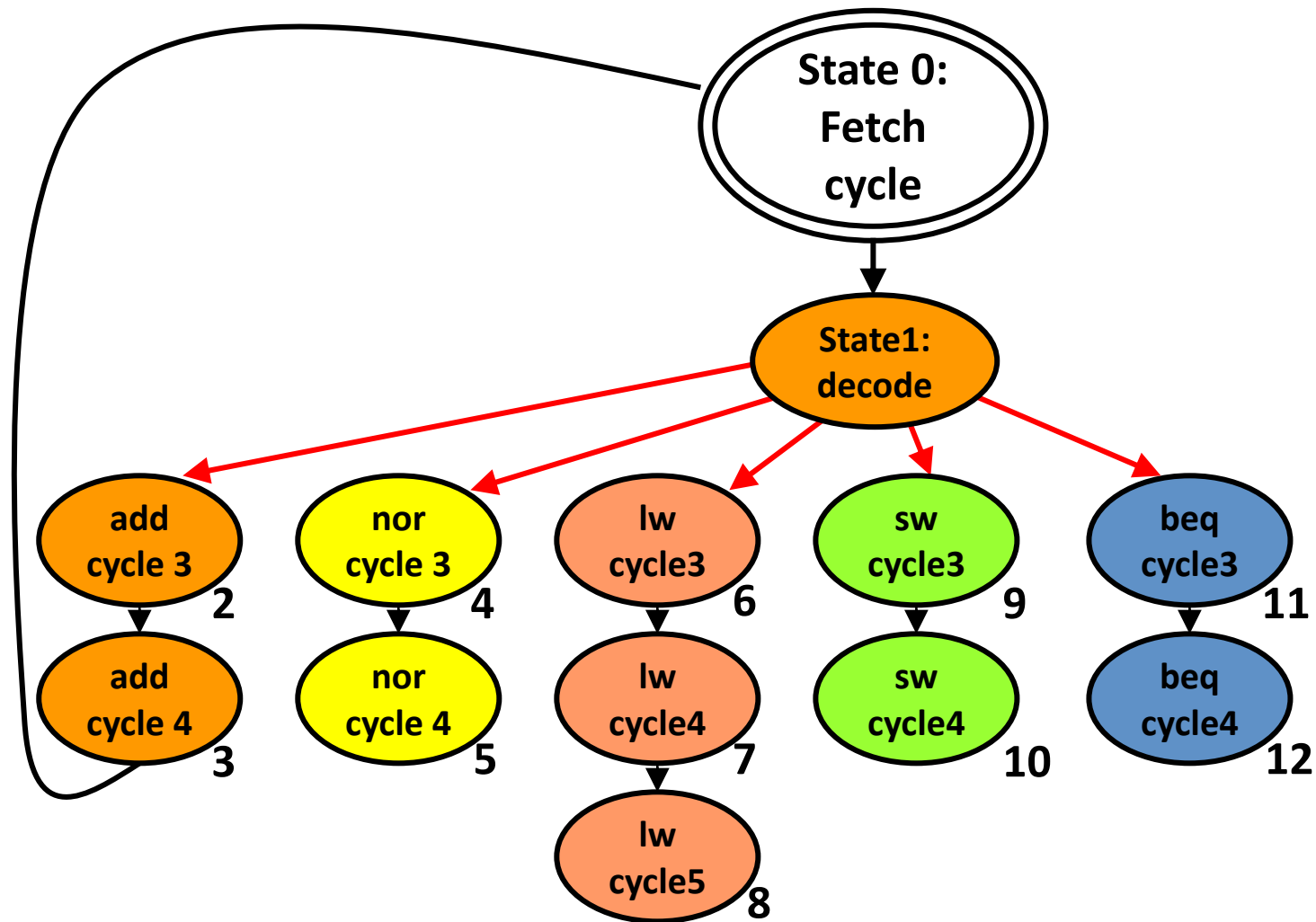
# Return to State 0: Fetch cycle to execute the next instruction



# Control Rom for nor (4 and 5)

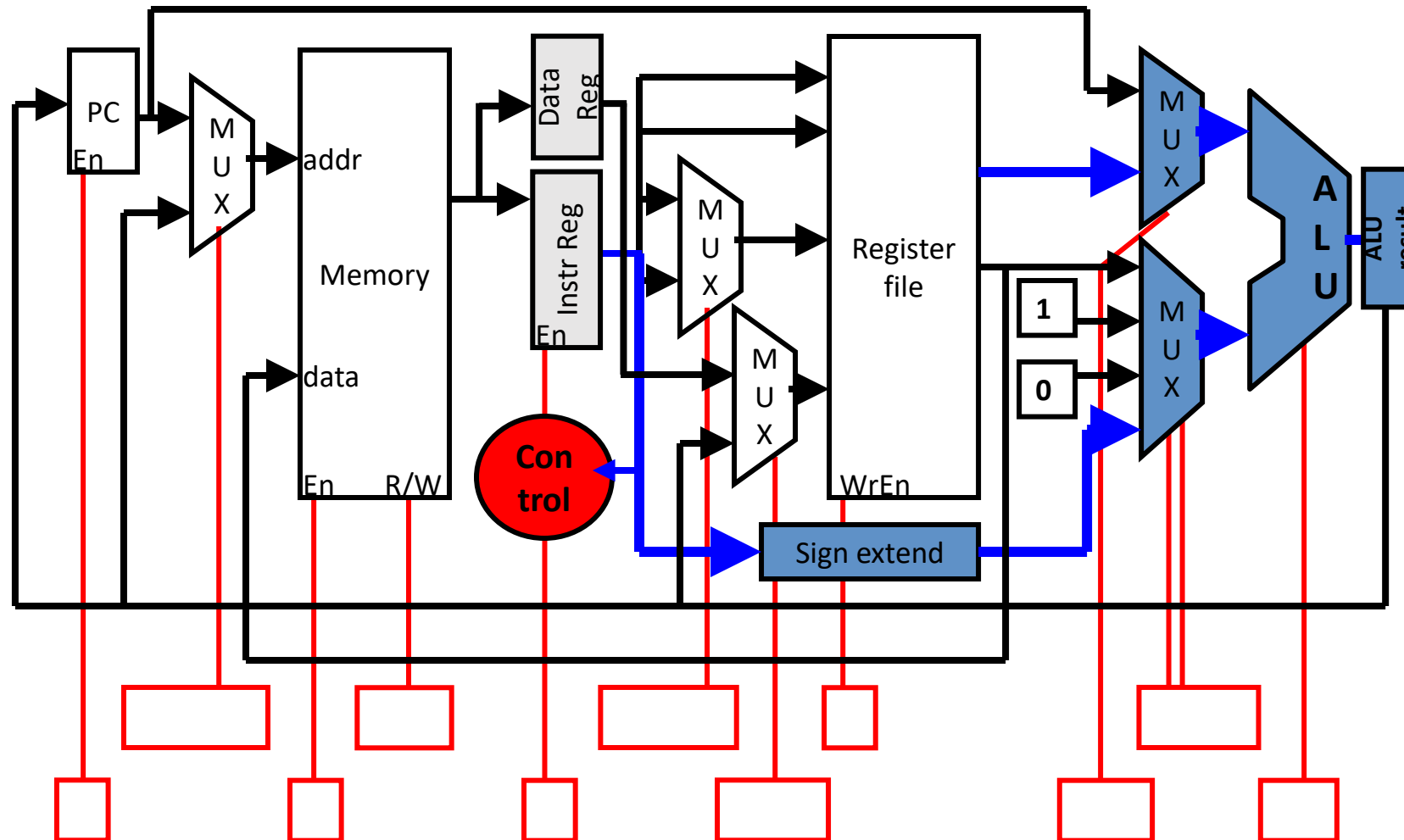


# Return to State 0: Fetch cycle to execute the next instruction



# State 6: LW cycle 3

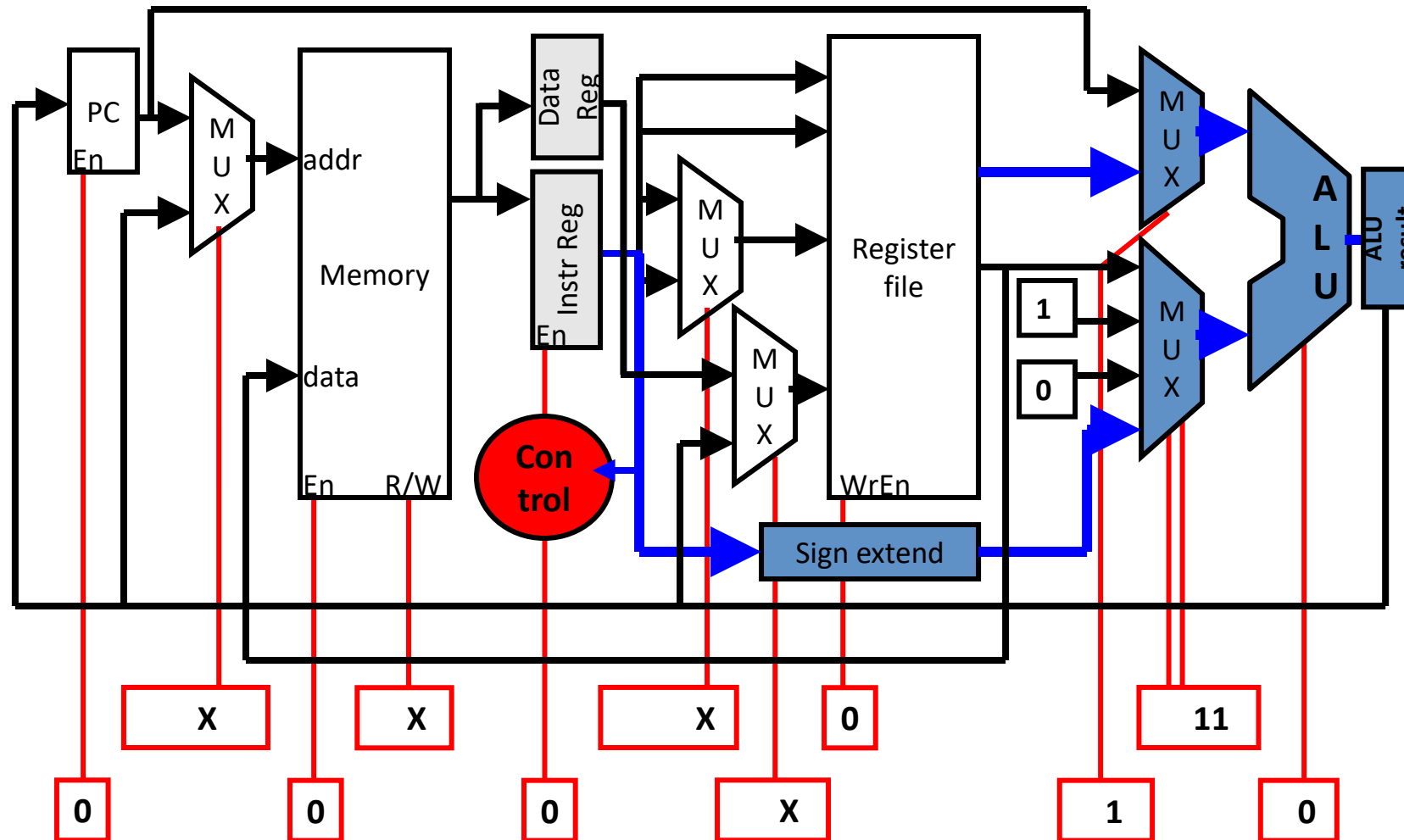
Calculate address for memory reference



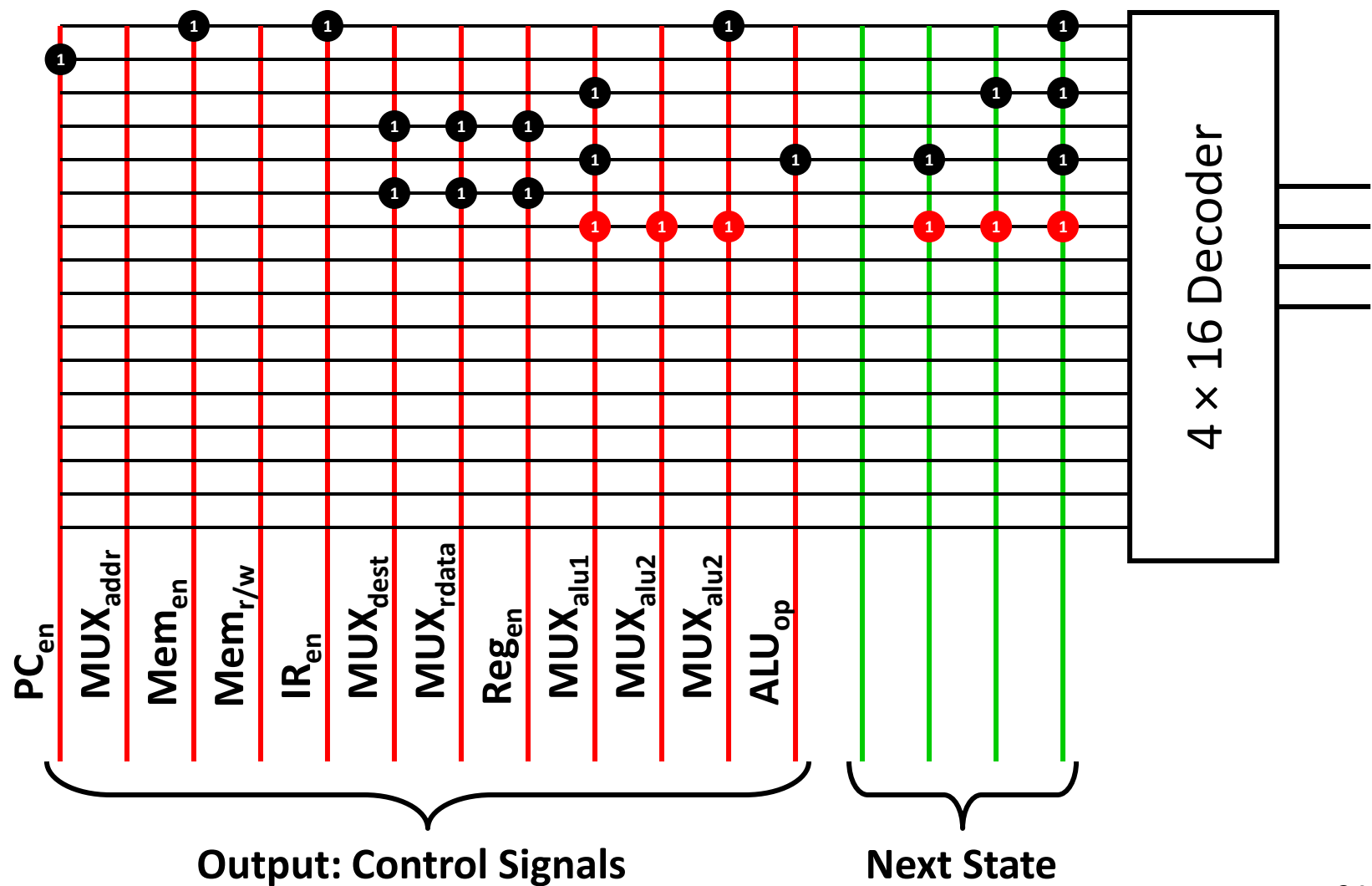


# State 6: LW cycle 3

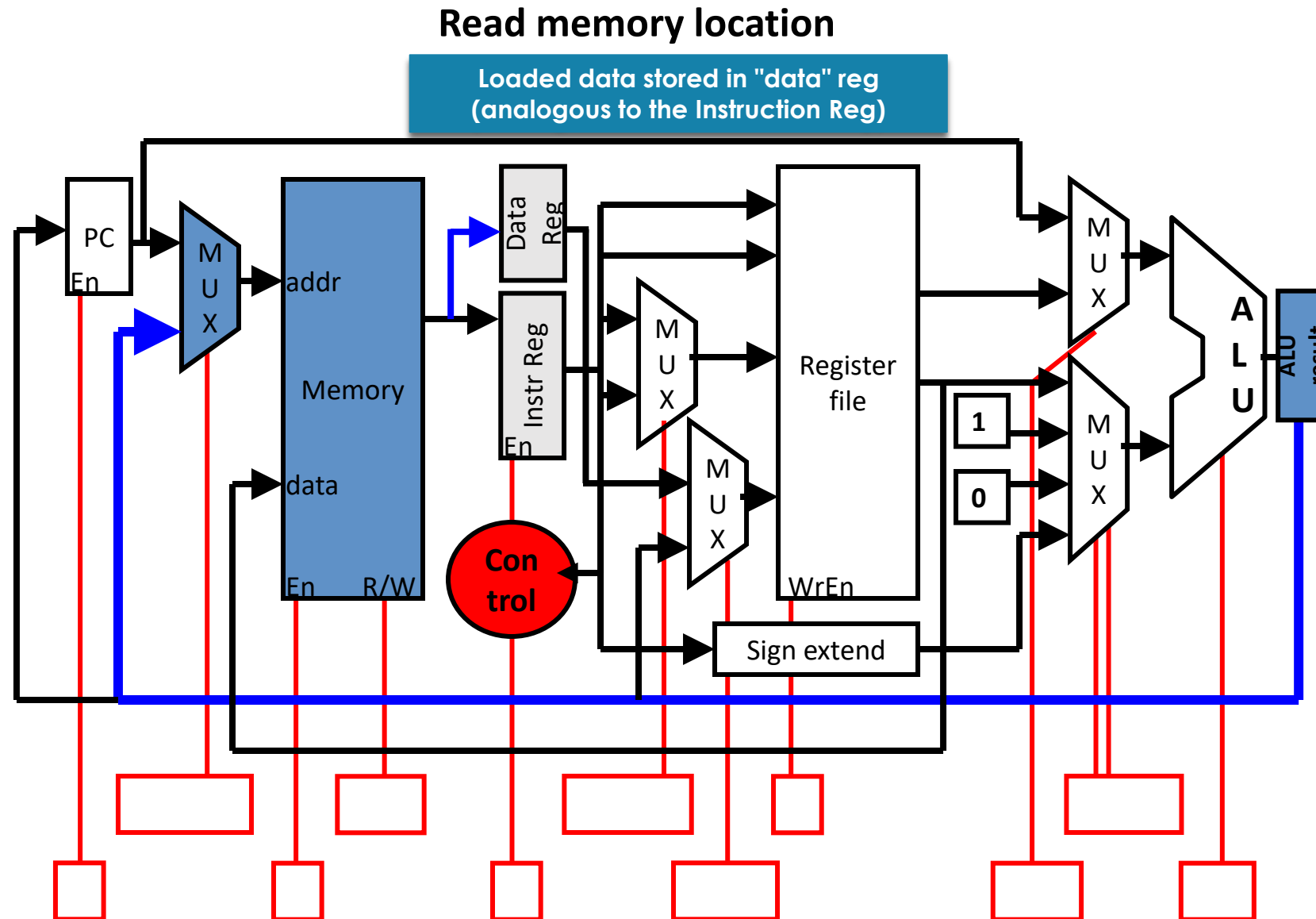
Calculate address for memory reference



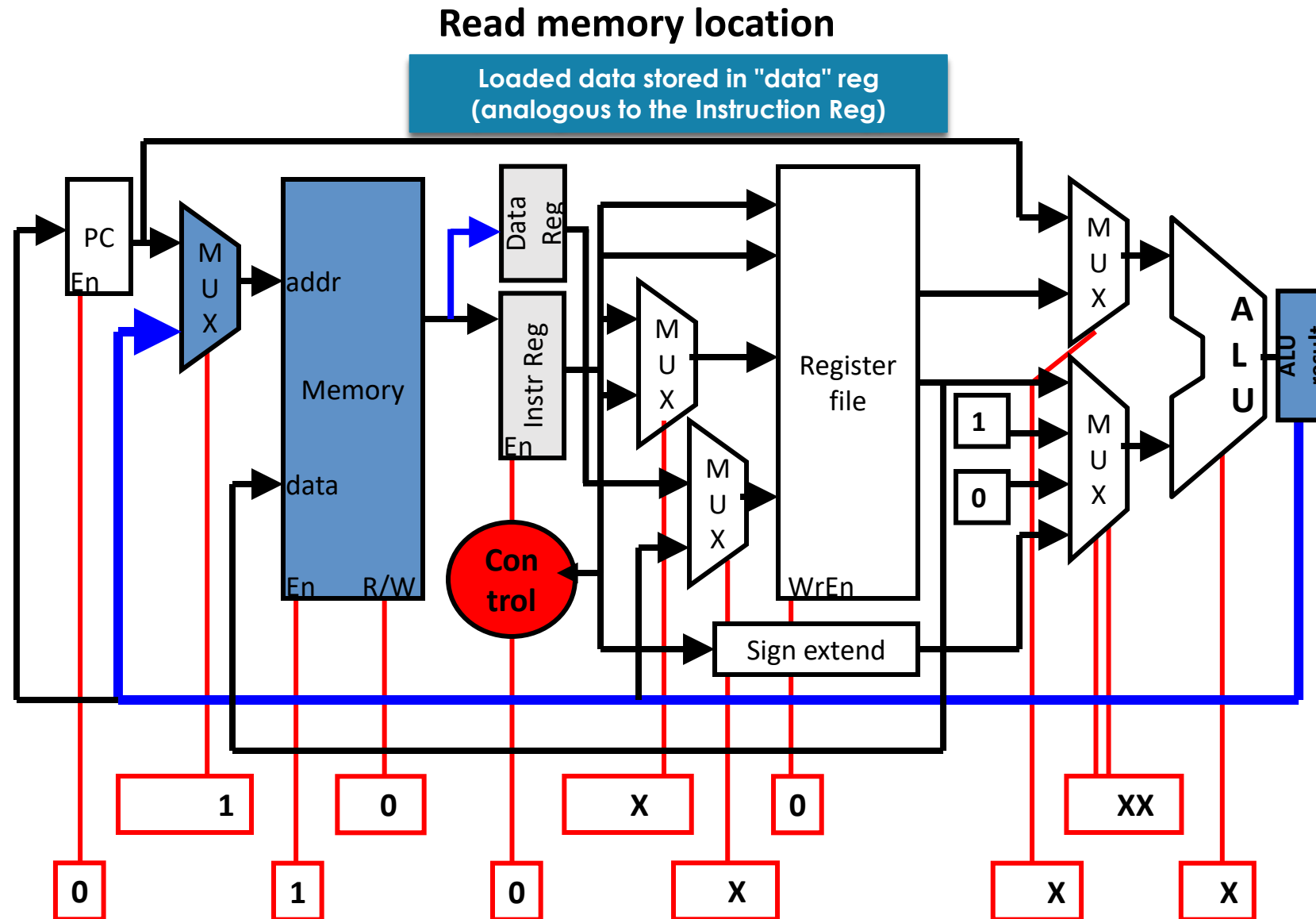
Control Rom (lw cycle 3)



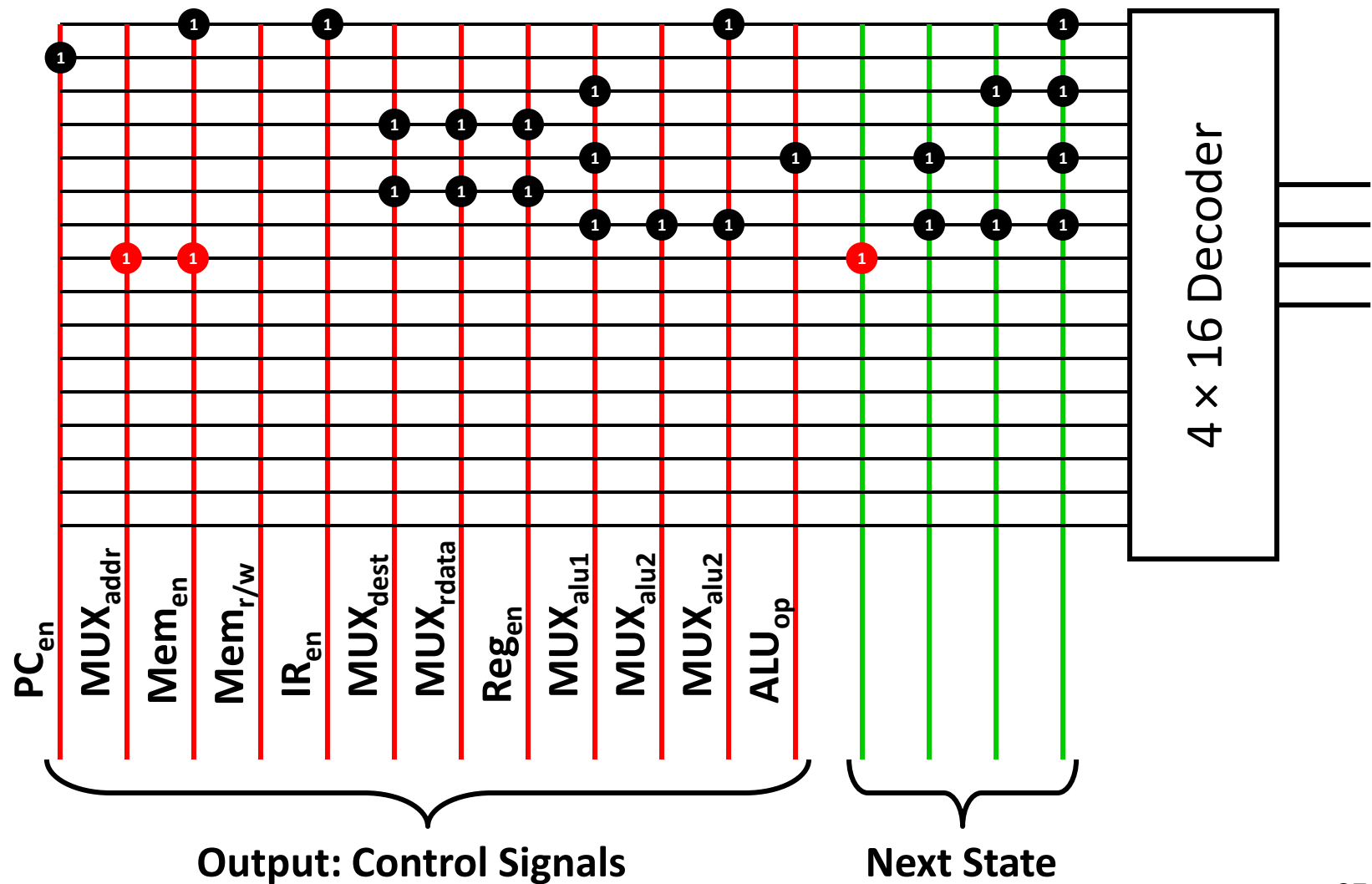
# State 7: LW cycle 4



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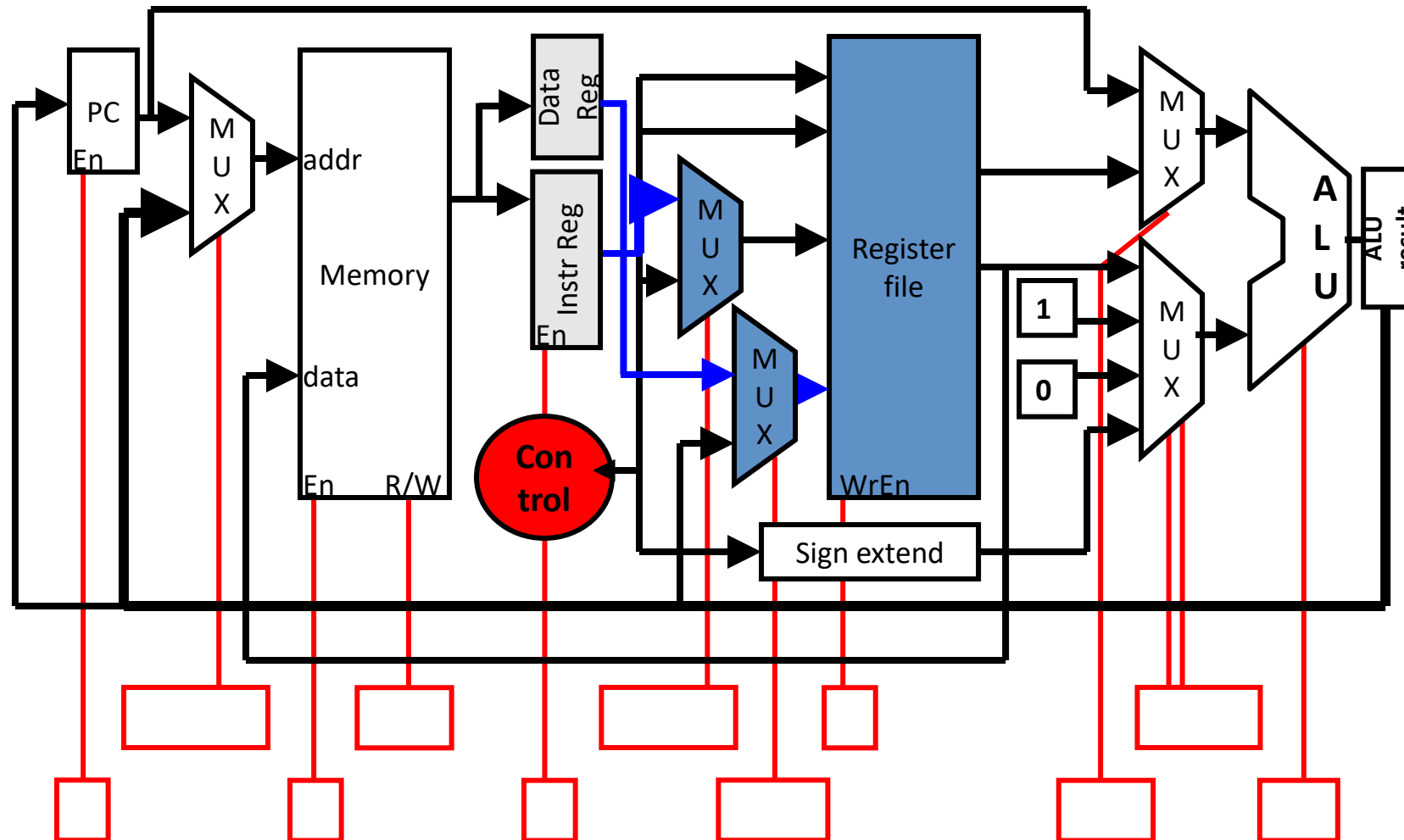


Control Rom (lw cycle 4)



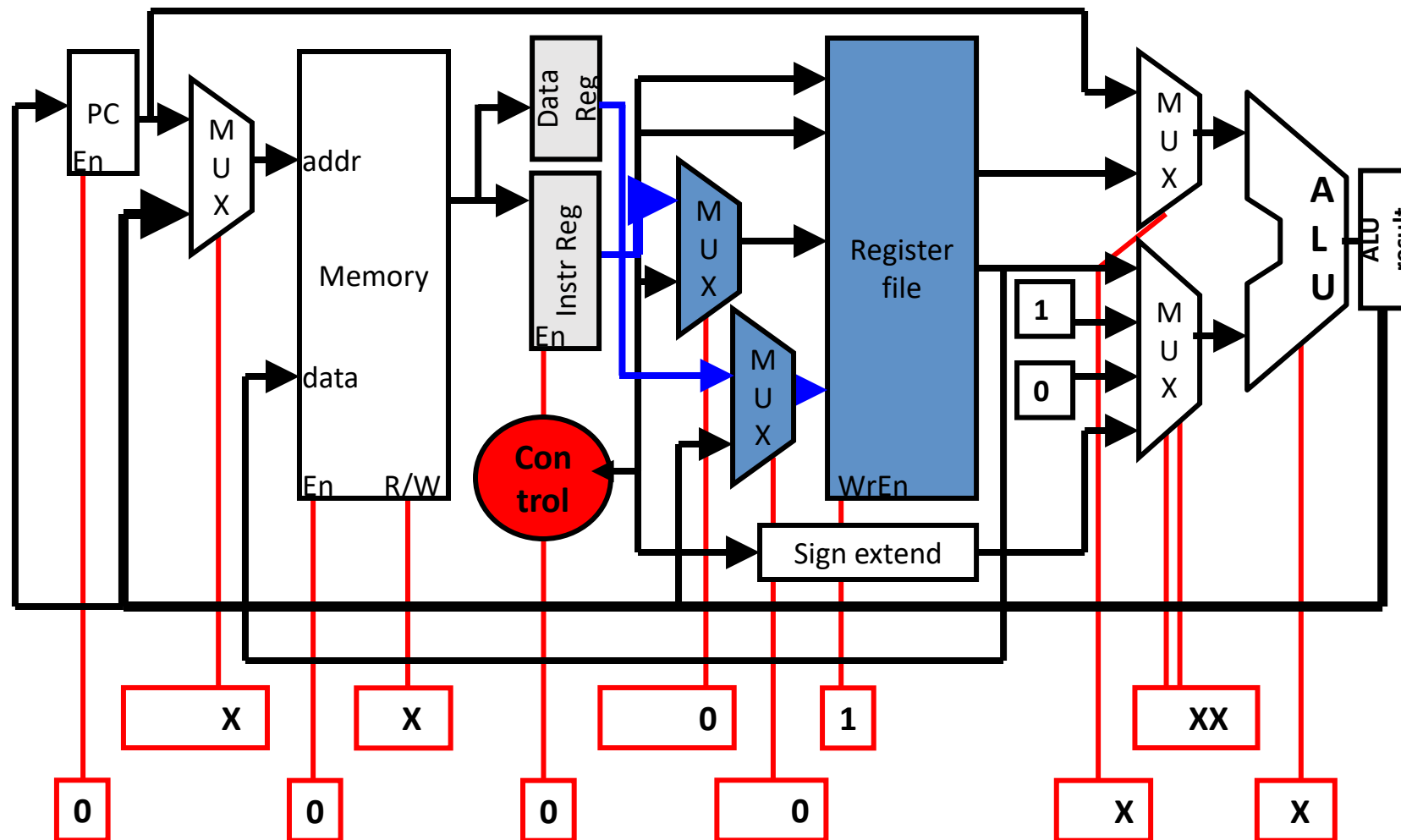
# State 8: LW cycle 5

Write memory value to register file

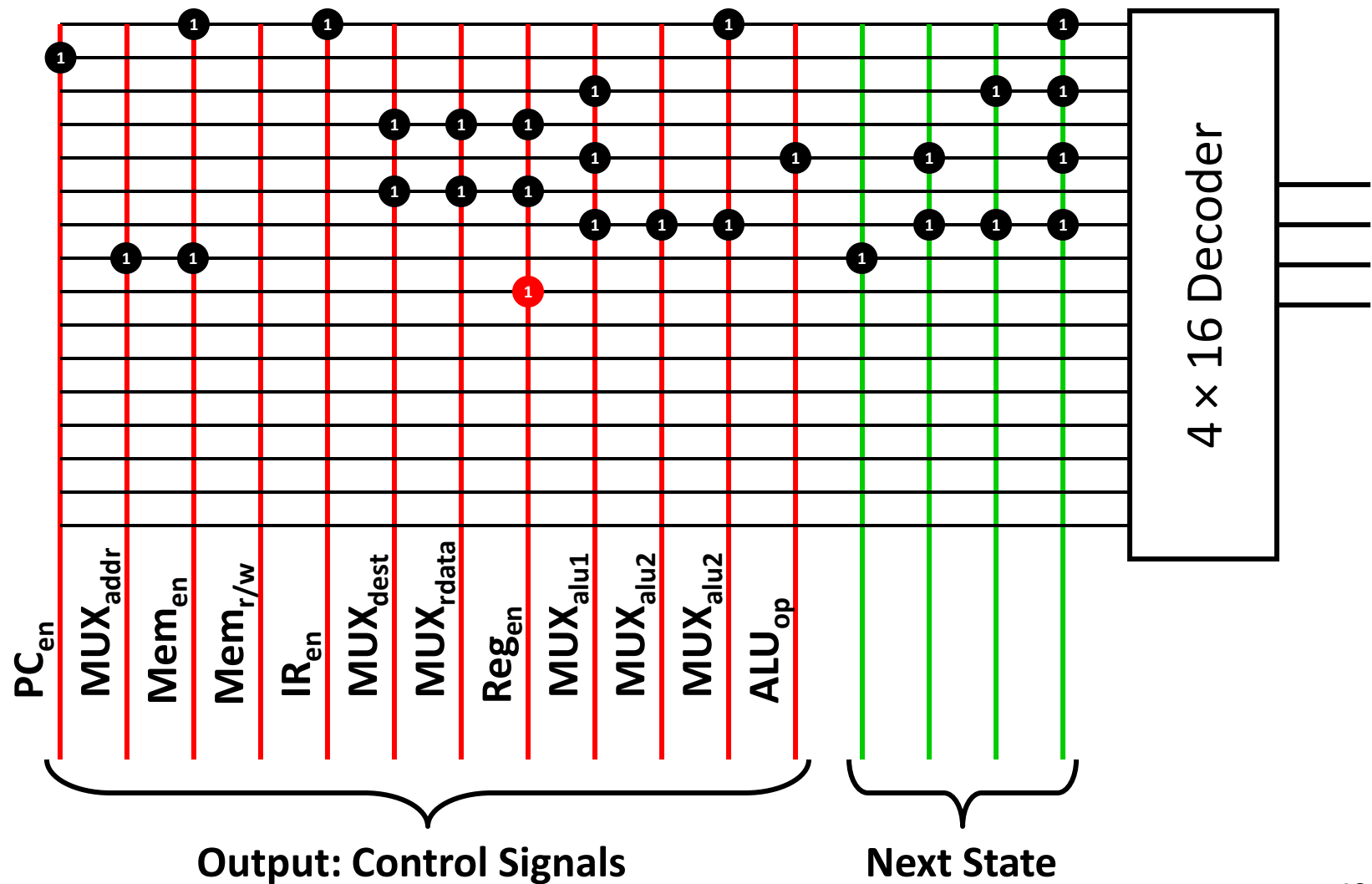


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Write memory value to register file

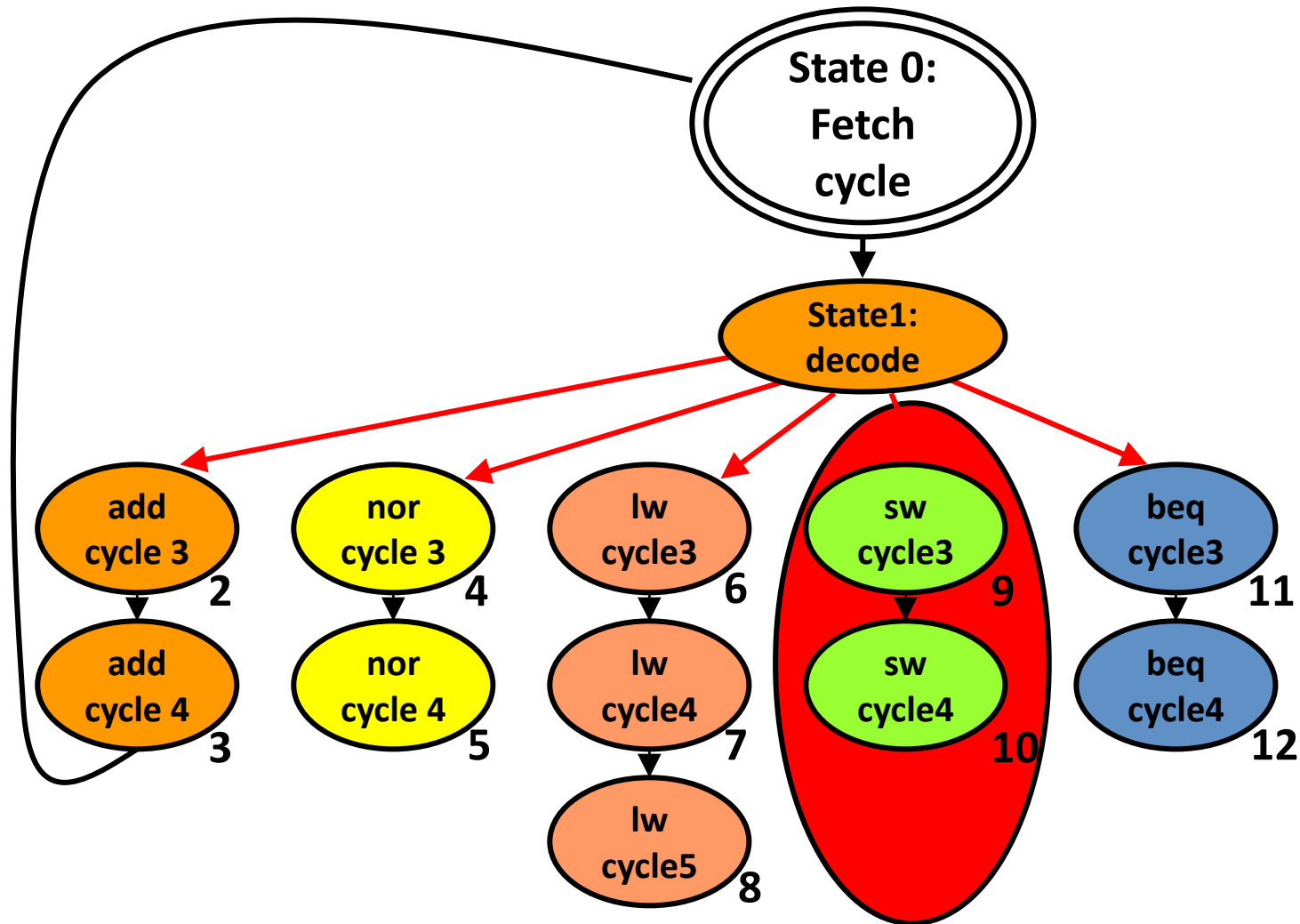


Control Rom (lw cycle 5)



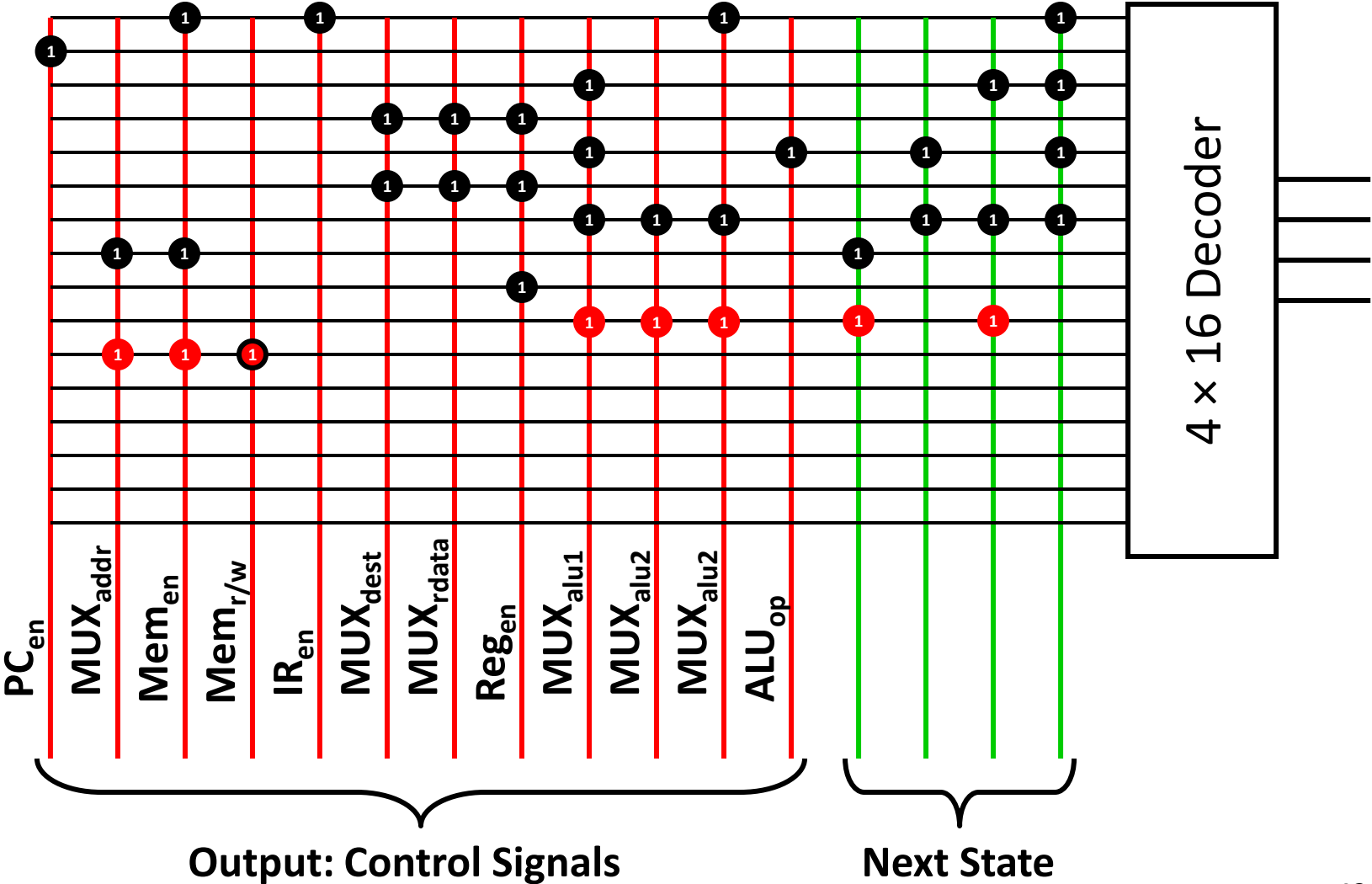


# Return to State 0: Fetch cycle to execute the next instruction

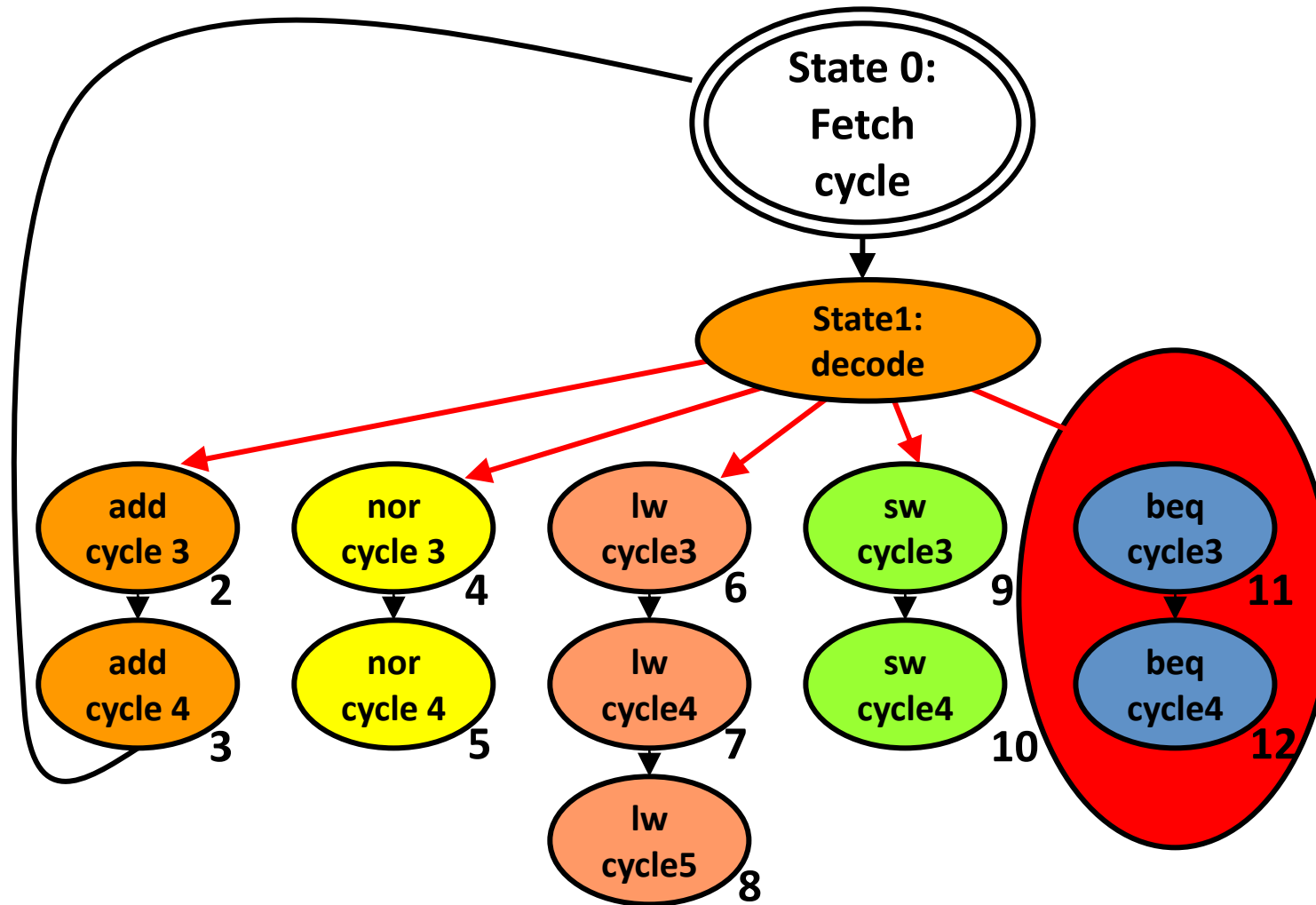


Same as lw, except  $\text{Mem}_{r/w}$  and Next State

# Control Rom (sw cycles 3 and 4)

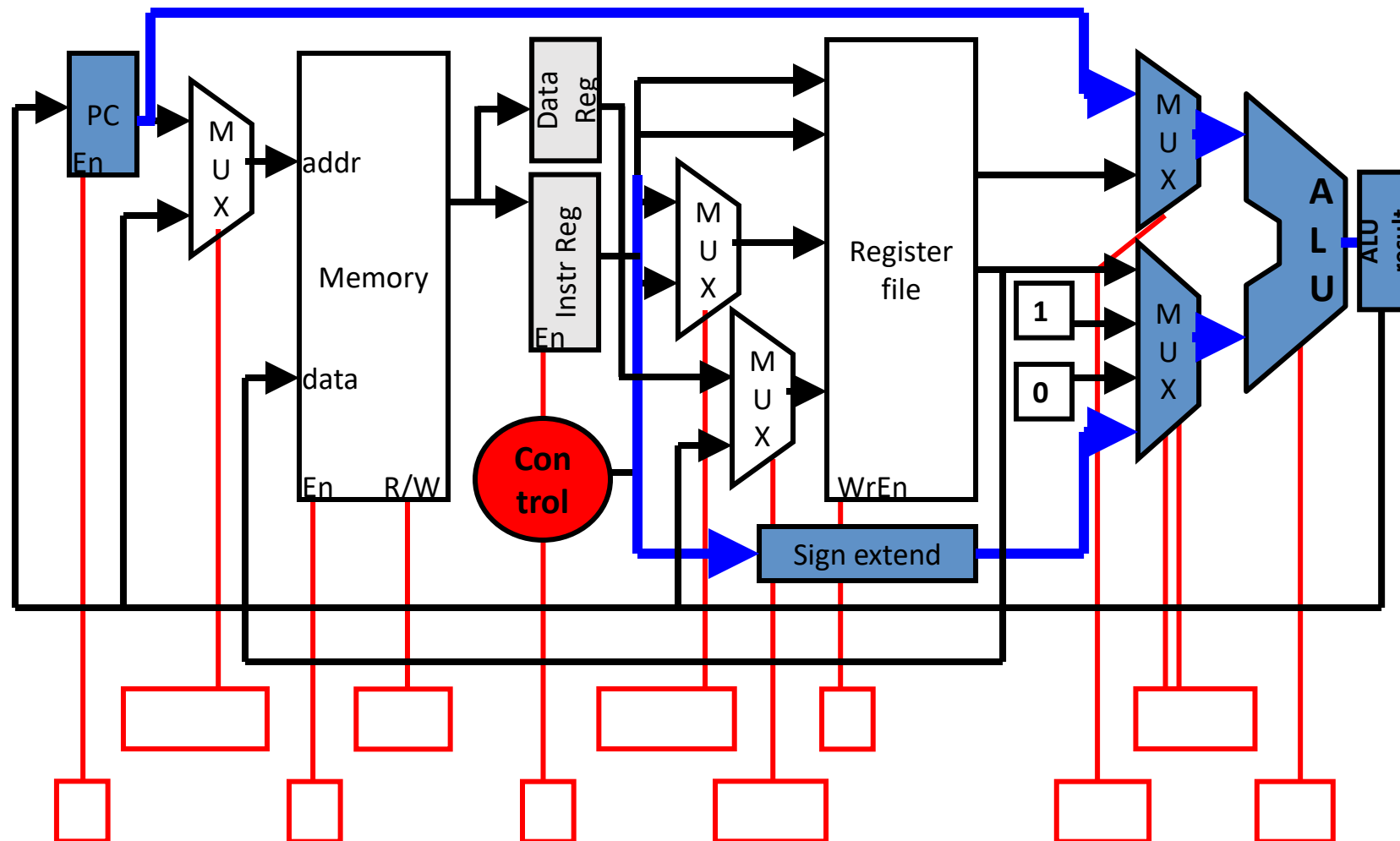


# Return to State 0: Fetch cycle to execute the next instruction



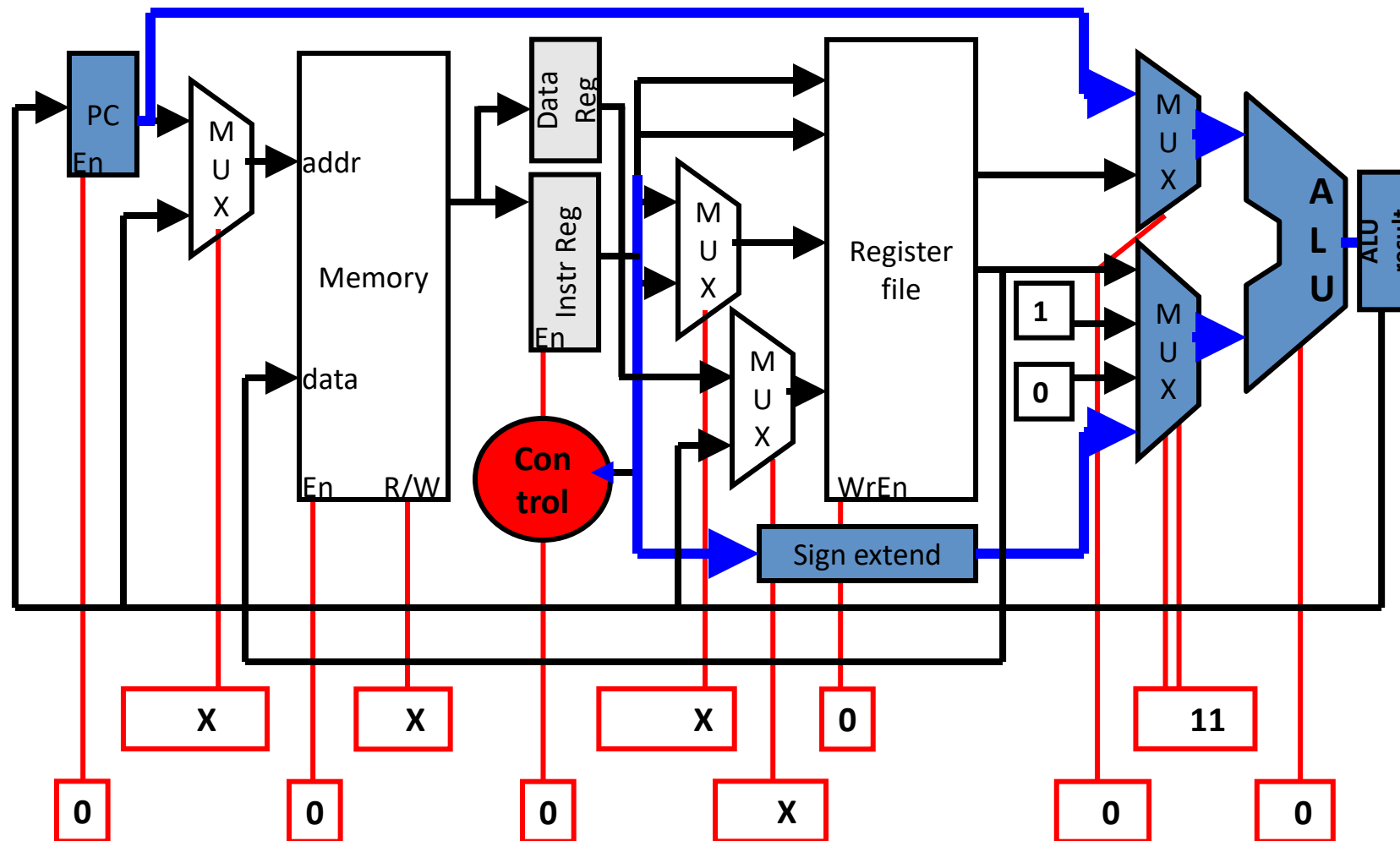
# State 11: beq cycle 3

Calculate target address for branch

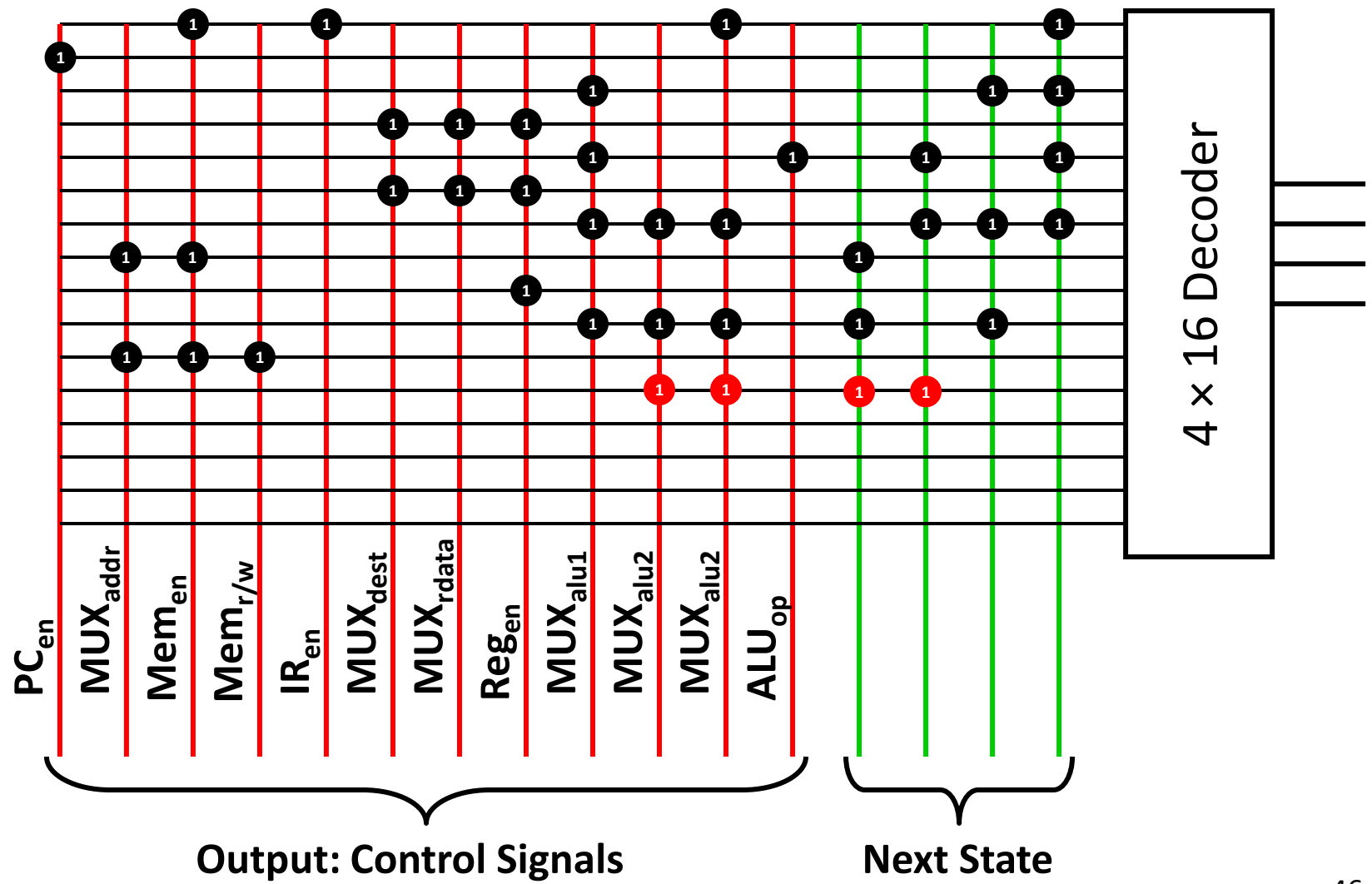


# State 11: beq cycle 3

Calculate target address for branch

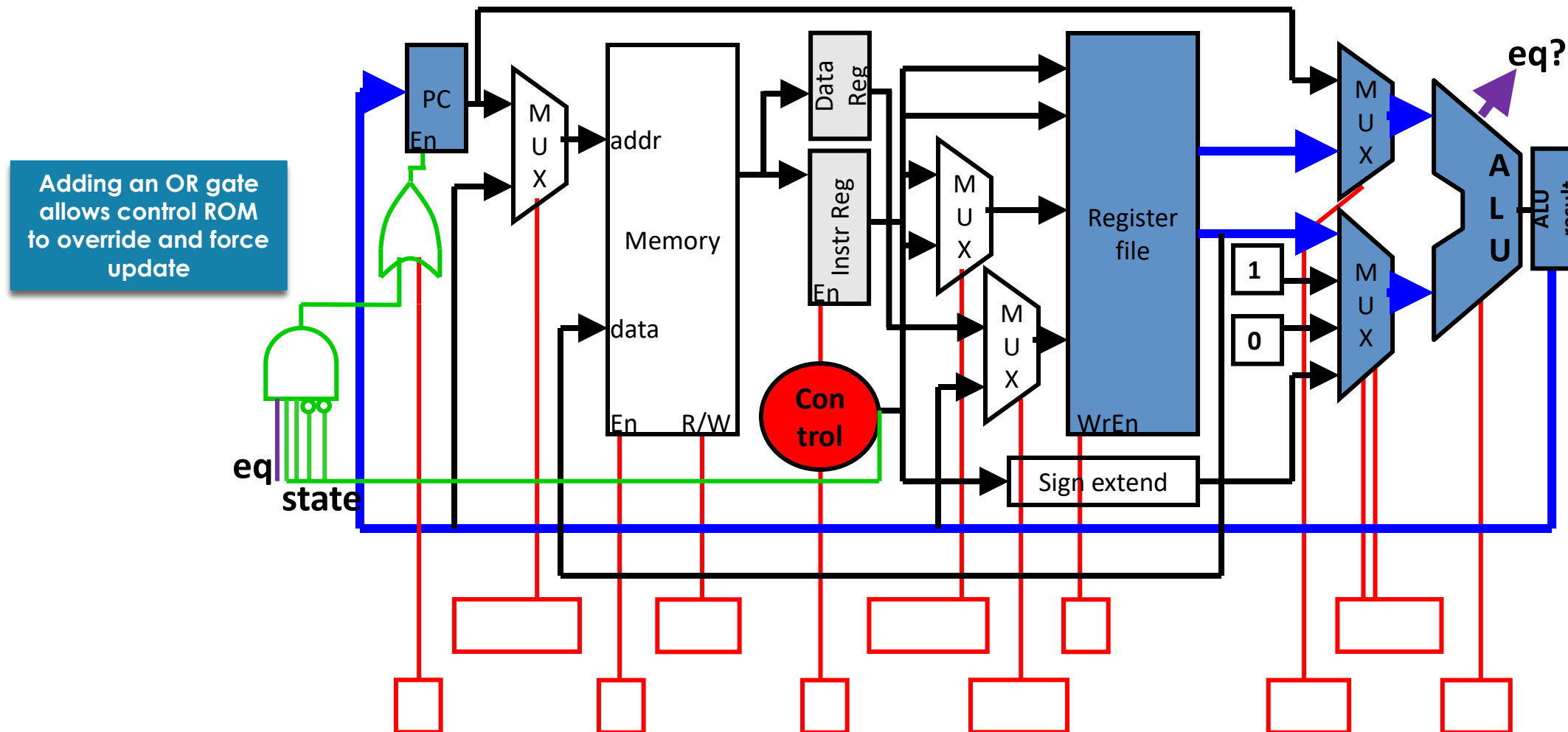


Control Rom (beq cycle 3)



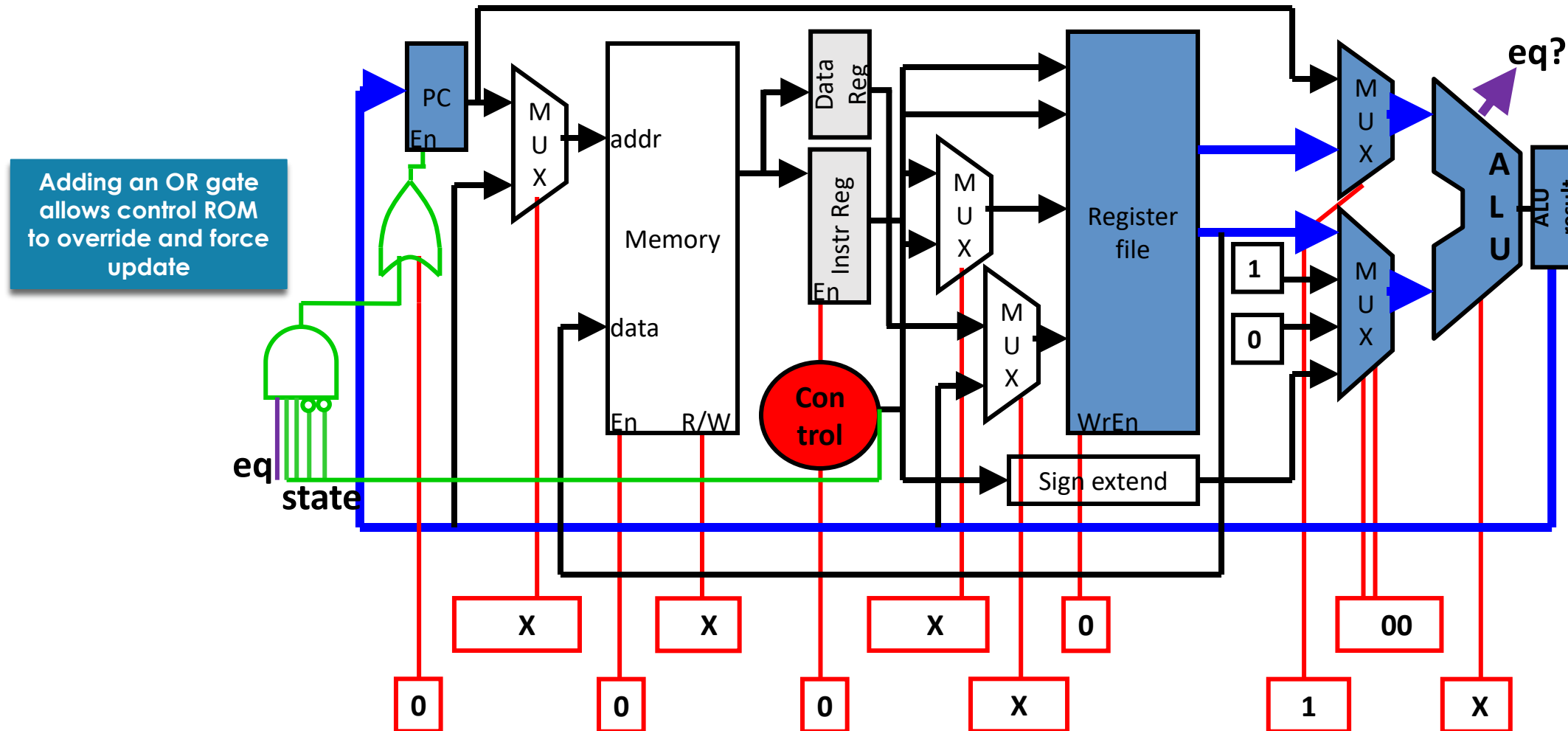
# State 12: beq cycle 4

Write target address into PC  
if ( $\text{data}_{\text{rega}} == \text{data}_{\text{regb}}$ )



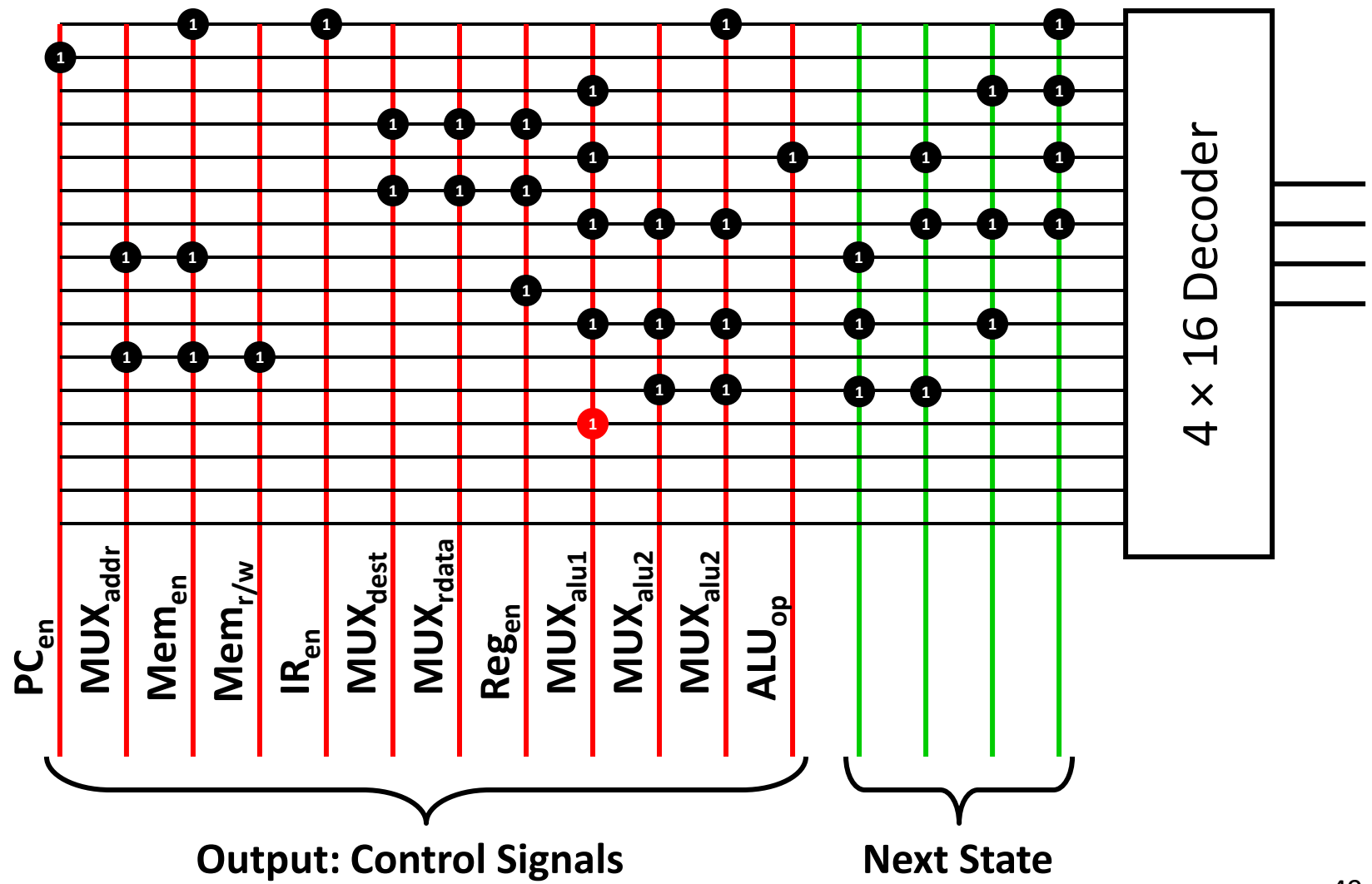
# State 12: beq cycle 4

Write target address into PC  
if ( $\text{data}_{\text{rega}} == \text{data}_{\text{regb}}$ )





Control Rom (beq cycle 4)



# Single vs Multi-cycle Performance

1 ns – Register File read/write time

2 ns – ALU/adder

2 ns – memory access

0 ns – MUX, PC access, sign extend,  
ROM

1. Assuming the above delays, what is the best cycle time that the LC2k multi-cycle datapath could achieve? Single cycle?
2. Assuming the above delays, for a program consisting of 25 LW, 10 SW, 45 ADD, and 20 BEQ, which is faster?



# Single vs Multi-cycle Performance

1 ns – Register File read/write time

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2 ns – memory access

0 ns – MUX, PC access, sign extend,  
ROM

1. Assuming the above delays, what is the best cycle time that the LC2k multi-cycle datapath could achieve? Single cycle?

$$\text{MC: } \text{MAX}(2, 1, 2, 2, 1) = 2\text{ns}$$

$$\text{SC: } 2 + 1 + 2 + 2 + 1 = 8\text{ ns}$$

2. Assuming the above delays, for a program consisting of 25 LW, 10 SW, 45 ADD, and 20 BEQ, which is faster?

$$\text{SC: } 100 \text{ cycles} * 8 \text{ ns} = 800 \text{ ns}$$

$$\text{MC: } (25*5 + 10*4 + 45*4 + 20*4) \text{cycles} * 2\text{ns} = 850 \text{ ns}$$



# Single and Multi-cycle performance

- Wait, multi-cycle is worse??
- For our ISA, most instructions take about the same time
- Multi-cycle shines when some instructions take much longer
- E.g. if we add a long latency instruction like multiply:
  - Let's say operation takes 10 ns, but could be split into 5 stages of 2 ns
  - SC: clock period = 16 ns, performance is 1600 ns
  - MC: clock period = 2 ns, performance is 850 ns

# Performance Metrics – Execution time

- What we really care about in a program is **execution time**
  - **Execution time** = total instructions executed X CPI x clock period
  - The "Iron Law" of performance
- CPI = **average** number of clock **cycles per instruction** *for an application*
- To calculate multi-cycle CPI we need:
  - Cycles necessary for each type of instruction
  - Mix of instructions executed in the application (dynamic instruction execution profile)

Poll: What are the units of  
(instructions executed x CPI x  
clock period)?

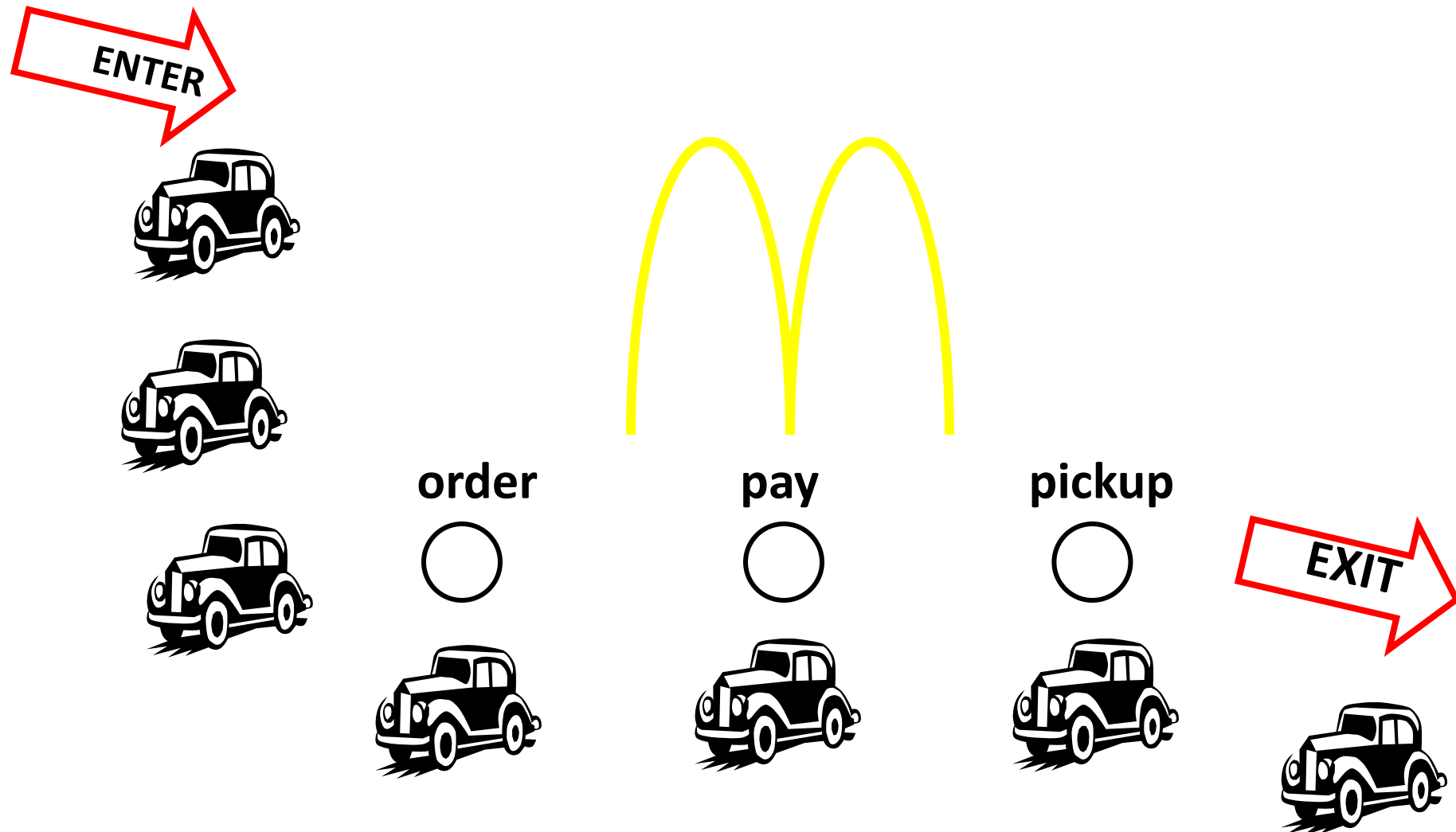
# Datapath Summary

- Single-cycle processor
  - $\text{CPI} = 1$  (by definition)
  - clock period =  $\sim 10$  ns
- Multi-cycle processor
  - $\text{CPI} = \sim 4.25$
  - clock period =  $\sim 2$  ns
- Better design:
  - $\text{CPI} = 1$
  - clock period =  $\sim 2$  ns
- How??
  - Work on multiple instructions at the same time

# Pipelining

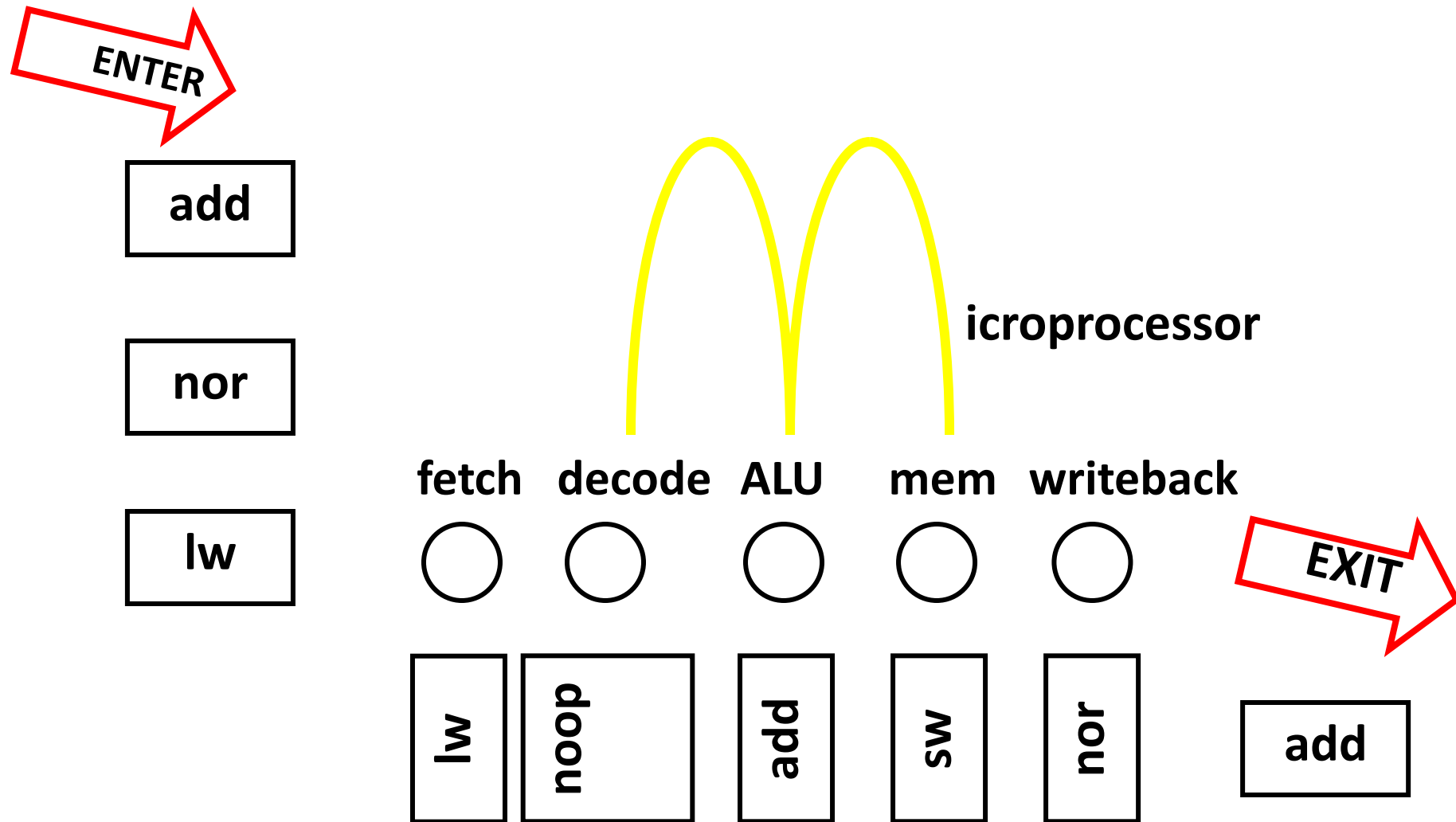
- Want to execute an instruction?
  - Build a processor (multi-cycle)
  - Find instructions
  - Line up instructions (1, 2, 3, ...)
  - Overlap execution
    - Cycle #1: Fetch 1
    - Cycle #2: Decode 1      Fetch 2
    - Cycle #3: ALU 1      Decode 2      Fetch 3
    - .....
  - This is called pipelining instruction execution.
  - Used extensively for the first time on IBM 360 (1960s).
  - CPI approaches 1.

# Pipelining





# Pipelining



# Next time

- Exam Review

