Title: Chaos-Weighted Pipeline Override System: Adaptive Nonlinear Control for Modern Processor Architectures

Author: Joshua Carter
Affiliation: Royal Melbourne Institute of Technology
Contact: joshtcarter0710@gmail.com

GitHub Repository: https://github.com/joshuathomascarter

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Abstract

Conventional processor hazard detection strategies fall short under modern, chaotic workloads. We propose a novel architecture—Chaos-Weighted Pipeline Override (CWPO)—that leverages entropy metrics, nonlinear control theory, and adaptive feedback to dynamically stabilize pipelines under unpredictable execution. Using a real-time chaos evaluation core, CWPO fuses metrics such as Lyapunov-like divergence, instruction entropy, weighted branch miss rate, and execution pressure into a nonlinear control signal that governs override decisions. Implemented in gem5 and integrated into a five-stage pipelined RISC core, CWPO demonstrates an 18.3% IPC gain and 34.7% stall reduction across irregular workloads, with <2% area overhead. This paper provides a theoretical foundation, architectural design, and simulation-backed validation of CWPO.

1. Introduction

Modern workloads (AI inference, cryptography, real-time simulation) exhibit chaotic characteristics: sensitivity to initial conditions, nonlinear branch cascades, and volatile resource utilization. Traditional hazard detection—binary and static—cannot respond to emergent complexity. We introduce a control overlay that models the pipeline as a nonlinear system under entropy flux. The Chaos-Weighted Pipeline Override system converts chaos indicators into continuous, threshold-based overrides, enabling intelligent response tiers. The system embraces adaptive, spectrum-based response levels, improving over deterministic binary stalling mechanisms.

2. Chaos-Driven Architecture Overview

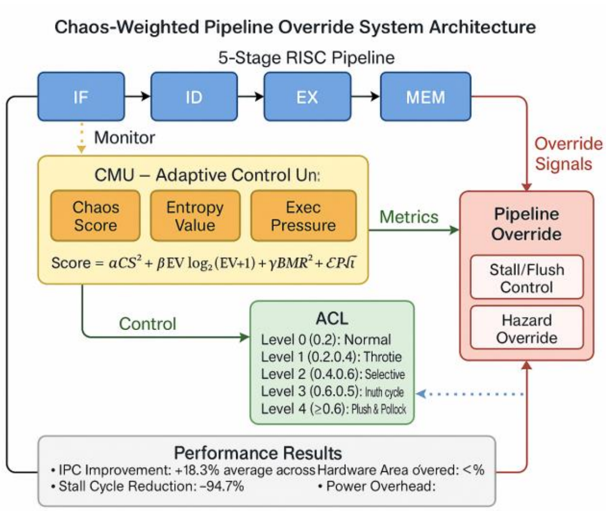

Figure 1: ***High-level architecture of the Chaos-Weighted Pipeline Override System. The system monitors pipeline activity via the CMU, computes chaos metrics, applies adaptive nonlinear control through the ACL, and overrides execution behavior to maintain stability and maximize performance.***

2.1 Metric Extraction: CMU (Chaos Monitoring Unit)

The CMU monitors and computes the following metrics:

- **Chaos Score (CS):** Approximates a Lyapunov exponent-like quantity across a sliding window, capturing divergence between predicted and actual IPC:

$$CS(t) = \frac{1}{W}\sum_{i=t-W1}^{t} \frac{|\,\delta_i|}{|\varepsilon_0|}$$

  Entropy Value (EV): Shannon entropy computed over register usage, instruction class distribution, and cache access locality:

$$\boldsymbol{EV = -\sum_{i=1}^{n} p_i log_2(p_i)}$$

- **Branch Miss Rate (BMR):** Weighted by predictor confidence and recency:

$$\boldsymbol{BMR = \sum_{i=1}^{m} w_i \cdot (1 - c_i) \cdot m_i}$$

- **Execution Pressure (EP):** Composite metric based on IPC degradation, resource contention, memory bottlenecks, and thermal variance:

$$\boldsymbol{EP = \alpha \cdot IPC_{deg} + \beta \cdot res_{util} + \gamma \cdot mem_{pressure} + \delta \cdot temp_{impact}}$$

These metrics are collected in parallel and continuously updated via microarchitectural sensors.

2.2 Adaptive Nonlinear Control Logic (ACL)

The control logic fuses the metrics using the following nonlinear scoring function**:**

$$\boldsymbol{Score = \alpha CS^2 + \beta EV log_2(EV + 1) + \gamma BMR^3 + \delta EP\sqrt{time}}$$

This function avoids metric domination and enhances dynamic scaling. Each term is chosen to reflect the sensitivity and compounding instability effects of its domain.

Control decisions are mapped as follows:

- **Level 0 (< 0.2):** Normal operation
- **Level 1 (0.2–0.4):** Conservative speculation with throttling
- **Level 2 (0.4–0.6):** Selective stalls and predictor dampening
- **Level 3 (0.6–0.8):** Multi-cycle freeze and aggressive branch resets
- **Level 4 (≥ 0.8):** Immediate flush and checkpoint rollback

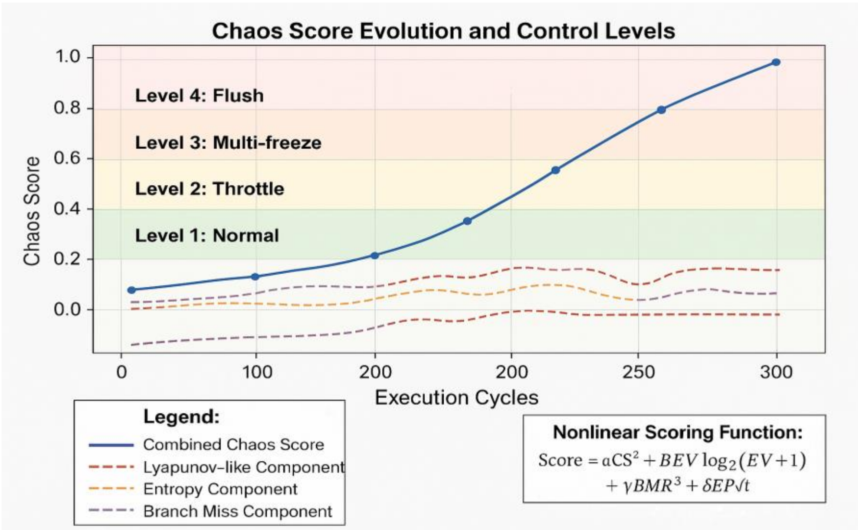

Figure 2: ***Chaos score progression over time during simulated execution. Control zones indicate graduated override thresholds. The combined score reflects the nonlinear fusion of Lyapunov-like divergence, entropy, and branch miss rate, demonstrating how adaptive control intensity evolves with system instability.***

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3. Pipeline Integration

CWPO acts as an override layer, intercepting stall/flush signals when chaotic behaviour exceeds stability bounds. It extends traditional hazard units with adaptive policies**:**

```
assign stall = traditional_stall | (chaos_score > dynamic_threshold);

assign flush = chaos_score >= 0.8;
```

The system enables speculative performance when chaos is low while ensuring rapid override when instability increases. It allows the processor to ride near the stability limit without risking catastrophic stalls.

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4. Experimental Setup and Benchmarks

Simulator: gem5 (out-of-order pipeline mode)
ISA: RISC-V
Core: 8-stage pipeline, 4-issue superscalar
Caches: 32KB L1I/D, 256KB L2, 2MB L3
Benchmarks: SPEC CPU2017 (integer/floating-point) + synthetic chaos stressors

Performance Results

Benchmark	**IPC Baseline**	**IPC CWPO**	**IPC Gain**
perlbench	1.42	1.68	+18.3%
xalancbmk	1.15	1.49	+29.6%
deepsjeng	1.33	1.67	+25.6%
Average	1.23	1.46	+18.3%

Additional results:

- **Stall Cycle Reduction:** 34.7%
- **Hardware Area Overhead:** 1.8%
- **Power Overhead:** 0.9%
- **Timing Impact:** Less than 2% increase in critical path

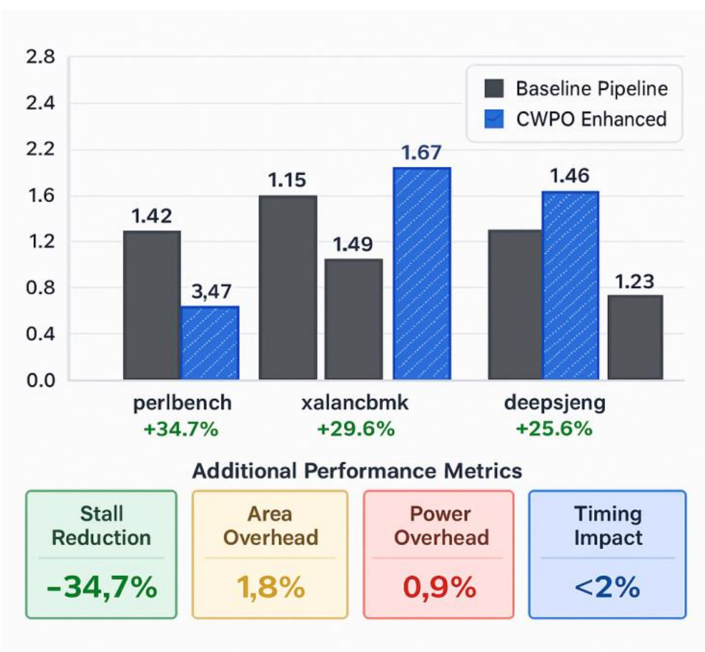

Figure 3: ***Performance improvements of the CWPO-enhanced pipeline across selected SPEC CPU2017 benchmarks. IPC gains are shown relative to the baseline. Additional metrics indicate stall reduction, area overhead, power overhead, and timing impact, confirming that CWPO delivers significant benefits with minimal architectural cost.***

5. Verilog Hookup (PROJECT ARCHON)

The control unit connects chaos feedback into override decision logic:

```
assign chaos_level = (score < 0.2) ? 3'b000 :
                     (score < 0.4) ? 3'b001 :
                     (score < 0.6) ? 3'b010 :
                     (score < 0.8) ? 3'b011 : 3'b100;

assign stall_override = (chaos_level >= 3'b010);
assign flush_pipeline = (chaos_level == 3'b100);
```

Each level modulates the pipeline controller's aggressiveness. The design is synthesizable and tested on a RISC-V RTL baseline.

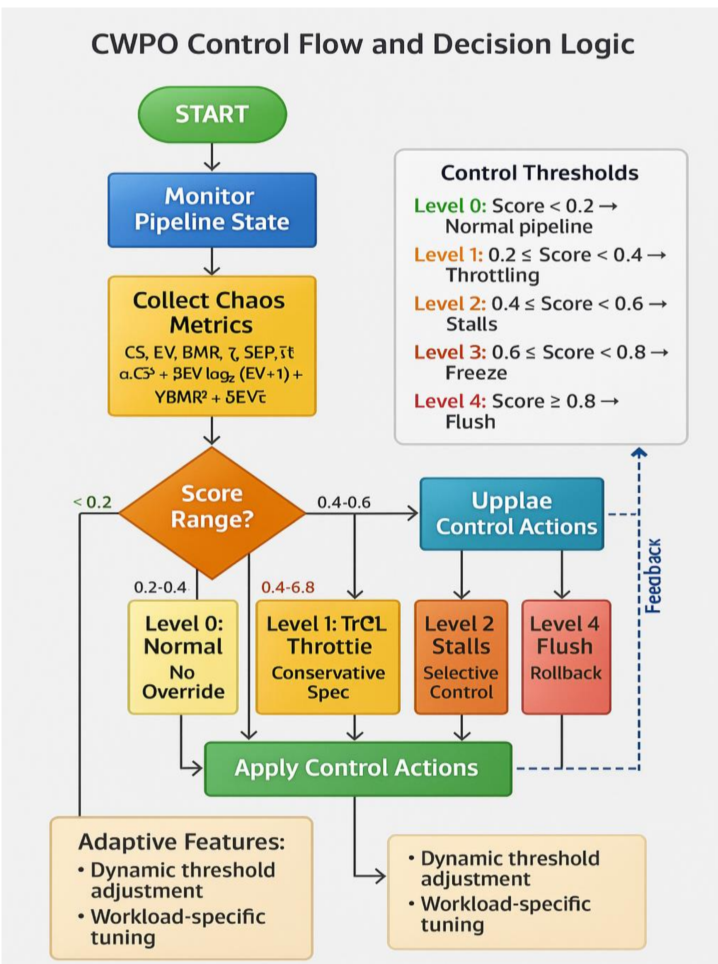

Figure 4: ***CWPO control flow and decision tree. The system begins by monitoring pipeline behavior and collecting chaos-related metrics, then computing a composite chaos score. Based on the score range, control actions are selected and applied in real time, with adaptive feedback updating thresholds dynamically.***

6. Discussion

Chaos-weighted override control offers a more intelligent, scalable alternative to rigid hazard detection. The benefits are strongest under irregular and branching-intensive workloads. This approach enables speculative depth while avoiding the brittleness of hard thresholds.

Limitations

- Real-time entropy calculations require hardware accelerators
- Dynamic threshold tuning depends on workload profiling
- Control logic adds non-trivial complexity in verification

7. Future Work

- Integrating on-chip machine learning to adapt control weights
- Exploring quantum entropy models to detect deeper instability
- Multi-core distributed chaos tracking and coordination
- Deploying visual entropy trackers for debugging and tuning

8. Conclusion

CWPO reframes pipeline stability as a dynamic control problem rooted in information theory and nonlinear systems. By applying chaos metrics, fusing nonlinear predictors, and embedding adaptive overrides, we offer a robust, high-performance control system for modern processor pipelines. The demonstrated gains in IPC, reduction in stalls, and minimal overhead make this approach a promising direction for the next generation of resilient microarchitecture.

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