



# GPU Parallel Programming: CUDA

National Tsing Hua University  
2025, Fall Semester



# Outline

- Programming Model
- CUDA Language
- Example Code Study
- CPU & GPU Synchronization
- Multi-GPU

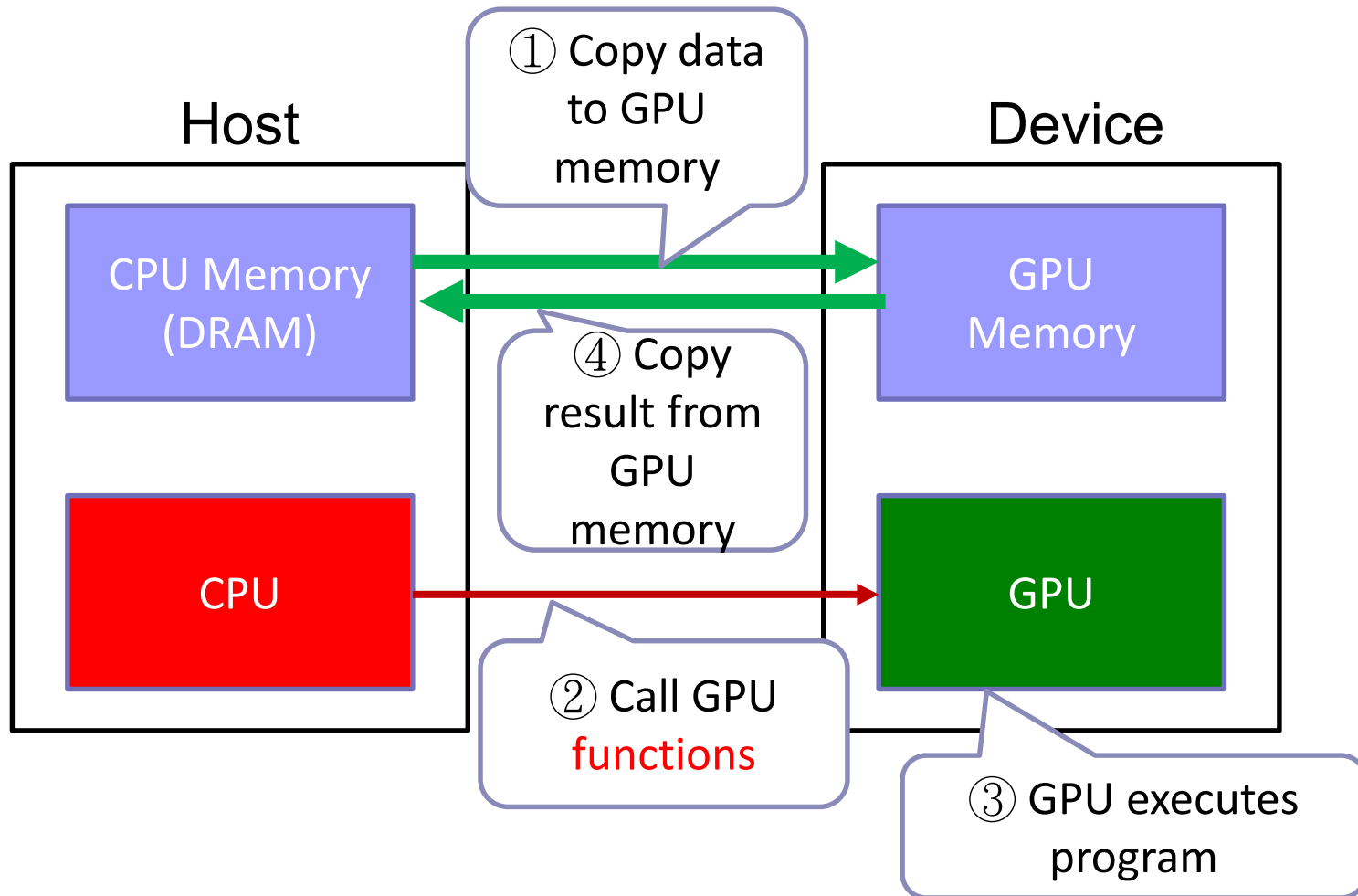
# What is CUDA?

## ■ CUDA: Compute Unified Device Architecture

- CUDA is a **compiler** and **toolkit** for programming NVIDIA GPUs
- Enable heterogeneous computing and horsepower of GPUs
- CUDA API extends the C/C++ programming language
- Express SIMD parallelism
- Give a high level abstraction from hardware

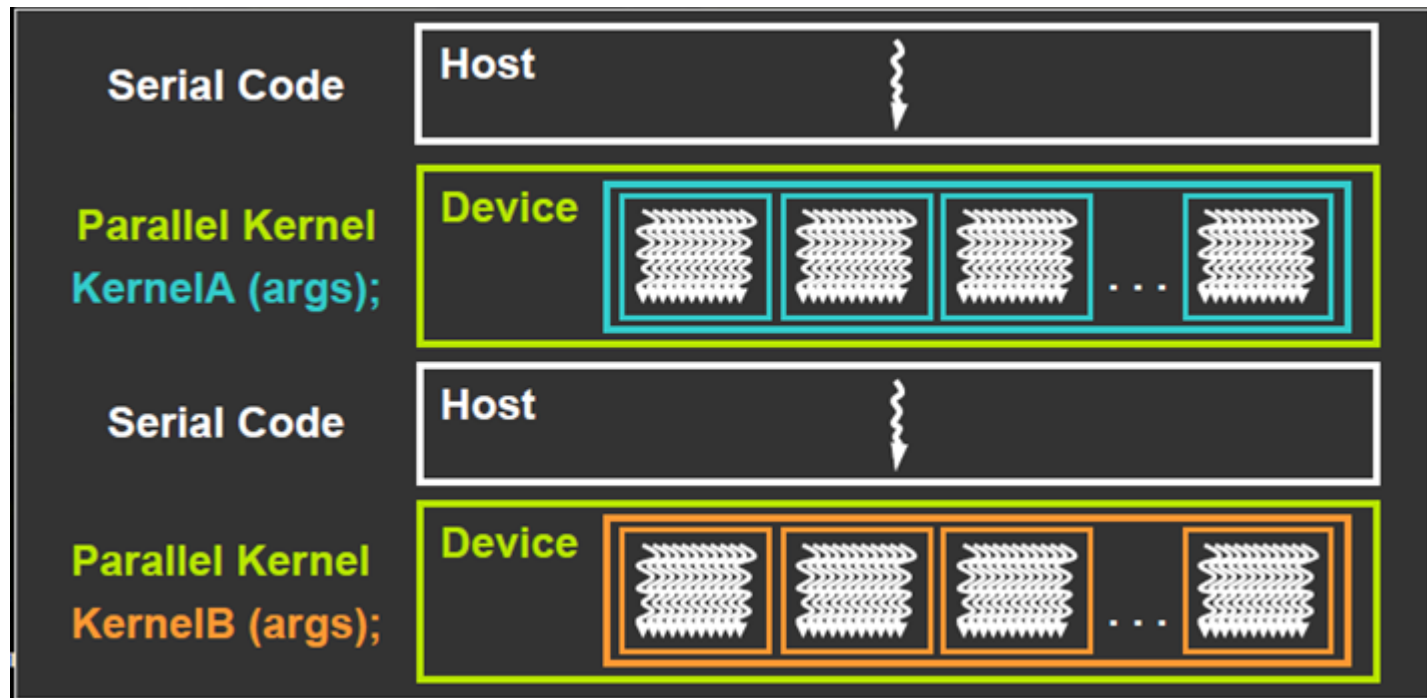
| CUDA SDK Version | Compute Capability | Architecture                   |
|------------------|--------------------|--------------------------------|
| 6.5              | 1.X                | Tesla                          |
| 7.5              | 2.0-5.x            | Fermi, Kepler, Maxwell         |
| 8.0              | 2.0-6.x            | Fermi, Kepler, Maxwell, Pascal |
| 9.0              | 3.0-7.x            | Kepler, Maxwell, Pascal, Volta |

# CUDA program flow



# CUDA Programming Model

- CUDA = serial program with parallel kernels, all in C
  - Serial C code executes in a host thread (i.e. CPU thread)
  - Parallel kernel C code executes in many device threads across multiple processing elements (i.e. GPU threads)



# CUDA program framework

GPU code  
(parallel)

CPU code  
(serial or  
parallel if  
p-thread/  
OpenMP/T  
BB/MPI is  
used.)

```
#include <cuda_runtime.h>
```

```
__global__ void my_kernel(...) {  
    ...  
}
```

```
int main() {  
    ...  
    cudaMalloc(...)  
    cudaMemcpy(...)  
    ...  
    my_kernel<<<nblock,blocksize>>> (...)  
    ...  
    cudaMemcpy(...)  
    ...  
}
```

# Kernel = Many Concurrent Threads

- One kernel is executed at a time on the device
- Many thread execute each kernel
  - Each thread executes the same code
  - ... on the different data based on its threadID

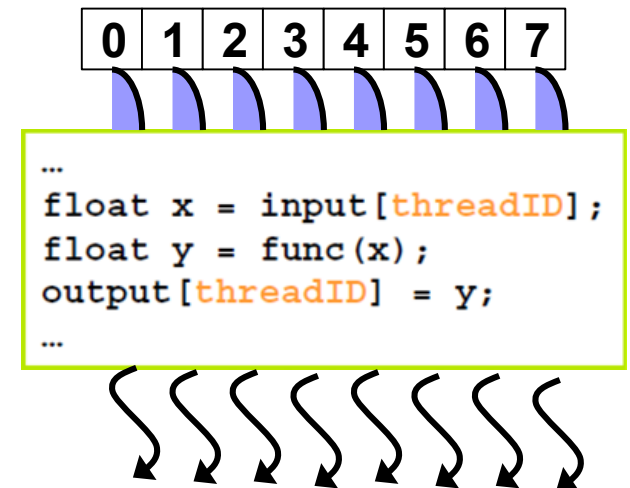
- CUDA thread might be

- Physical threads

- ◆ As on NVIDIA GPUs
    - ◆ GPU thread creation and context switching are essentially free

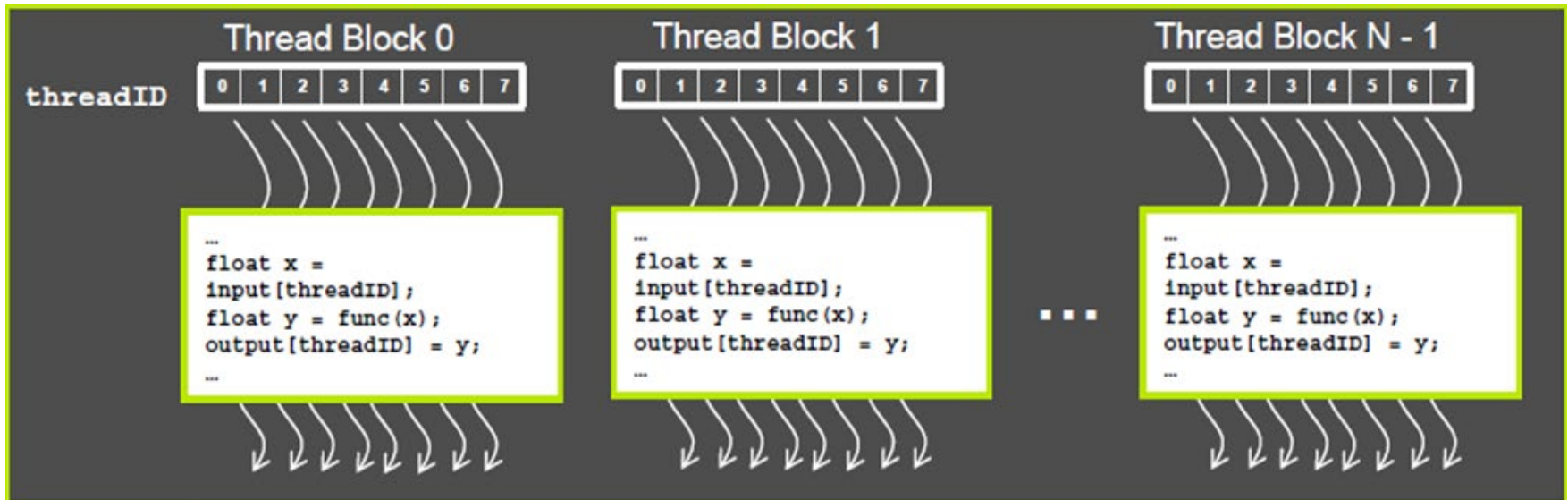
- Or virtual threads

- ◆ E.g. 1 CPU core might execute multiple CUDA threads



# Hierarchy of Concurrent Threads

- Threads are grouped into thread blocks
  - Kernel = grid of thread blocks



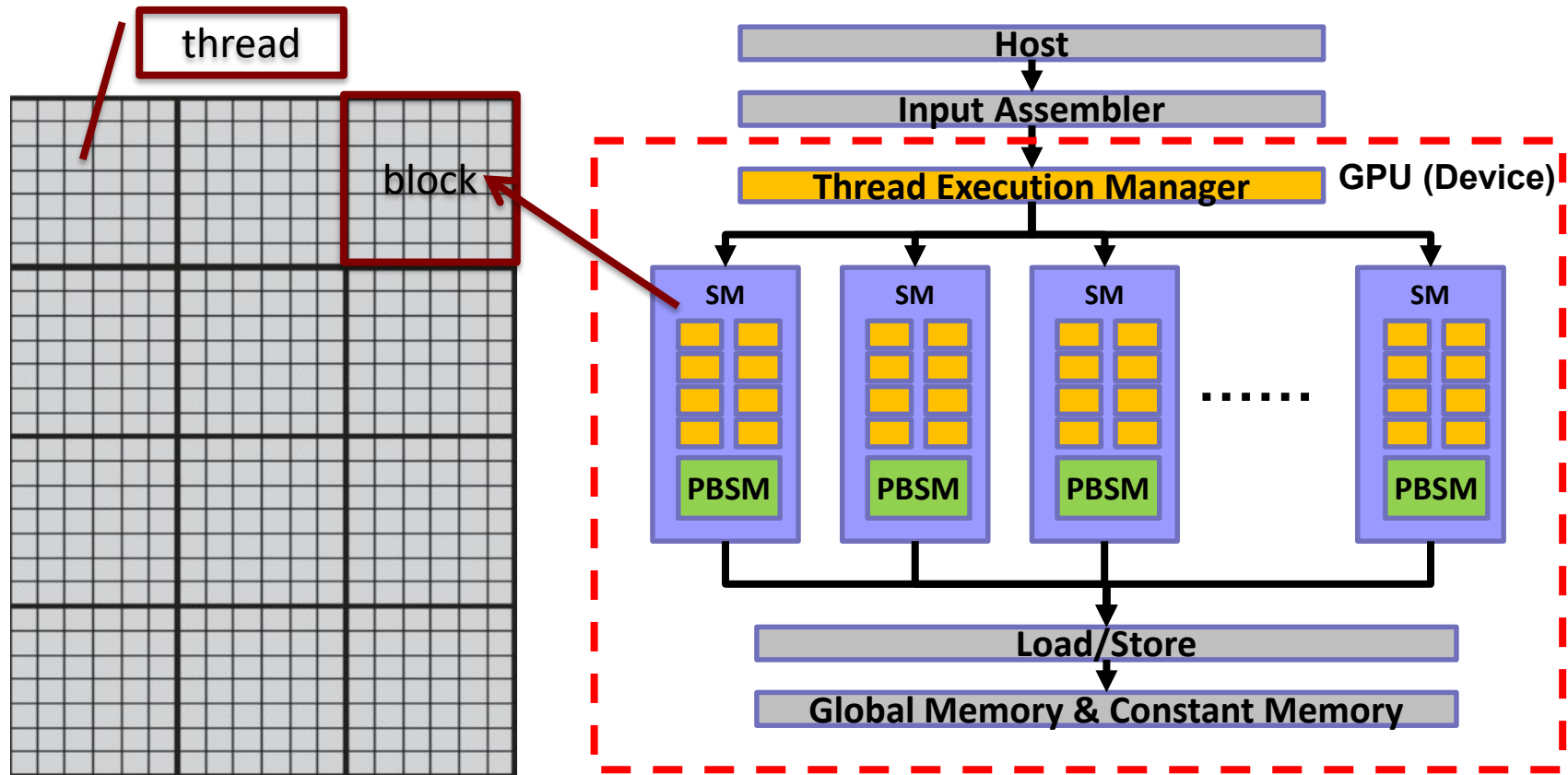
- By definition, threads in the same block may synchronized with barriers, but not between blocks

```
scratch[threadID] = begin[threadID];  
__syncthreads();  
int left = scratch[threadID - 1];
```



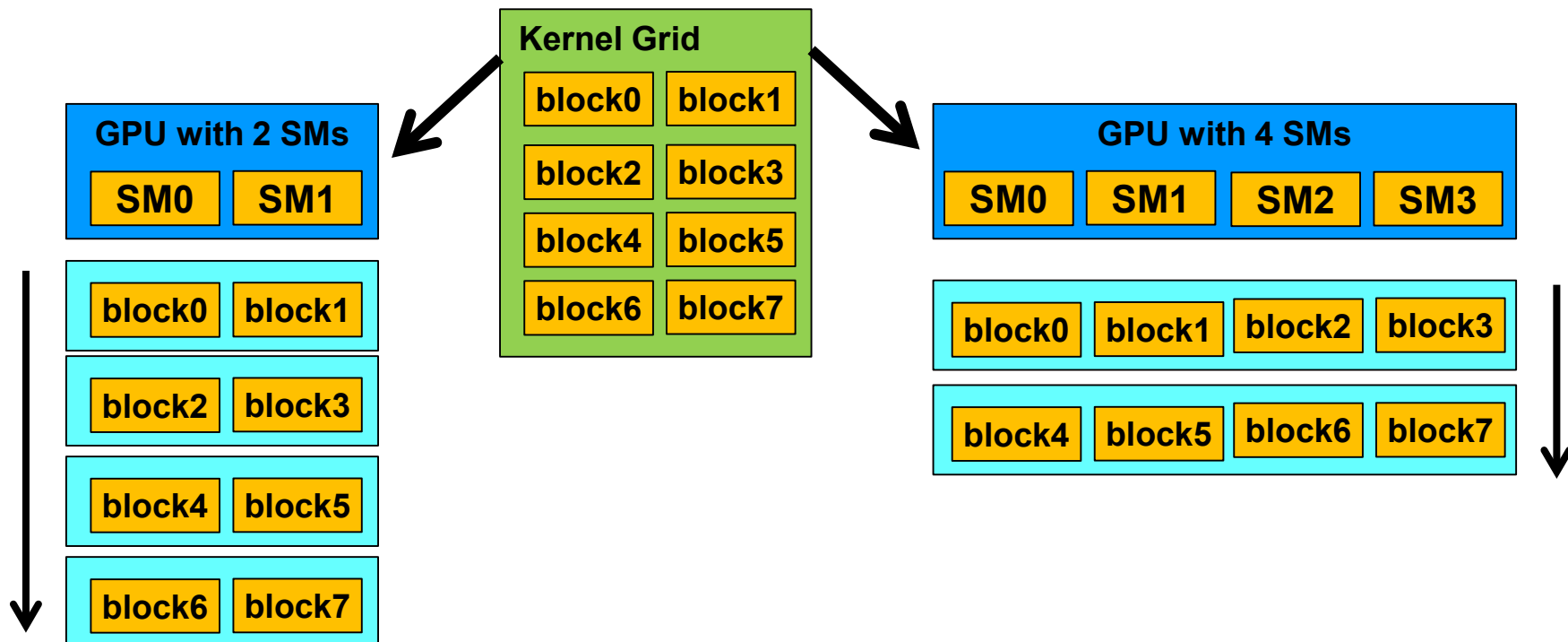
# Software Mapping

- Software: grid → blocks → threads
- Hardware: GPU(device) → SM(multicore processor) → core



# Block Level Scheduling

- Blocks are independent to each other to give scalability
  - A kernel scales across any number of parallel cores by scheduling blocks to SMs



# Thread group limits

## ■ GTX1080 CUDA Capability 6.1

➤ Use `deviceQuery.cpp` to find out your limits

## ■ Total number of threads per kernel = threads per block \* number of blocks

➤ Max dimension size of a thread block (x,y,z): (1024, 1024, 64)

➤ Max dimension size of a grid size (x,y,z): ( $2^{31}-1$ ,  $2^{16}-1$ ,  $2^{16}-1$ )

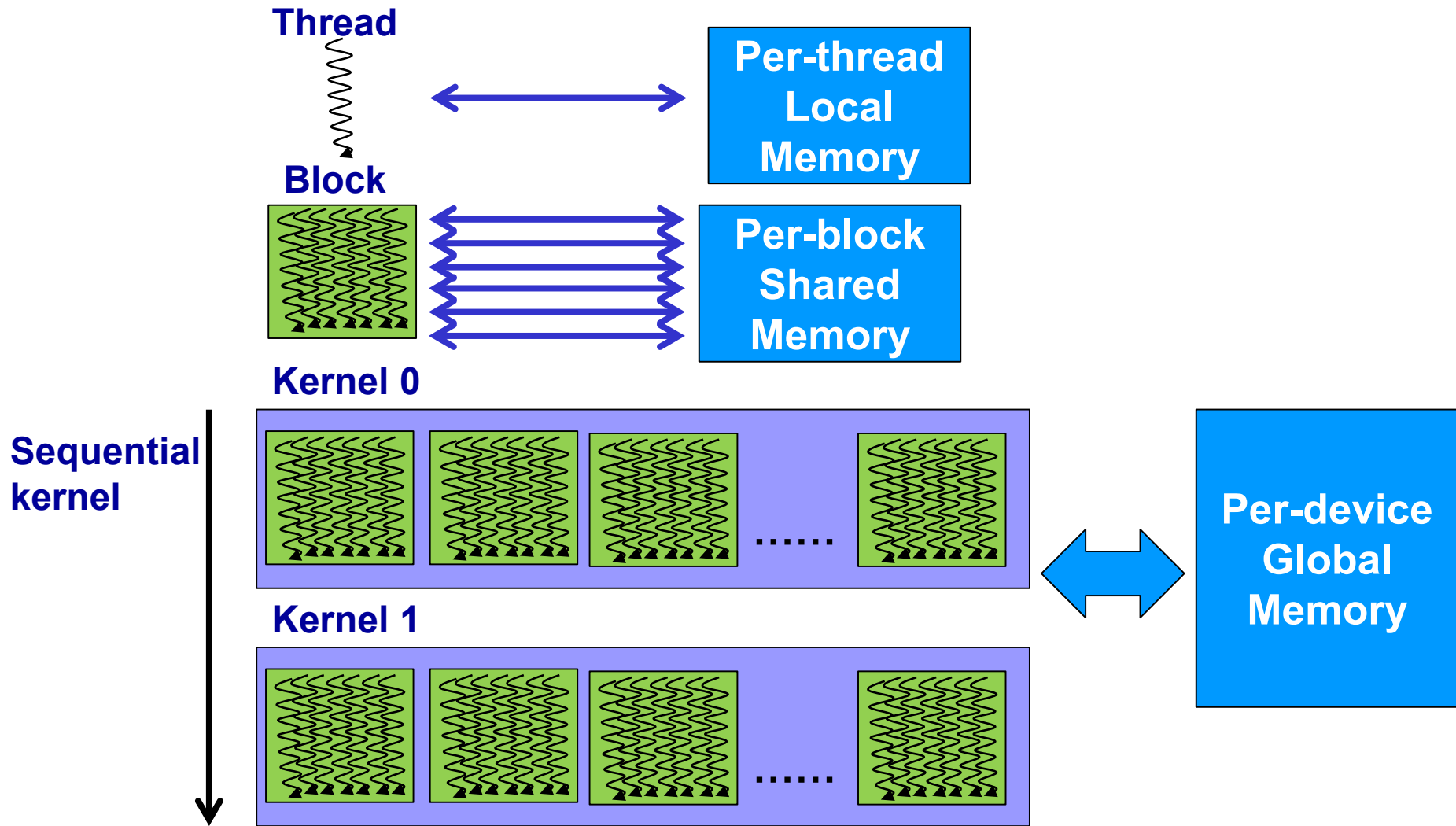
## ■ Maximum execution concurrency

➤ Maximum number of resident grids per device (Concurrent Kernel Execution): 32

➤ Maximum number of threads per multiprocessor: 2048

➤ Maximum number of threads per block: 1024

# Memory Hierarchy



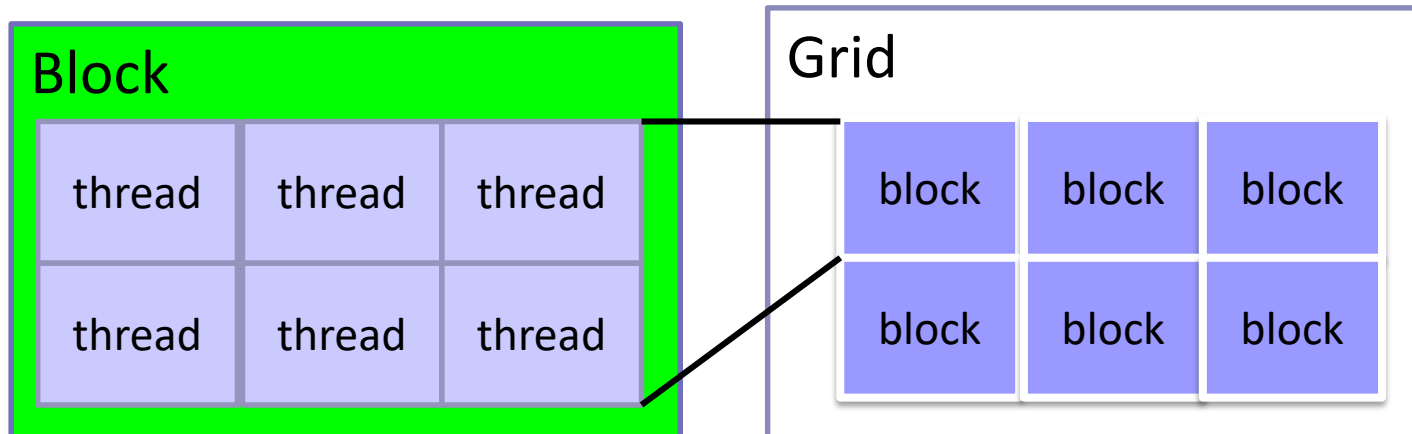
# Memory size limits

## ■ GTX1080 CUDA Capability 6.1

- Use `deviceQuery.cpp` to find out your limits
- Total amount of global memory: 11171 MBytes
- Total amount of constant memory: 64 KBytes
- Total amount of shared memory per block: 48 KBytes
- Total number of registers available per block: 65536

# CUDA Programming Terminology

- Host : CPU
- Device : GPU
- Kernel : functions executed on GPU
- Thread : the basic execution unit
- Block : a group of threads
- Grid : a group of blocks



# Quiz

- Can a kernel run across multiple SM processors?
- Does the kernel below have to run on 10 different SM processors?
  - `my_kernel<<< 10, 10 >>>();`
- Can the threads from a same block run across multiple SM processors?
- What is the difference between the two kernels below?
  1. `my_kernel<<< 1, 100 >>>(A);`
  2. `my_kernel<<< 100, 1 >>>(A);`
- Why shared block memory can only be accessed by the threads in the same blocks?
- Why we have to call `__syncthreads()` within a block if there are data dependency between statements
- Why `__syncthreads()` is not supported across blocks?



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# CUDA Language

Philosophy: provide minimal set of extensions necessary

## ■ Kernel launch

```
kernelFunc<<< nB, nT, nS, Sid >>>(...); // nS and Sid are optional
```

- nB : number of blocks per grid (grid size)
- nT : number of threads per block (block size)
- nS : shared memory size (in bytes)
- Sid : stream ID, default is 0

## ■ Build-in device variables

- threadIdx; blockIdx; blockDim; gridDim

## ■ Intrinsic functions that expose operations in kernel code

```
__syncthreads();
```

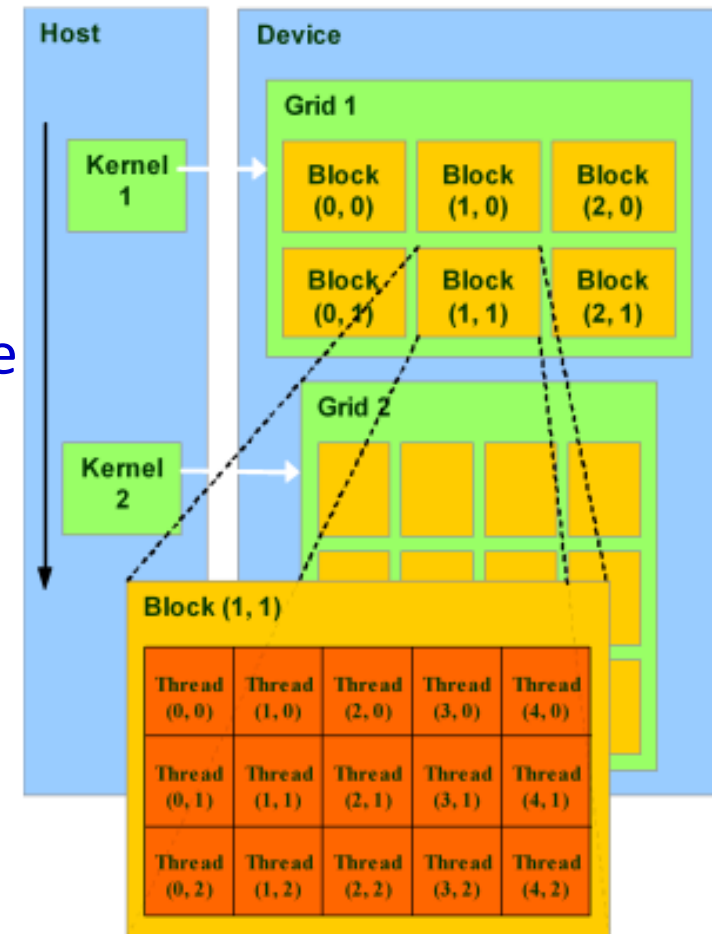
## ■ Declaration specifier to indicate where things live

```
__global__ void KernelFunc(...); // kernel function, run on device  
__device__ void GlobalVar;        // variable in device memory  
__shared__ void SharedVar;        // variable in per-block shared memory
```

# Thread and Block IDs

- Build-in device variables
  - `threadIdx`; `blockIdx`; `blockDim`; `gridDim`
- The index of threads and blocks can be denoted by a 3 dimensional struct
  - `dim3` defined in `vector_types.h`  

```
struct dim3 { x; y; z; };
```
- Example:
  - `dim3 grid(3, 2);`
  - `dim3 blk(5, 3);`
  - `my_kernel<<< grid, blk >>>();`
- Each thread can be uniquely identified by a tuple of index (x,y) or (x,y,z)



Q: When will we use multi-dimensional index?

# Quiz

- How to index a 100 elements of an array under the following kernel launch setting?

```
// Kernel definition
__global__ void VecAdd(float* A)
{
    int i =           
    A[i] = A[i] + 1;
}
```

1. `my_kernel<<< 1, 100 >>>(A);`
2. `my_kernel<<< 100, 1 >>>(A);`
3. `my_kernel<<< 10, 10 >>>(A);`
4. `size=10; dim3 blk(size, size);`  
`my_kernel<<< 1, blk >>>(A, size);`

# Quiz

- How to index a 100 elements of an array under the following kernel launch setting?

```
// Kernel definition
__global__ void VecAdd(float* A)
{
    int i =           
    A[i] = A[i] + 1;
}
```

1. `my_kernel<<< 1, 100 >>>(A);` → `int i = threadIdx;`
2. `my_kernel<<< 100, 1 >>>(A);` → `int i = blockIdx;`
3. `my_kernel<<< 10, 10 >>>(A);`  
→ `int i=blockIdx*blockDim+threadIdx;`
4. `size=10; dim3 blk(size, size);`  
`my_kernel<<< 1, blk >>>(A, size);`  
→ `int i = threadIdx.x * blockDim.x + threadIdx.y;`

# Function Qualifiers

| Function qualifiers                       | limitations   |
|---|---|
| <code>__device__</code> function          | Executed on the device<br>Callable from the device only                                       |
| <code>__global__</code> function          | Executed on the device<br>Callable from the host only<br>(must have <b>void</b> return type!) |
| <code>__host__</code> function            | Executed on the host<br>Callable from the host only   |
| Functions without qualifiers              | Compiled for the host only  |
| <code>__host__ __device__</code> function | Compiled for both the host and the device   |

# Variable Type Qualifiers

| Variable qualifiers           | limitations  |
|-------------------------------|--|
| <code>__device__ var</code>   | <ul style="list-style-type: none"><li>• Resides in <b>device's global memory space</b></li></ul>   |
| <code>__constant__ var</code> | <ul style="list-style-type: none"><li>• Has the lifetime of an application</li><li>• Is accessible from all the threads within the grid and from the host through the runtime library</li></ul>  |
| <code>__shared__ var</code>   | <ul style="list-style-type: none"><li>• Resides in device's <b>constant memory space</b></li></ul> <ul style="list-style-type: none"><li>• Resides in the <b>shared memory</b> space of a thread block</li><li>• Has the <b>lifetime of the block</b></li><li>• Is only accessible from all the threads within the block</li></ul> |

# Device memory operations

## ■ Three functions:

- `cudaMalloc()`, `cudaFree()`, `cudaMemcpy()`
- Similar to the C's `malloc()`, `free()`, `memcpy()`

1. `cudaMalloc(void **devPtr, size_t size)`

- `devPtr`: return the address of the allocated device memory
- `size`: the allocated memory size (**bytes**)

2. `cudaFree (void *devPtr)`

3. `cudaMemcpy( void *dst, const void *src,  
size_t count, enum cudaMemcpyKind kind)`

- `count`: size in **bytes** to copy

# cudaMemcpyKind

- one of the following four values

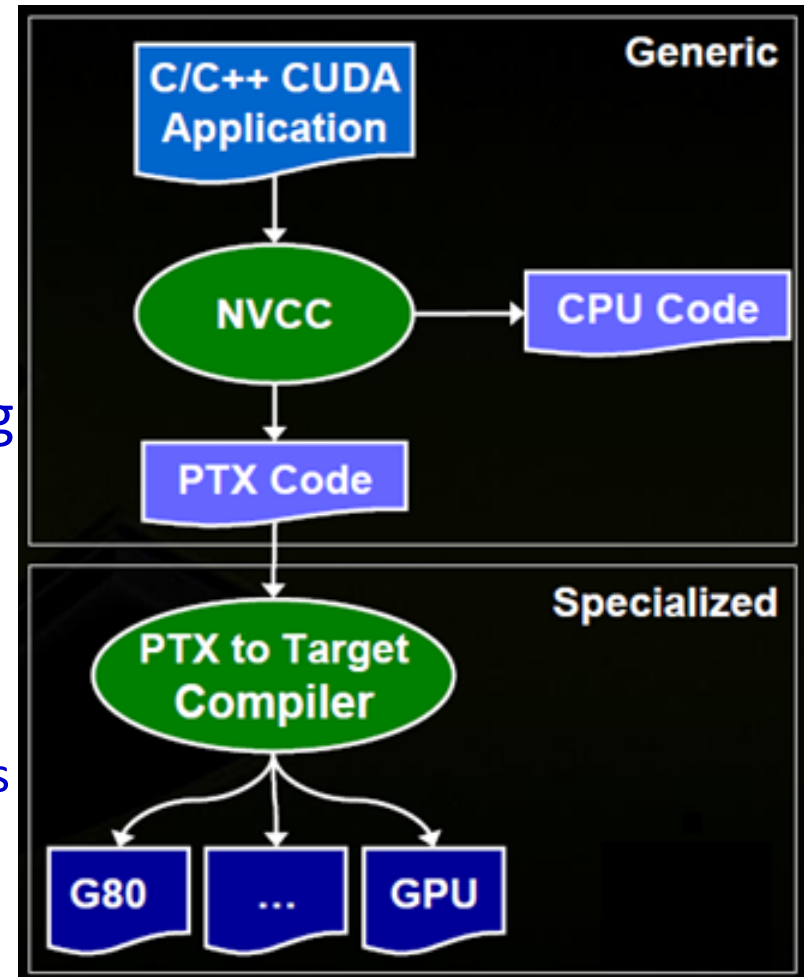
| cudaMemcpyKind           | Meaning         | dst    | src    |
|--------------------------|-----------------|--------|--------|
| cudaMemcpyHostToHost     | Host → Host     | host   | host   |
| cudaMemcpyHostToDevice   | Host → Device   | device | host   |
| cudaMemcpyDeviceToHost   | Device → Host   | host   | device |
| cudaMemcpyDeviceToDevice | Device → Device | device | device |

host to host has the same effect as memcpy()



# Program Compilation

- Any source file containing CUDA language must be compiled with NVCC
  - NVCC separates code running on the host from code running on the device
- Two-stage compilation:
  - Virtual ISA
    - ◆ PTX: Parallel Threads eXecutions
  - Device-specific binary object





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# Example 1: Hello World!


```
__global__ void mykernel(void) {  
  
int main(void) {  
    mykernel<<<1,1>>>();  
    printf("Hello World!\n");  
    return 0;  
}
```

## ■ Two new syntactic elements...

1. `__global__` indicates a function that runs on the device and is called from host code
2. `mykernel<<<1,1>>>()`;  
Triple angle brackets mark a call from host code to device code, which is called a “kernel launch”.

## Example 2: add 2 numbers

```
__global__ void add(int *a, int *b, int *c) {  
    *c = *a + *b;  
}  
int main(void) {  
    int ha=1,hb=2,hc;  
    add<<<1,1>>>(&ha, &hb, &hc);  
    printf("c=%d\n",hc);  
    return 0;  
}
```



- This does not work!!
- `int ha, hb, hc` are in the host memory (DRAM), which cannot be used by device (GPU).
- We need to allocate variables in “device memory”.

# The correct main()

```
int main(void) {  
    int a=1, b=2, c; // host copies of a, b, c  
    int *d_a, *d_b, *d_c; // device copies of a, b, c  
    // Allocate space for device copies of a, b, c  
    cudaMalloc((void **)&d_a, sizeof(int));  
    cudaMalloc((void **)&d_b, sizeof(int));  
    cudaMalloc((void **)&d_c, sizeof(int));  
    // Copy inputs to device  
    cudaMemcpy(d_a, &a, sizeof(int), cudaMemcpyHostToDevice);  
    cudaMemcpy(d_b, &b, sizeof(int), cudaMemcpyHostToDevice);  
    // Launch add() kernel on GPU  
    add<<<1,1>>>(d_a, d_b, d_c);  
    // Copy result back to host  
    cudaMemcpy(&c, d_c, size, cudaMemcpyDeviceToHost);  
    // Cleanup  
    cudaFree(d_a); cudaFree(d_b); cudaFree(d_c);  
    return 0;  
}
```

# Example 3: add 2 vectors

## ■ Let's first look at the sequential code!

```
// function definition
void VecAdd(int N, float* A, float* B, float* C)
{
    for(int i = 0; i<N; i++)
        C[i] = A[i] + B[i];
}

int main()
{ ...
    VecAdd (N, Ah, Bh, Ch);
    ...
}
```

# Parallel CUDA code

- Use `blockIdx.x` as the index of the arrays
  - Each thread processes 1 addition, for the elements indexed at `blockIdx.x`.

```
// Kernel definition
__global__ void VecAdd(float* A, float* B, float* C)
{
    int i = threadIdx.x;
    C[i] = A[i] + B[i];
}

int main()
{ ...
    // Kernel invocation with N threads
    VecAdd<<<1, N>>>(Ah, Bh, Ch); ...
}
```

# Alternative implementation

- Using parallel thread instead

```
__global__ void add(int *a, int *b, int *c) {  
    c[blockIdx.x] = a[blockIdx.x] + b[blockIdx.x];  
}  
  
int main(void) {  
    int a[N], b[N], c[N];  
    int *d_a, *d_b, *d_c;  
    ...  
    add<<< N, 1 >>>(d_a, d_b, d_c);  
    ...  
}
```

- **N blocks and each block has 1 thread.**

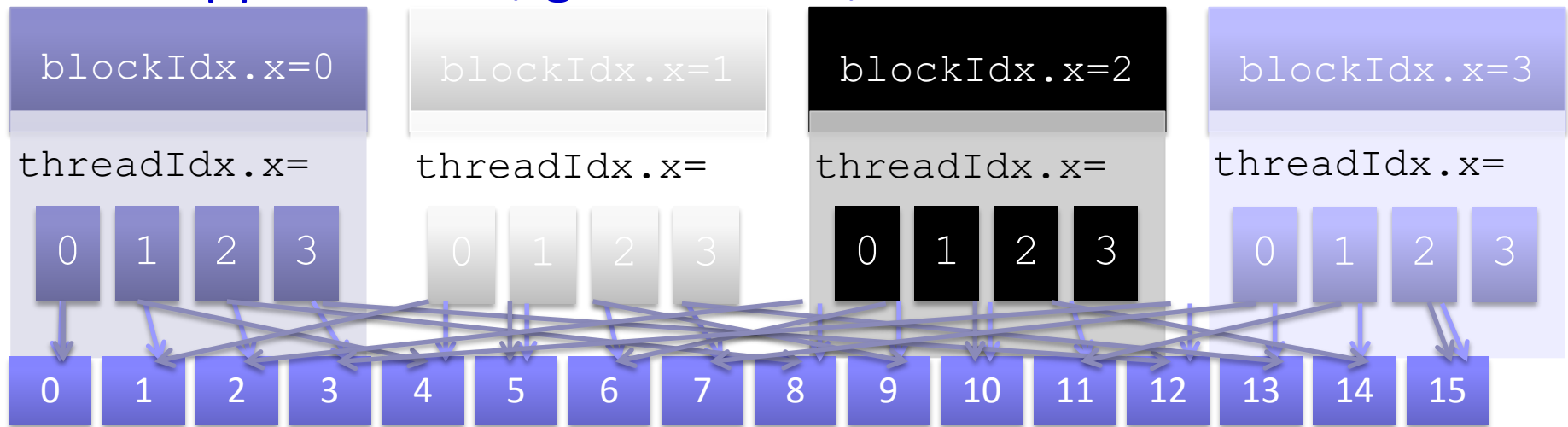
- Which one is better?

- Threads in the same block can **communicate, synchronize** with others, but the number of threads per block is limited.



# 3rd implementation

- Using multiple threads and multiple blocks
- Suppose  $N=16$ , grid size = 4, and block size = 4

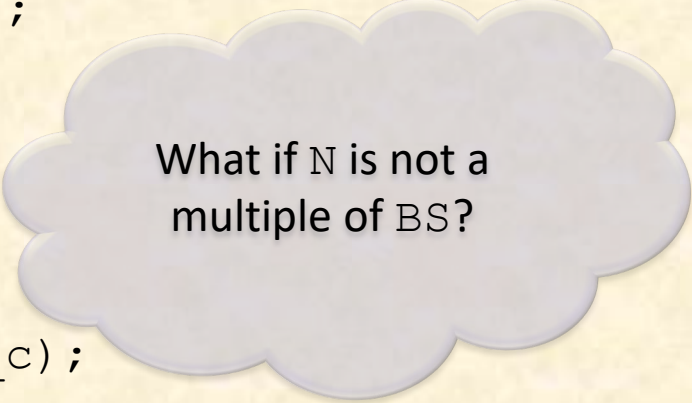


- How to index 16 elements of an array?
  - Method 1:  $\text{index} = \text{blockIdx.x} * 4 + \text{threadIdx.x}$
  - Method 2:  $\text{index} = \text{threadIdx.x} * 4 + \text{blockIdx.x}$
- Which one is better?

# The general case

- Use the built-in variable `blockDim.x` for threads per block.

```
__global__ void add(int *a, int *b, int *c) {  
    int index = threadIdx.x + blockIdx.x * blockDim.x;  
    c[index] = a[index] + b[index];  
}  
  
int main(void) {  
    int a[N], b[N], c[N];  
    int *d_a, *d_b, *d_c;  
    ...  
    add<<< N/BS, BS >>>>(d_a, d_b, d_c);  
    ...  
}
```



What if N is not a multiple of BS?

- BS is block size (number of threads per block)

# A even more general case

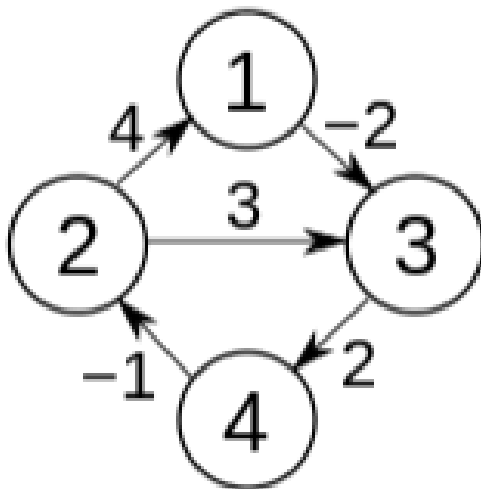
```
__global__ void add(int *a, int *b, int *c, int n) {  
    int index = threadIdx.x + blockIdx.x * blockDim.x;  
    if (index < n)  
        c[index] = a[index] + b[index];  
}  
int main(void) {  
    int a[N], b[N], c[N];  
    int *d_a, *d_b, *d_c;  
    ...  
    add<<< (N+BS-1)/BS, BS>>>(d_a, d_b, d_c, N);  
    ...  
}
```

- The kernel function can have branches, but with a price to pay...

# Example4: APSP

- Given a weighted directed graph  $G(V, E, W)$ , where  $|V| = n$ ,  $|W| = m$ , and  $W > 0$ , find the shortest path of all pairs of vertices  $(v_i, v_j)$ .

- Example:



|     |     |     |     |
|-----|-----|-----|-----|
| 0   | INF | -2  | INF |
| 4   | 0   | 3   | INF |
| INF | INF | 0   | 2   |
| INF | -1  | INF | 0   |

Initial  
weight

|   |    |    |   |
|---|----|----|---|
| 0 | -1 | -2 | 0 |
| 4 | 0  | 2  | 4 |
| 5 | 1  | 0  | 2 |
| 3 | -1 | 1  | 0 |

Final  
result

# Floyd-Warshall (Sequential code)

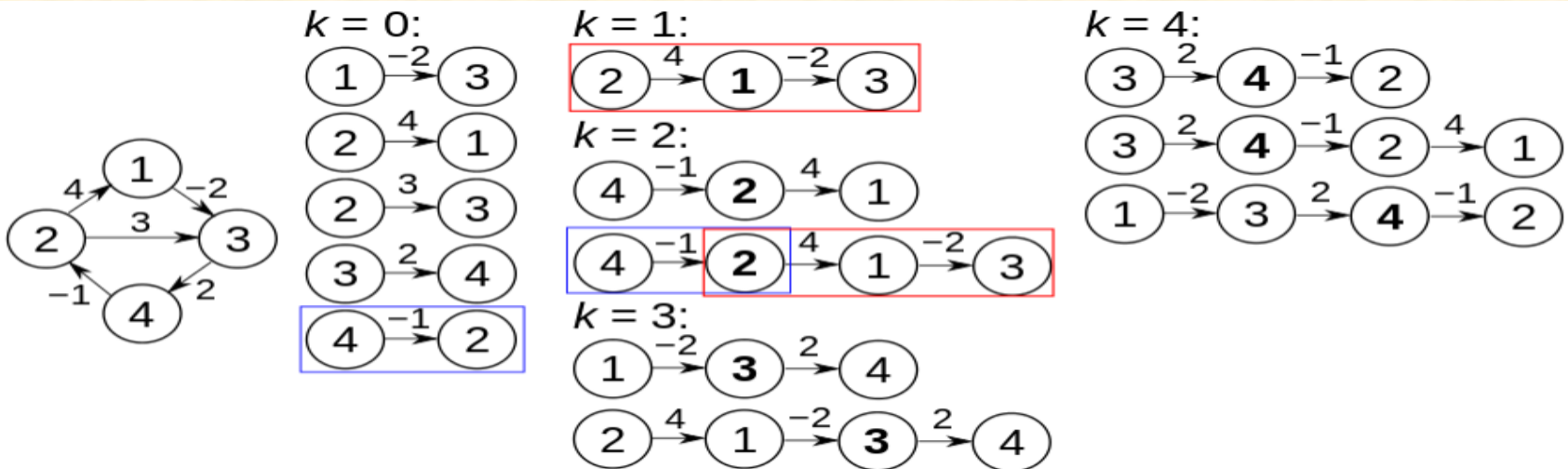
Floyd-Warshall( $G, W$ )

```

{   $n \leftarrow |V|$ 
    $D^{(0)} \leftarrow W$ 
   for  $k = 1$  to  $n$  do
     for  $i = 1$  to  $n$  do
       for  $j = 1$  to  $n$  do
         if  $D^{(k-1)}[i, j] > D^{(k-1)}[i, k] + D^{(k-1)}[k, j]$ 
           then  $D^{(k)}[i, j] \leftarrow D^{(k-1)}[i, k] + D^{(k-1)}[k, j]$ 
         else  $D^{(k)}[i, j] \leftarrow D^{(k-1)}[i, j]$ 
   return  $D^{(n)}$ 
}

```

How to parallelize it?



# Implementation I

- 1 block and  $n$  threads.
- Thread  $i$  updates the SP for vertex  $i$ .

```
__global__ void FW_APSP(int k, int D[n][n]) {  
    int i = threadIdx.x;  
    for (int j = 0; j < n; j++)  
        if (D[i][j] > D[i][k] + D[k][j])  
            D[i][j] = D[i][k] + D[k][j];  
}  
  
int main() { ...  
    for (int k = 0; k < n; k++)  
        FW_APSP<<<1, n>>>(k, D);  
}
```

Simple! But can it be faster ?

# Implementation 2

## ■ Each thread updates one pair of vertices

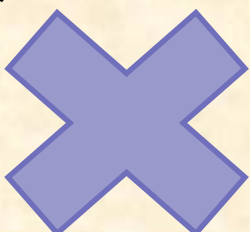
➤ Increase parallelism from  $n$  to  $n^2$

```
__global__ void FW_APSP(int k, int D[n][n]) {  
    int i = threadIdx.x;  
    int j = threadIdx.y;  
    if (D[i][j] > D[i][k] + D[k][j])  
        D[i][j] = D[i][k] + D[k][j];  
}  
  
int main() { ...  
    dim3 threadsPerBlock(n, n);  
    for (int k = 0; k < n; k++)  
        FW_APSP<<<1, threadsPerBlock >>>(k, D);  
}
```

## ■ How about the for-loop of $k$ ?

# Implementation 3

```
__global__ void FW_APSP(int D[n][n]) {  
    int i = threadIdx.x;  
    int j = threadIdx.y;  
    for (int k = 0; k < n, k++)  
        if (D[i][j] > D[i][k] + D[k][j])  
            D[i][j] = D[i][k] + D[k][j];  
}  
int main() { ...  
    dim3 threadsPerBlock(n, n);  
    FW_APSP<<<1, threadsPerBlock >>>(D);  
}
```



- It is a synchronous computation
  - There are data dependency on k...



# Add \_\_syncthreads ()

```
__global__ void FW_APSP(int D[n][n]) {  
    int i = threadIdx.x;  
    int j = threadIdx.y;  
    for (int k = 0; k < n, k++) {  
        if (D[i][j] > D[i][k] + D[k][j])  
            D[i][j] = D[i][k] + D[k][j];  
        __syncthreads();  
    }  
}  
  
int main() { ...  
    dim3 threadsPerBlock(n, n);  
    FW_APSP<<<1, threadsPerBlock>>>(D);  
}
```



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# Asynchronous Functions

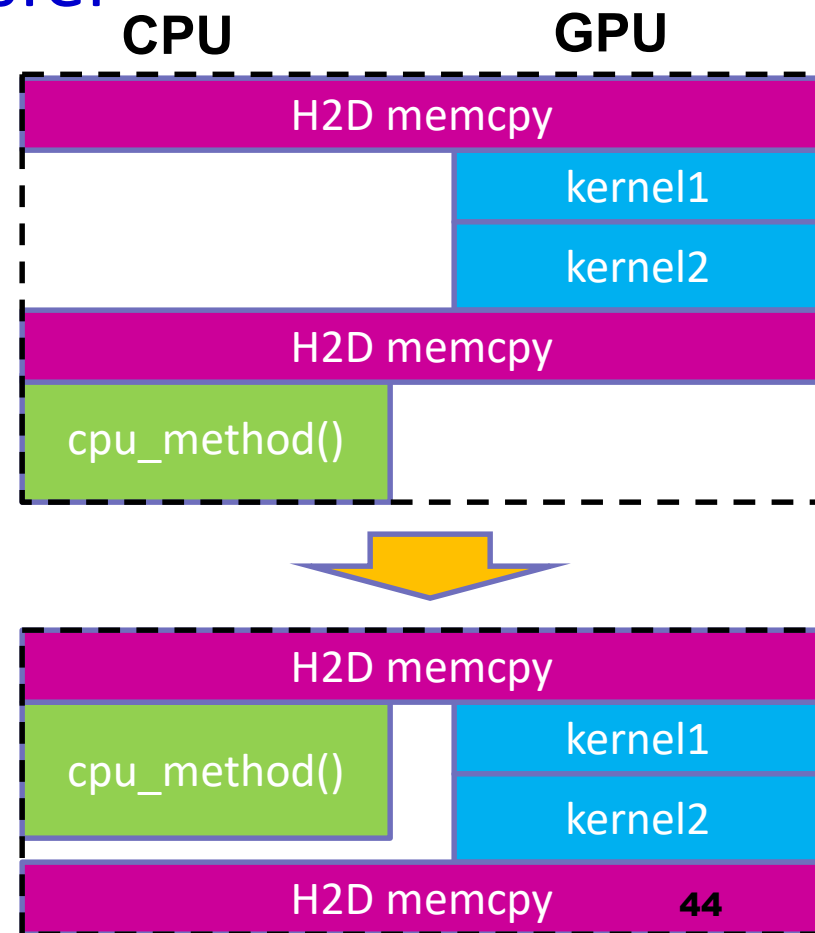
- To facilitate concurrent execution between **host** and **device**, **most CUDA function** calls are **asynchronous**:
  - Control is returned to the host thread before the device has completed the requested task.
  - **But function calls from a kernel are serialized on GPU**
- Asynchronous functions:
  - **Kernel launches**
  - Asynchronous memory copy and set options: **cudaMemcpyAsync, cudaMemcpyAsync**
  - **cudaMemcpy** within the **same device**
  - H2D cudaMemcpy of **64kB or less**
  - **cudaEvent functions**

# Why Use Asynchronous Functions?

- Overlap CPU computation with the GPU computation or data transfer

```
void main() {  
    cudaMemcpy ( /**/, H2D ) ;  
    kernel1 <<< grid, block>>> () ;  
    kernel2 <<< grid, block>>> () ;  
    cudaMemcpy ( /**/, D2H ) ;  
    cpu_method() ;  
}
```


```
void main() {  
    cudaMemcpy ( /**/, H2D ) ;  
    kernel1 <<< grid, block>>> () ;  
    kernel2 <<< grid, block>>> () ;  
    cudaMemcpyAsync ( /**/, D2H ) ;  
    cpu_method() ;  
}
```



# Risk of Using Asynchronous Functions

- Programmer must enforce synchronization between **GPU** and **CPU** when there is **data dependency**

```
void main() {  
    cudaMemcpyAsync ( d_a, h_a, count, H2D ) ;  
    kernel <<< grid, block>>> (d_a) ;  
    cudaMemcpyAsync ( h_a, d_a, count, D2H ) ;  
    cpu_method(h_a);  
}
```

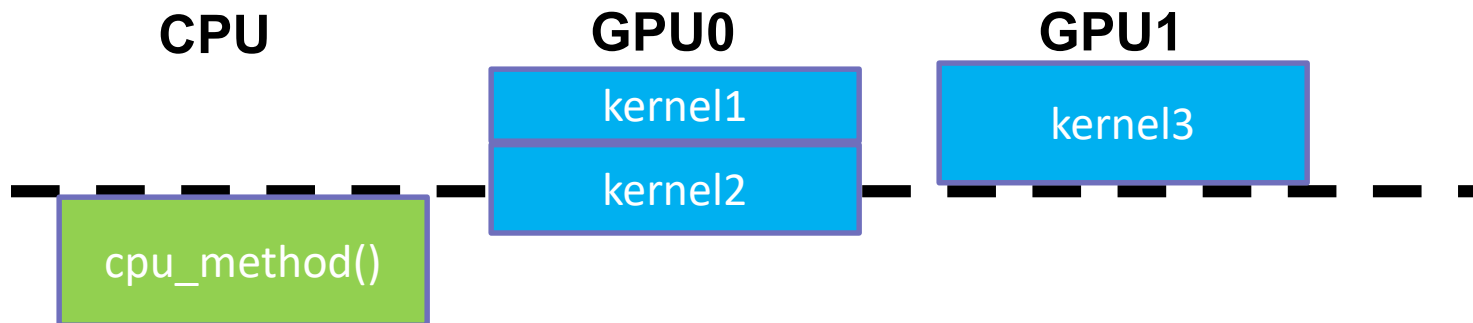


# Synchronization between CPU & GPU

- **Device based:** `cudaDeviceSynchronize()`
  - Block a **CPU thread** until all issued CUDA calls to a **device** complete
- **Context based:** `cudaThreadSynchronize()`
  - Block a **CPU thread** until all issued CUDA calls from the **thread** complete
- **Stream based:** `cudaStreamSynchronize(stream-id)`
  - Block a **CPU thread** until all CUDA calls in stream **stream-id** complete
- **Event based:**
  - `cudaEventSynchronize(event)`
    - ◆ Block a **CPU thread** until **event** is recorded
  - `cudaStreamWaitEvent(stream-id, event)`
    - ◆ Block a **GPU stream** until event reports completion

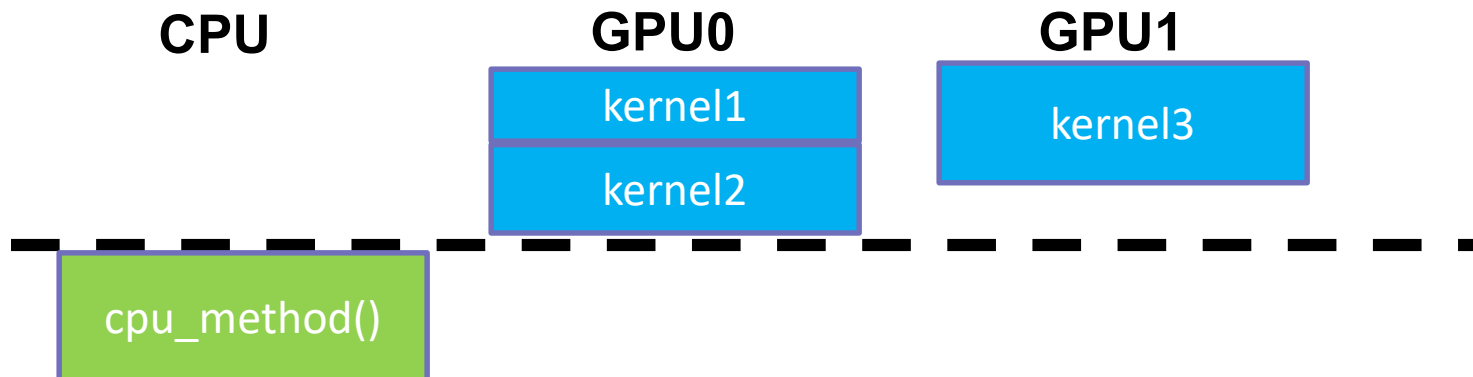
# Device Synchronization Example

```
void main() {  
    cudaSetDevice(0);  
    kernel1 <<< grid, block>>> ();  
    kernel2 <<< grid, block>>> ();  
    cudaSetDevice(1);  
    kernel3 <<< grid, block>>> ();  
    cudaDeviceSynchronize()  
    cpu_method();  
}
```



# Thread Synchronization Example

```
void main() {  
    cudaSetDevice(0);  
    kernel1 <<< grid, block>>> ();  
    kernel2 <<< grid, block>>> ();  
    cudaSetDevice(1);  
    kernel3 <<< grid, block>>> ();  
    cudaThreadSynchronize()  
    cpu_method();  
}
```



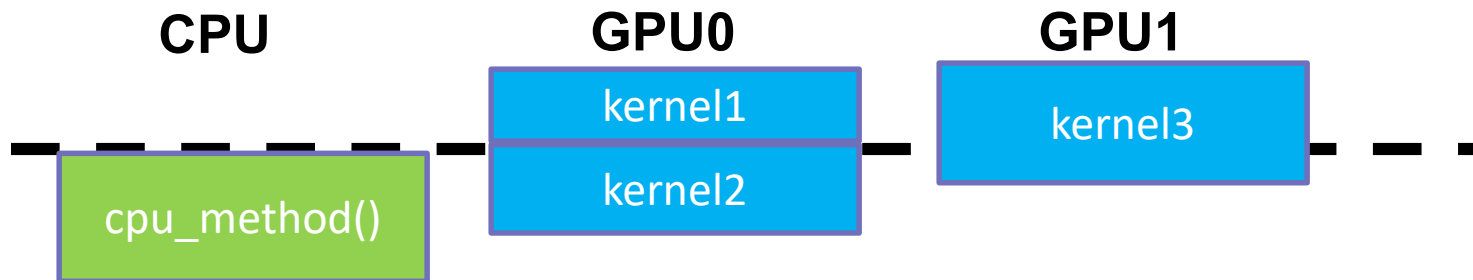


# CUDA event

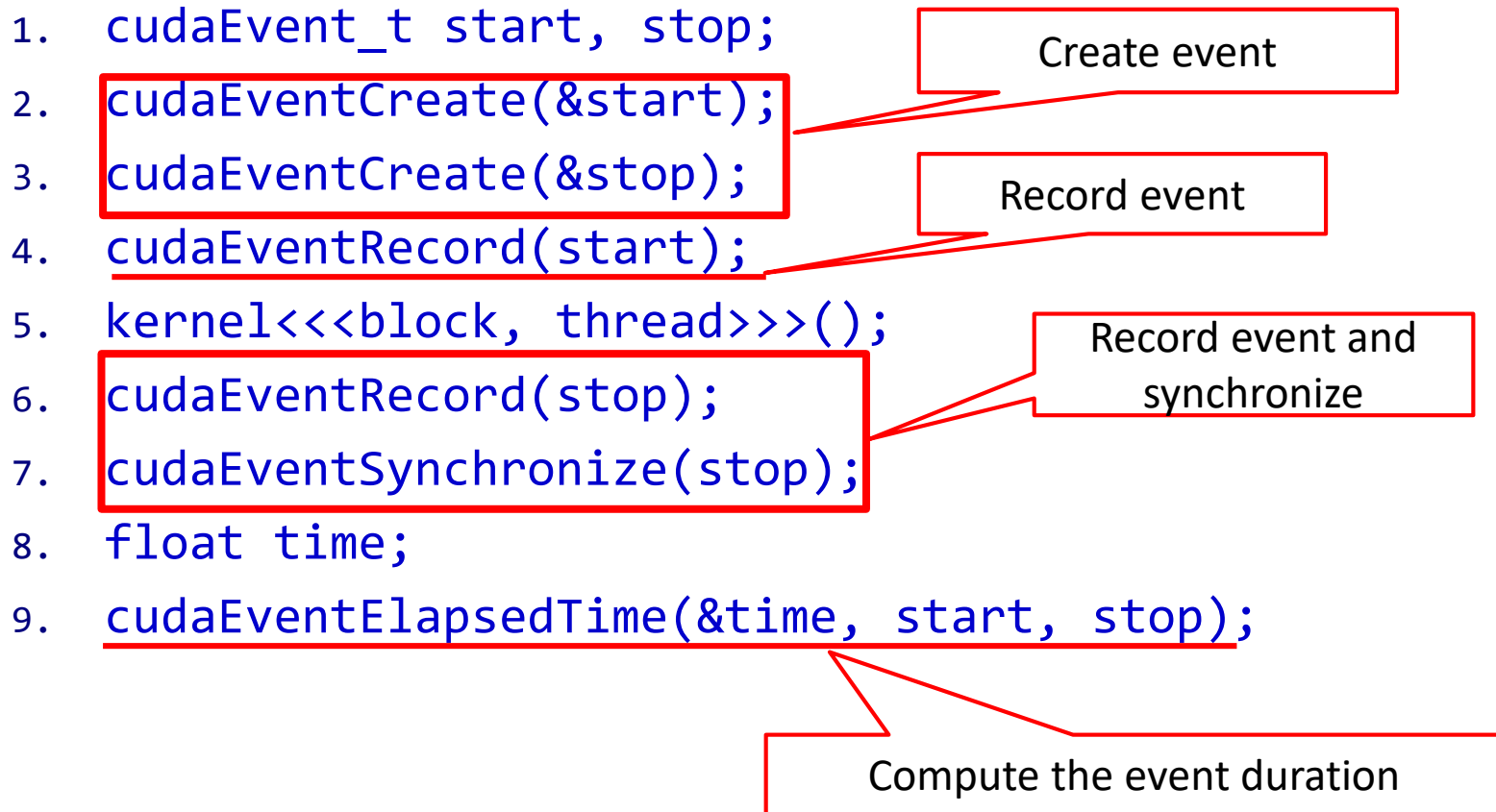
- Data type : `cudaEvent_t`
- `cudaError_t cudaEventCreate(cudaEvent_t* event)`
  - Create CUDA event
- `cudaError_t cudaEventRecord(cudaEvent_t event, cudaStream_t stream = 0)`
  - Record CUDA event
  - If stream is non-zero, the event is recorded after all preceding operations in the stream have been completed
  - Since operation is **asynchronous**, `cudaEventQuery()` and/or `cudaEventSynchronize()` must be used to determine when the event has actually been recorded
- `cudaError_t cudaEventSynchronize(cudaEvent_t event)`
  - Wait until the completion of all device work preceding the most recent call to **`cudaEventRecord()`**

# Event Synchronization Example

```
void main() {  
    cudaSetDevice(0);  
    kernel1 <<< grid, block>>> ();  
    cudaEventRecrod(event)  
    kernel2 <<< grid, block>>> ();  
    cudaSetDevice(1);  
    kernel3 <<< grid, block>>> ();  
    cudaEventSynchronize (event)  
    cpu_method();  
}
```



# Kernel Time Measurement Example





# Outline

- Programming Model
- CUDA Language
- Example Code Study
- CPU & GPU Synchronization
- **Multi-GPU**

# Multi-GPUs

## ■ Multi-GPUs within a node

- A single CPU thread, multiple GPU
- Multiple CPU threads belonging to the **same process**, such as **pthread** or **openMP**

## ■ Multiple GPUs on multiple nodes

- Need to go through network API, such as **MPI**

# Single thread multi-GPUs

- All CUDA calls are issued to the current GPU

- `cudaSetDevice()` sets the current GPU

```
// Run independent kernel on each CUDA device
int numDevs = 0;
cudaGetDeviceCount(&numDevs);
for (int d = 0; d < numDevs; d++) {
    cudaSetDevice(d);
    kernel<<<blocks, threads>>>(args);
}
```

- Asynchronous calls (kernels, memcpy) don't block switching the GPU

```
cudaSetDevice( 0 );
kernel<<<...>>>(...);
cudaSetDevice( 1 );
kernel<<<...>>>(...);
```

# Using CUDA with OpenMP

- Put CUDA functions inside the parallel region
- General setting:
  - The number of CPU threads is the same as the number of CUDA devices. Each CPU thread controls a different device, processing its portion of the data.
- It's possible to use more CPU threads than there are CUDA devices, BUT...
  - Several CPU threads will be allocating resources and launching kernel on the same device, which will slow down the performance.
  - Kernel launched on a single GPU could not operate concurrently (unless using different **stream**)

# Example: cudaOMP.cu

```
...
cudaGetDeviceCount(&num_gpus);
...
omp_set_num_threads(num_gpus);
// create as many CPU threads as there are CUDA devices
#pragma omp parallel
{
    unsigned int cpu_thread_id = omp_get_thread_num();
    unsigned int num_cpu_threads = omp_get_num_threads();
    cudaSetDevice(cpu_thread_id);
    int gpu_id = -1;
    cudaGetDevice(&gpu_id);
    printf("CPU thread %d (of %d) uses CUDA device %d\n",
          cpu_thread_id, num_cpu_threads, gpu_id);
    ...
}
```



# Using CUDA with MPI

```
int main(int argc, char* argv[]) {
    int rank, size;
    int A[32];
    int i;
    MPI_Init(&argc, &argv);
    MPI_Comm_rank(MPI_COMM_WORLD, &rank);
    MPI_Comm_size(MPI_COMM_WORLD, &size);
    printf("I am %d of %d\n", rank, size);
    for(i = 0; i < 32; i++) A[i] = rank+1;
    launch(A); // a call to launch CUDA kernel
    MPI_Barrier(MPI_COMM_WORLD);
    MPI_Finalize();
    return 0;
}
```

# Example: launch (A)

```
extern "C"  
void launch(int *A) {  
    int *dA;  
    cudaMalloc((void**) &dA, sizeof(int) * 32);  
    cudaMemcpy(dA, A, sizeof(int) * 32,  
               cudaMemcpyHostToDevice);  
    kernel<<<1, 32>>>(dA);  
    cudaMemcpy(A, dA, sizeof(int) * 32,  
               cudaMemcpyDeviceToHost);  
    cudaFree(dA);  
}
```

# Sharing data between GPUs

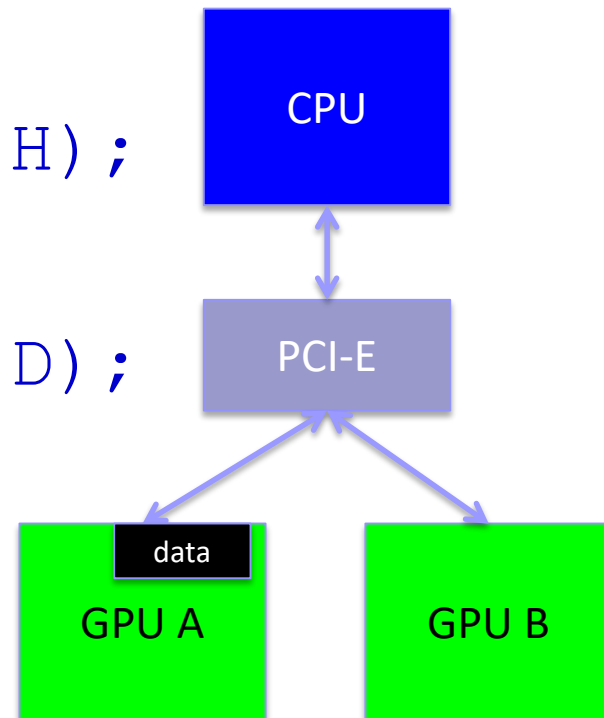
## ■ Options

1. Explicit copies via host
2. Zero-copy shared host array
3. Peer-to-peer memory copy

# 1. Explicit copies via host

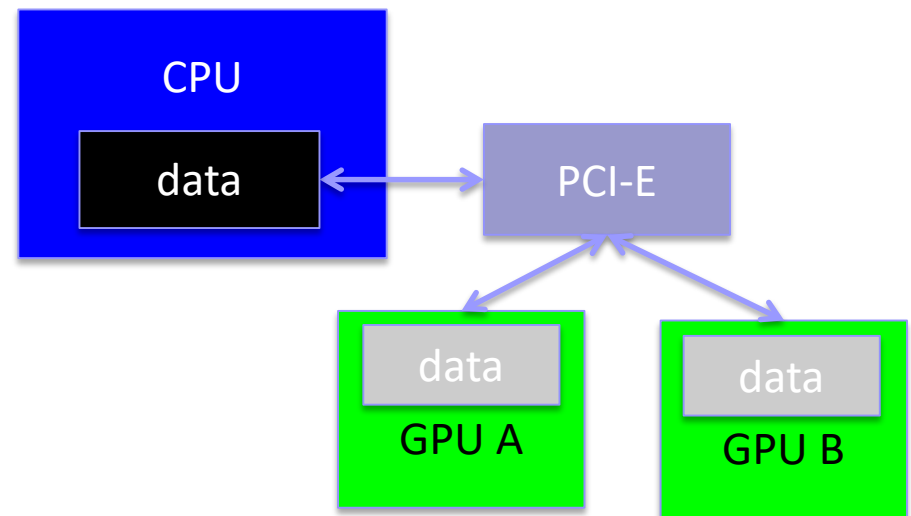
- CPU explicitly copies data from device A to device B
- Example:

```
cudaSetDevice(0);  
cudaMemcpy(DM1, HM, n, D2H);  
cudaSetDevice(1);  
cudaMemcpy(HM, DM2, n, H2D);
```



## 2. Using zero-copy

- “Zero-copy” refers to direct device access to host memory
- Device threads can read directly from host memory over PCI-e without using cudaMemcpy H2D or D2H
- The host memory must be pinned (page-locked)
  - Pageable memory cannot be directly accessed by the GPU because of the OS virtual memory mechanism



# Host Memory Allocation

## ■ `malloc()`

- Regular C library memory allocation
- Managed by host
- Cannot be directly accessed by GPUs
- Must be copied to device memory via `cudaMemcpy()`

## ■ `cudaMallocHost(void ** hostPtr, size_t size)`

- Allocate **pinned** (page-locked) host memory for higher `cudaMemcpy` performance
- Used with `cudaMemAsync()` for **async memory copy** or CUDA stream

## ■ `cudaHostAlloc(void ** hostPtr, size_t size, unsigned int flags)`

- Add the flag ***“cudaHostAllocMapped”*** to allocate **pinned** host memory for higher `cudaMemcpy` performance
- Add the flag ***“cudaHostAllocPortable”*** to allocate **shared** host memory for **“Zero copy”**

➔ **All these functions return host memory pointer**

# Zero Copy via `cudaHostAlloc()`

- Allocate **host memory** using `cudaHostAlloc()`
  - It returns a **host pointer**. It can enable faster host memory access.
  - **Must** add flag `cudaHostAllocMapped` for **page-locked**
  - Add flag `cudaHostAllocPortable` for **sharing among all devices**
- Bind host pointer to device pointer using `cudaHostGetDevicePointer(void**, void*, 0)`

```
int *hostPtr, *dev0Ptr, *dev1Ptr;
cudaHostAlloc(&hostPtr, 10, cudaHostAllocMapped |
cudaHostAllocPortable);
cudaSetDevice(0);
cudaHostGetDevicePointer(&devPtr0, hostPtr, 0);
kernel<<1,10>>(devPtr0);
cudaSetDevice(1);
cudaHostGetDevicePointer(&dev1Ptr, hostPtr, 0);
kernel<<1,10>>(devPtr1);
```

# Pitfalls of using zero-copy

- PCI-e is lower in bandwidth and higher in latency than **GPU global memory**
  - ➔ access speed is slower than global memory
- Use zero-copy if:
  - The data is **only accessed once** or few times
  - Generate data on the device and copy back to host **without reuse**
  - Kernel(s) that access the memory are **compute bound**



### 3. Peer-to-Peer Memcpy

- Direct copy from pointer on GPU A to pointer on GPU B
- Using two functions

```
cudaError_t cudaMemcpyPeer(void *dst, int  
dstDevice, const void* src, int srcDevice,  
size_t count)
```

```
cudaError_t cudaMemcpyPeerAsync(void *dst,  
int dstDevice, const void* src, int  
srcDevice, size_t count, cuda_stream_t  
stream=0)
```

# Example: P2P memcpy

```
cudaSetDevice(0);           //set device 0 as current
float *p0;
size_t size = 1024*sizeof(float);
cudaMalloc(&p0, size); //allocate mem on device 0
cudaSetDevice(1);           //set device 1 as current
float *p1;
cudaMalloc(&p1, size); //allocate mem on device 1

cudaSetDevice(0);           //set device 0 as current
Kernel1<<<1000,128>>>(p0); //launch on dev 0
cudaSetDevice(1);           //set device 1 as current
cudaMemcpyPeer(p1,1,p0,0,size); //copy p0 to p1
Kernel1<<<1000,128>>>(p1); //launch on dev 1
```



# Reference

- [NVIDIA CUDA Library Documentation](#)
- [NVIDIA, Introduction to Dynamic Parallelism](#)
- [NVIDIA, CUDA C++ Best Practices Guide](#)
- [CUDA Tutorial](#)