

Useful Skew Design Flow

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Introduction

First Thing First

Variation Issue

Multi-Corner Issue

Clock-Tree Issue

Adjustable Delay Buffer Issue

Q & A



Introduction



Useful Skew Design: Why vs. Why Not

Why not

- ▶ Need more engineer training.
- ▶ Balanced clock-tree is more difficult to build.
- ▶ Don't know how to handle process variation, multi-corner multi-mode, . . . , etc.

Why

If you do it correctly,

- ▶ spend less time for struggling timing issues.
- ▶ obtain better chip performance or yield.



Clock Arrival Time vs. Clock Skew

- ▶ Clock signal runs periodically.
- ▶ Thus, absolute clock arrival time u_i is not so important.
- ▶ Instead, the skew $y_{ij} = u_i - u_j$ is more important in this scenario.



Useful Skew Design vs. Zero-Skew Design

- ▶ “Critical cycle” instead of “critical path”.
- ▶ “Negative cycle” instead of “negative slack”.
- ▶ If there is a negative cycle, it means that there is no positive slack solution no matter how to schedule.
- ▶ Others are pretty much the same.
- ▶ Same design principle:
 - ▶ Always tackle the most critical one first!



Linear Programming vs. Network Flow Formulation

- ▶ Linear programming formulation
 - ▶ can handle more complex constraints
- ▶ Network flow formulation
 - ▶ usually more efficient
 - ▶ return the most critical cycle as a bonus.
 - ▶ can handle quantized buffer delay (???)
- ▶ Anyway, timing analysis is much more time-consuming than the optimization solving.



Target Skew vs. Actual Skew

Don't mess up these two concepts:

- ▶ Target skew:
 - ▶ the skew we want to achieve in the scheduling stage.
 - ▶ Usually deterministic (we schedule a meeting at 10:00, rather than $10:00 \pm 34$ minutes, right?)
- ▶ Actual skew
 - ▶ the skew that the clock tree actually generates.
 - ▶ Can be formulated as a random variable.



A Simple Case

To warm up, let us start with a simple case:

- ▶ Assume equal path delay variations.
- ▶ Single-corner.
- ▶ Before a clock tree is built.
- ▶ No adjustable delay buffer (ADB).



Network

Definition (Network)

A *network* is a collection of finite-dimensional vector spaces of *nodes* and *edges/arcs*:

- ▶ $V = \{v_1, v_2, \dots, v_N\}$, where $|V| = N$
- ▶ $E = \{e_1, e_2, e_3, \dots, e_M\}$ where $|E| = M$

which satisfies 2 requirements:

1. The boundary of each edge is comprised of the union of nodes
2. The intersection of any edges is either empty or a boundary node of both edges.



Example

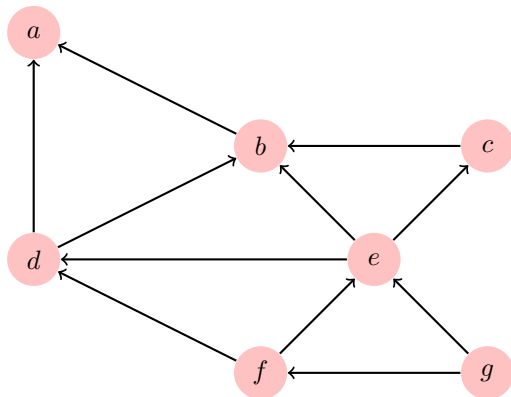


Figure 1: A network

Orientation

Definition (Orientation)

An *orientation* of an edge is an ordering of its boundary node (s, t) , where

- ▶ s is called a source/initial node
- ▶ t is called a target/terminal node

Definition (Coherent)

Two orientations to be the same is called *coherent*



Node-edge Incidence Matrix

Definition (Incidence Matrix)

A $N \times M$ matrix A^T is a node-edge incidence matrix with entries:

$$A(i, j) = \begin{cases} +1 & \text{if } e_i \text{ is coherent with } v_j, \\ -1 & \text{if } e_i \text{ is not coherent with } v_j, \\ 0 & \text{otherwise.} \end{cases}$$

Example (II)

$$A^T = \begin{bmatrix} 0 & -1 & 1 & 1 & 0 \\ 1 & 1 & 0 & -1 & -1 \\ -1 & 0 & -1 & 0 & 1 \end{bmatrix}$$



Timing Constraint

- ▶ Setup time constraint

$$y_{\text{skew}}(i, f) \leq T_{\text{CP}} - D_{if} - T_{\text{setup}} = u_{if}$$

While this constraint destroyed, cycle time violation (zero clocking) occurs.

- ▶ Hold time constraint

$$y_{\text{skew}}(i, f) \geq T_{\text{hold}} - d_{if} = l_{if}$$

While this constraint destroyed, race condition (double clocking) occurs.



Timing Constraint Graph

- ▶ Create a graph (network) by
 - ▶ replacing the hold time constraint with an *h-edge* with cost $-(T_{\text{hold}} - d_{ij})$ from FF_i to FF_j , and
 - ▶ replacing the setup time constraint with an *s-edge* with cost $T_{\text{CP}} - D_{ij} - T_{\text{setup}}$ from FF_j to FF_i .
- ▶ Two sets of constraints stemming from clock skew definition:
 - ▶ The sum of skews for paths having the same starting and ending flip-flop to be the same;
 - ▶ The sum of clock skews of all cycles to be zero



Timing Constraint Graph (TCG)

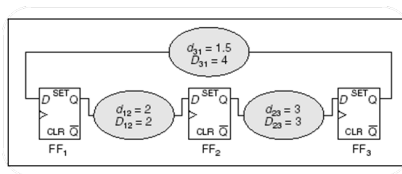
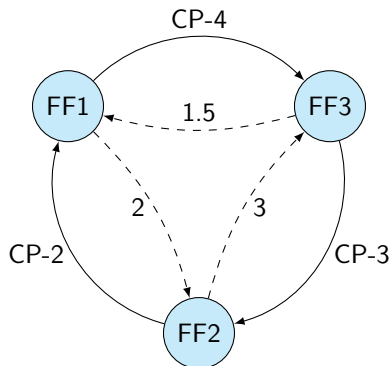


Figure 2: Example circuit



First Thing First



Meet all timing constraints

- ▶ Find y in $\{y \in \mathbb{R}^n \mid y \leq d, Au = y\}$
- ▶ How to solve:
 1. Find a negative cycle, fix it.
 2. Iterate until no negative cycle is found.
- ▶ Bellman-Ford-like algorithm (and its variants are publicly available):
 - ▶ Strongly suggest “Lazy Evaluation”:
 - ▶ Don't do full timing analysis on the whole timing graph at the beginning!
 - ▶ Instead, perform timing analysis only when the algorithm needs.
 - ▶ Stop immediately whenever a negative cycle is detected.



Delay Padding (DP)

- ▶ Delay padding is a technique that fixes the timing issue by intentionally **solely** “increasing” delays.
- ▶ Usually formulated as:
 - ▶ Find p, y in $\{p, y \in \mathbb{R}^n \mid y \leq d + p, Au = y, p \geq 0\}$
- ▶ If the objective is to minimize the sum of p , then the problem is the dual of the standard *min-cost flow* problem, which can be solved efficiently by the *network simplex* algorithm (publicly available).
- ▶ Beautiful right?



Delay Padding (II)

- ▶ No, the above formulation is not practical.
- ▶ In modern design, “inserting” a delay may mean swapping a faster cell with a slower cell from the cell library. Thus, no need to minimize the sum of p .
- ▶ More importantly, it may not be possible to find a position to insert delay for some delay paths.
- ▶ Some papers consider only allowing insert delays to the max-delay path only. Some papers consider only allowing insert delays to both the max- and min-delay paths together only. None of them are perfect.

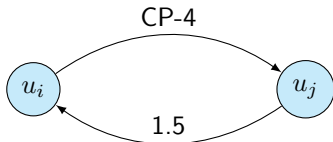


Delay Padding (III)

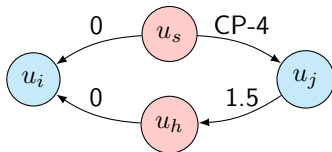
- ▶ My suggestion. Instead of calculating the necessary p' 's and then look for the suitable position to insert, it is easier (and more flexible) to determine the position first and then calculate the suitable values.
- ▶ It can be achieved by modifying the timing graph and solve a feasibility problem. Easy enough!
- ▶ Quantized delay can be handled too (???).



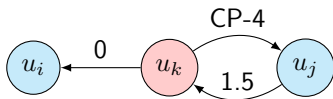
Four possible ways to insert delay



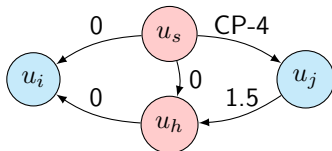
(a) No delay can be inserted



(b) p_s, p_h independently



(c) $p_s = p_h$



(d) $p_s \geq p_h$

Figure 3:

Delay Padding (cont'd)

- ▶ If there exists a negative cycle in the modified timing graph, it implies that the timing problem cannot be fixed by simply the delay padding technique.
 - ▶ Then, try decrease D_{ij} , or increase T_{CP}
- ▶ Be aware of the min-delay path is still the min-delay path after a certain amount of delay is inserted (how???)



Variation Issue



Yield-driven Clock Skew Scheduling

- ▶ Assume all timing issues are fixed.
- ▶ Now, how to schedule the arrival times to maximize yield?
- ▶ According to the critical-first principle, we seek for the most critical cycle first.
- ▶ The problem can be formulated as:
 - ▶ $\max\{\beta \in \mathbb{R} \mid y \leq d - \beta, Au = y\}.$
- ▶ It is equivalent to the *minimum mean cycle* problem, which can be solved efficiently by for example *Howard's algorithm* (publicly available).



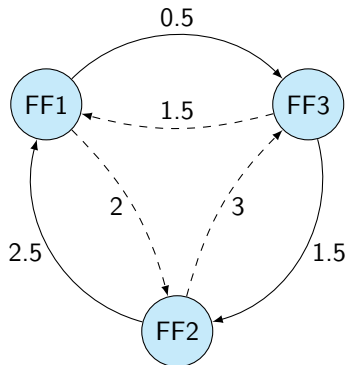
Minimum Balancing Algorithm

- ▶ Then we evenly distribute the slack on this cycle.
- ▶ To continue the next most critical cycle, we contract the first one into a “super vertex” and repeat the process.
- ▶ The process stops when the timing graph remains only a single vertex.
- ▶ The overall method is known as *minimum balancing* (MB) algorithm in the literature.



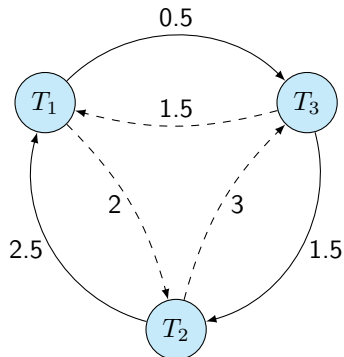
Example: Most timing-critical cycle

The most vulnerable timing constraint



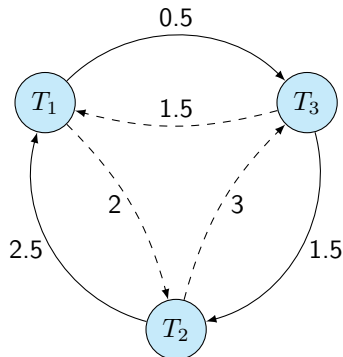
Example: Distribute the slack

- Distribute the slack evenly along the most timing-critical cycle.



Example: Distribute the slack

- Distribute the slack evenly along the most timing-critical cycle.



$$-1.5 \leq T_3 - T_1 \leq 0.5$$



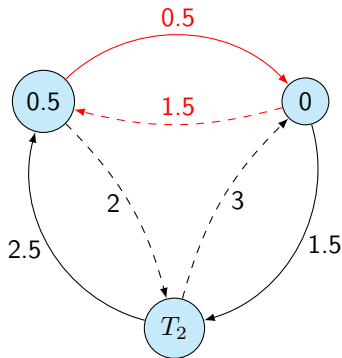
$$T_3 - T_1 = -0.5 \text{ evenly}$$



$$T_3 = 0$$
$$T_1 = 0.5 \quad T_3 = 0$$

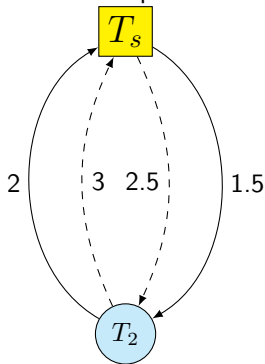
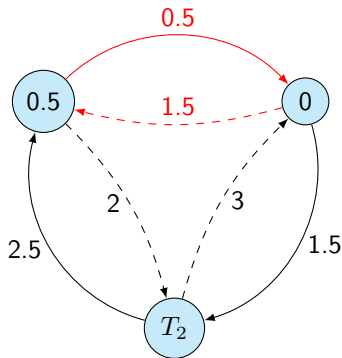
Example: Distribute the slack (cont'd)

- To determine the optimal slacks and skews for the rest of the graph, we replace the critical cycle with a super vertex.



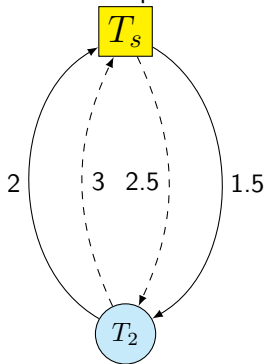
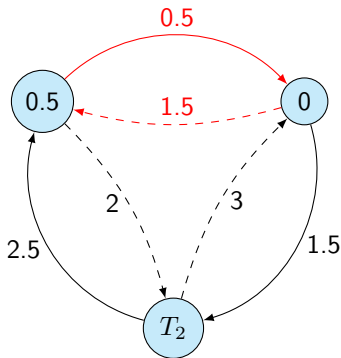
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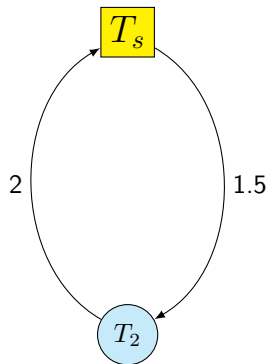
Example: Distribute the slack (cont'd)

- To determine the optimal slacks and skews for the rest of the graph, we replace the critical cycle with a super vertex.

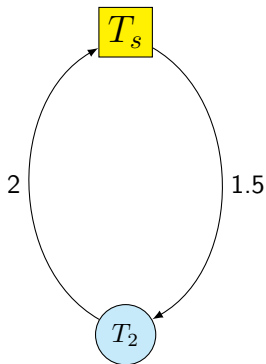


$$\begin{aligned} T_1 - T_2 &\leq 2.5 \\ T_2 - T_1 &\leq 2 \\ \downarrow \\ (0.5 + T_s) - T_2 &\leq 2.5 \\ T_2 - (0.5 + T_s) &\leq 2 \\ \downarrow \\ T_s - T_2 &\leq 2 \\ T_2 - T_s &\leq 2.5 \end{aligned}$$

Repeat the process iteratively



Repeat the process iteratively



$$-2 \leq T_2 - T_s \leq 1.5$$



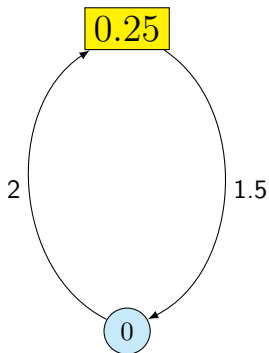
$$T_2 - T_s = -0.25 \quad \text{evenly}$$



$$T_2 = 0$$

$$T_2 = 0 \quad T_s = 0.25$$

Repeat the process iteratively (II)



$$-2 \leq T_2 - T_s \leq 1.5$$



$$T_2 - T_s = -0.25 \quad \text{evenly}$$

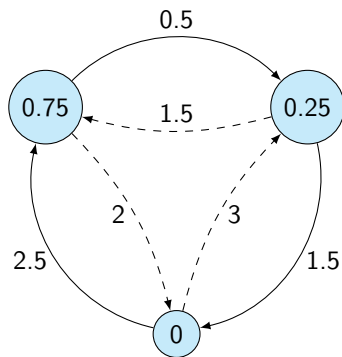


$$T_2 = 0$$

$$T_2 = 0 \quad T_s = 0.25$$

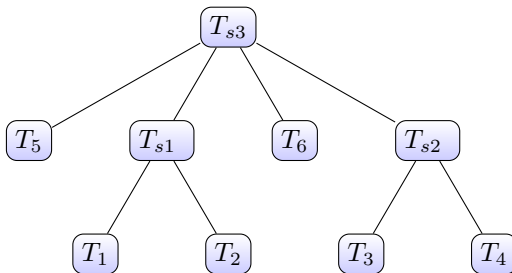
Final result

- ▶ $\text{Skew}_{12} = 0.75$
 - ▶ $\text{Skew}_{23} = -0.25$
 - ▶ $\text{Skew}_{31} = -0.5$
 - ▶ $\text{Slack}_{12} = 1.75$
 - ▶ $\text{Slack}_{23} = 1.75$
 - ▶ $\text{Slack}_{31} = 1$
- where $\text{Slack}_{ij} = \text{CP} - D_{ij} - T_{\text{setup}} - \text{Skew}_{ij}$



What the MB algorithm really give us?

- The MB algorithm not only give us the scheduling solution, but also a tree-topology that represents the order of “criticality”!



Clock-tree Synthesis and Placement

- ▶ I strongly suggest that the topology of the clock-tree precisely follows the order of “criticality”!
 - ▶ since the lower branch of clock-tree has smaller skew variation.
- ▶ I also suggest that the placer should follow the topology of the clock-tree:
 - ▶ Physically place the registers of the same branch together.
 - ▶ The locality implies stronger correlation of variations and implies even smaller skew variation due to the cancellation effect.
 - ▶ Note that the current SSTA does not provide the correlation information, so this is the best you can do!



Second Example: Yield-driven Clock Skew Scheduling

- ▶ Now assume that SSTA (or STA+OCV, POCV, AOCV) is performed.
- ▶ Let (\bar{d}, s) be the (mean, variance) of \mathbf{d}
- ▶ The most critical cycle can be obtained by solving:
 - ▶ $\max\{\beta \in \mathbb{R} \mid y \leq \bar{d} - \beta s, Au = y\}$
- ▶ It is equivalent to the minimum cost-to-time ratio cycle problem, which can be solved efficiently by for example Howard's algorithm (publicly available).
- ▶ Gaussian distribution is assumed. For arbitrary distribution, see my DAC'08 paper.



What About the Correlation?

- ▶ In the above formulation, we minimum the maximum possibility of timing violation of each *individual* timing constraint. So only individual delay distribution is needed.
- ▶ Yes, the objective function is not the true timing-yield. But it is reasonable, easy to solve, and is the best you can do so far.



Multi-Corner Issue



Meet all timing constraints in Multi-Corner

- ▶ Assume no Adjustable Delay Buffer (ADB)
- ▶ Find y in $\{y \in \mathbb{R}^n \mid y \leq d^{(k)}, Au = y, \forall k \in [1..K]\}$
- ▶ Equivalent to finding y in $\{y \in \mathbb{R}^n \mid y \leq \min_k \{d^{(k)}\}, Au = y\}$
- ▶ Feasibility problem
- ▶ How to solve:
 1. Find a negative cycle, fix it.
 2. Iterate until no negative cycle is found.
- ▶ Better avoid fixing the timing issue corner-by-corner. Inducing ping-pong effect.



Delay padding (DP) in Multi-Corner

- ▶ The problem CANNOT be formulated as a network flow problem. But still you can solve it by a linear programming formulation.
- ▶ Or, decompose the problem into subproblems for each corner.
- ▶ Again use the modified timing graph technique.
- ▶ Then, y 's are shared variables of subproblems.
- ▶ If we solve each subproblem individually, the solution will not agree with each other. Induce *ping-pong effect*.
- ▶ Need something to drive the agreement.



Delay Padding (DP) in Multi-Corner (cont'd)

- ▶ Follow the idea of *dual decomposition*: If a solution is above the average, then introduce a punishment cost. If a solution is below the average, then introduce a rewarding cost.
- ▶ Then, each subproblem is a min-cost potential problem, which can be solved efficiently.
- ▶ If some subproblems do not have feasible solutions, it implies that the problem cannot be fixed by simply delay padding.
- ▶ The process repeats until all solutions converge. If not, it implies that the problem cannot be fixed by simply delay padding.



Yield-driven Clock Skew Scheduling

- ▶ $\max\{\beta \in \mathbb{R} \mid y \leq d^{(k)} - \beta s, Au = y, \forall k \in [1..K]\}$
- ▶ More or less the same as in Single Corner.



Clock-Tree Issue



Clock Tree Synthesis (CTS)

- ▶ Construct merging location
 - ▶ DME algorithm, Elmore delay, buffer insertion
- ▶ Some research on *bounded-skew DME algorithm*. But the algorithm is too complicated in my opinion.
- ▶ If the previous stage is over-optimized, the clock tree is hard to implement. If it happens, some budgeting techniques should be invoked (engineering issue)
- ▶ After a clock tree is constructed, more accurate timing (rather than Elmore delay) can be obtained via timing analysis.



Co-optimization Issue

- ▶ After a clock tree is built, we have a clearer picture.
- ▶ Should I perform the re-scheduling? And how?
- ▶ Some papers suggest adding a factor to the timing constraint, say:

$$1.2u_i - 0.8u_j \leq w_{ij}$$

- ▶ Then the formulation is not a kind of network-flow, but may still be solvable by linear programming.
- ▶ Need to investigate more deeply.



Adjustable Delay Buffer Issue



Adjustable delay buffers in Multi-Mode

- ▶ Assume adjustable delay buffers are added solely to the clock tree
- ▶ Hence, each mode can have a different set of arrival times.
- ▶ Easier for clock skew scheduling, harder for clock-tree synthesis.



Meet timing constraint in Multi-Mode:

- ▶ find $y^{(m)}$ in $\{y^{(m)} \in \mathbb{R}^n \mid y^{(m)} \leq d^{(m)}, A u^{(m)} = y^{(m)}, \forall m \in [1..M]\}$
- ▶ Can be done in parallel.
- ▶ find a negative cycle, fix it (do not need to know all $d_i^{(m)}$ at the beginning) for every mode in parallel.



Delay Padding (DP) in Multi-mode

- ▶ Again use a modified timing graph technique.
- ▶ NOT a network flow problem. Use LP, or
- ▶ Dual decomposition \rightarrow min-cost potential problem for each mode
 - ▶ Only p 's are shared variables.
 - ▶ Initial feasible solution obtained by the single-mode method
 - ▶ A negative cycle \Rightarrow problem cannot be fixed by DP
- ▶ Not converge \Rightarrow problem cannot be fixed by DP
 - ▶ Try decrease D_{ij} , or increase T_{CP}



Yield-driven Clock Skew Scheduling

- ▶ $\max\{\beta \in \mathbb{R} \mid y^{(m)} \leq d^{(m)} - \beta s, A u^{(m)} = y^{(m)}, \forall m \in [1..M]\}$
- ▶ Pretty much the same as Single-Mode.



Difficulty in ADB Multi-Mode Design

- ▶ How to design the clock-tree?
- ▶ What is the order of criticality?
- ▶ How to determine the minimum range of ADB?



Q & A



Backup

```
pandoc -s -t beamer --toc useful_skew.md beamer.yaml \  
-o useful_skew.pdf
```

