Computer Architecture

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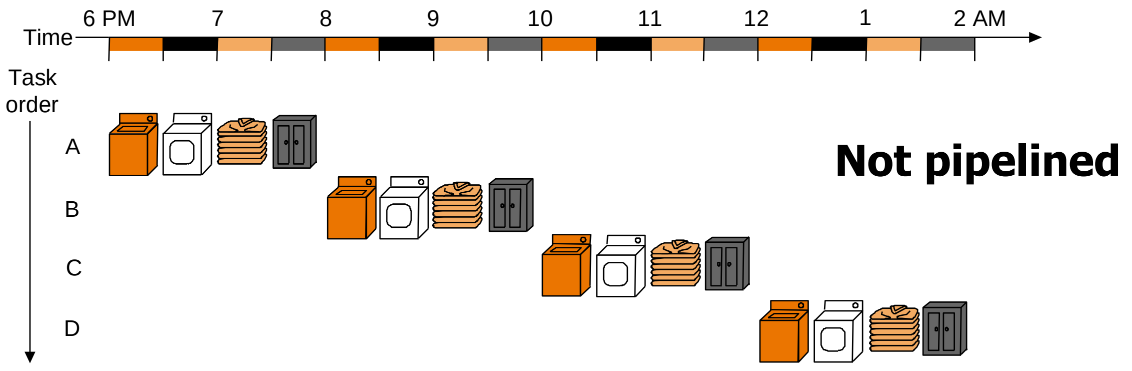
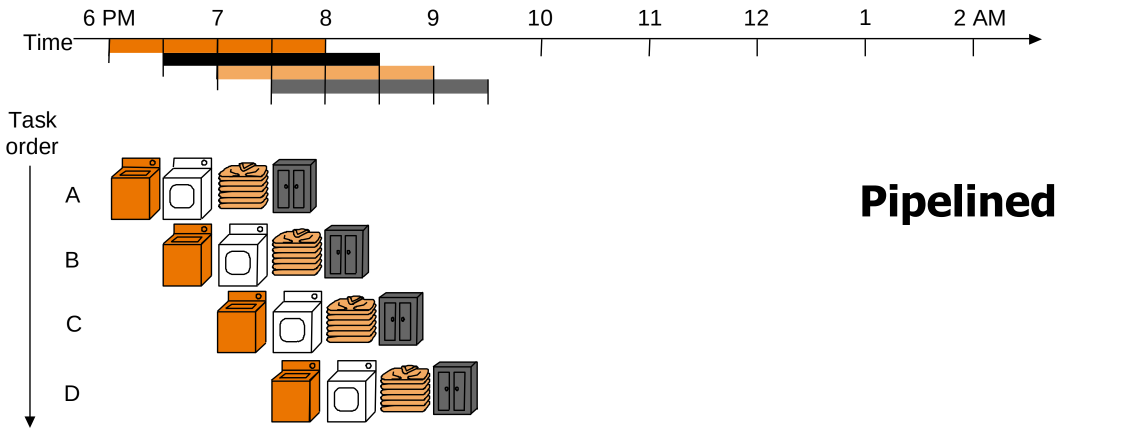
Enhancing Performance with Pipelining

Pipelining

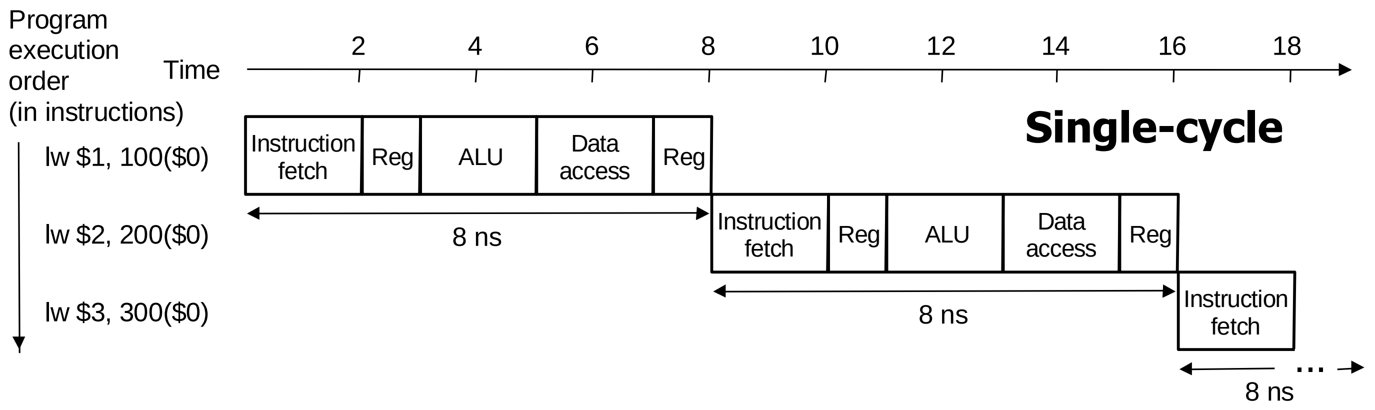
- Start work ASAP!! Do not waste time!



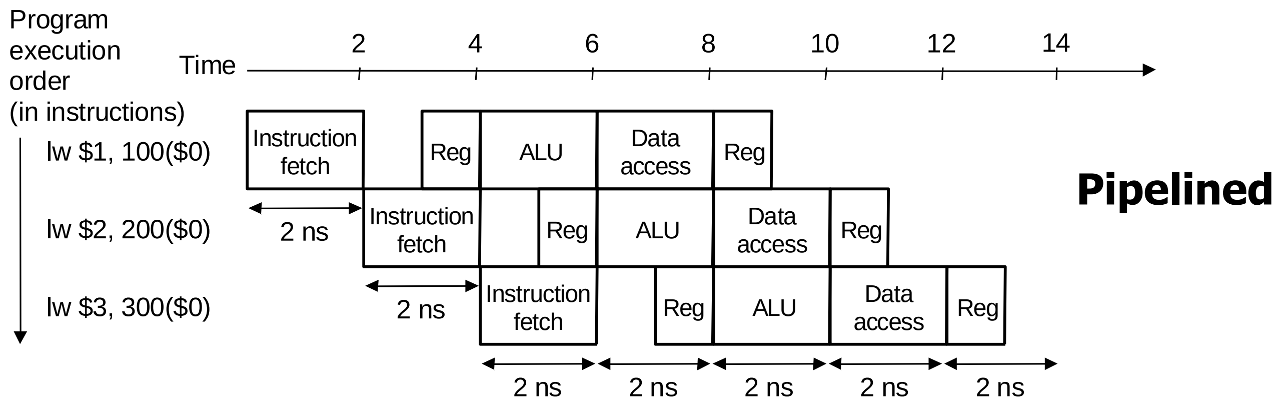
Assume 30 min. each task – wash, dry, fold, store – and that separate tasks use separate hardware and so can be overlapped



Pipelined vs. Single-Cycle Instruction Execution: the Plan



Assume 2 ns for memory access, ALU operation; 1 ns for register access: therefore, single cycle clock 8 ns; pipelined clock cycle 2 ns.



Pipelining: Keep in Mind

- Pipelining *does not reduce latency* of a single task, it *increases throughput* of entire workload
- Pipeline rate *limited by longest stage*
  - *potential* speedup = number pipe stages
  - *unbalanced lengths* of pipe stages reduces speedup
- Time to *fill* pipeline and time to *drain* it – when there is *slack* in the pipeline – reduces speedup

Example Problem

- *Problem: for the laundry fill in the following table when*
  1. *the stage lengths are 30, 30, 30 30 min., resp.*
  2. *the stage lengths are 20, 20, 60, 20 min., resp.*

Person	Unpipelined finish time	Pipeline 1 finish time	Ratio unpipelined to pipeline 1	Pipeline 2 finish time	Ratio unpiplelined to pipeline 2
1					
2					
3					
4					
n					

- *Come up with a formula for pipeline speed-up!*

Pipelining MIPS

- What makes it easy with MIPS?
  - all *instructions are same length*
    - so fetch and decode stages are similar for all instructions
  - just a *few instruction formats*
    - simplifies instruction decode and makes it possible in one stage
  - *memory operands appear only in load/stores*
    - so memory access can be deferred to exactly one later stage
  - *operands are aligned in memory*
    - one data transfer instruction requires one memory access stage

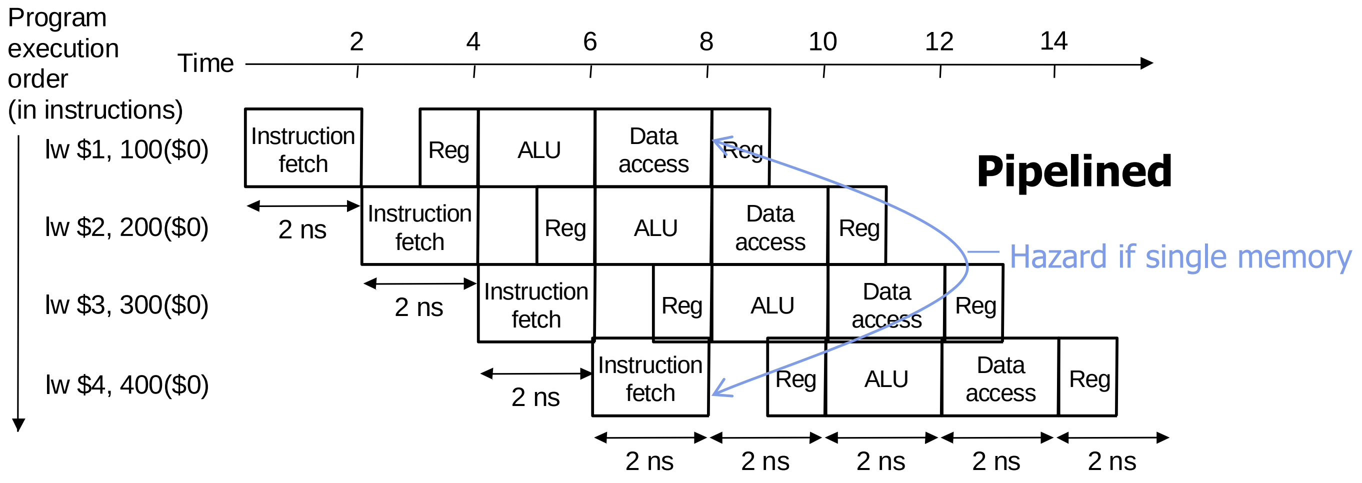
Pipelining MIPS

- What makes it hard?
  - *structural hazards*: different instructions, at different stages, in the pipeline want to use the same hardware resource
  - *control hazards*: succeeding instruction, to put into pipeline, depends on the outcome of a previous branch instruction, already in pipeline
  - *data hazards*: an instruction in the pipeline requires data to be computed by a previous instruction still in the pipeline

- Before actually building the pipelined datapath and control we first briefly examine these potential hazards individually…

Structural Hazards

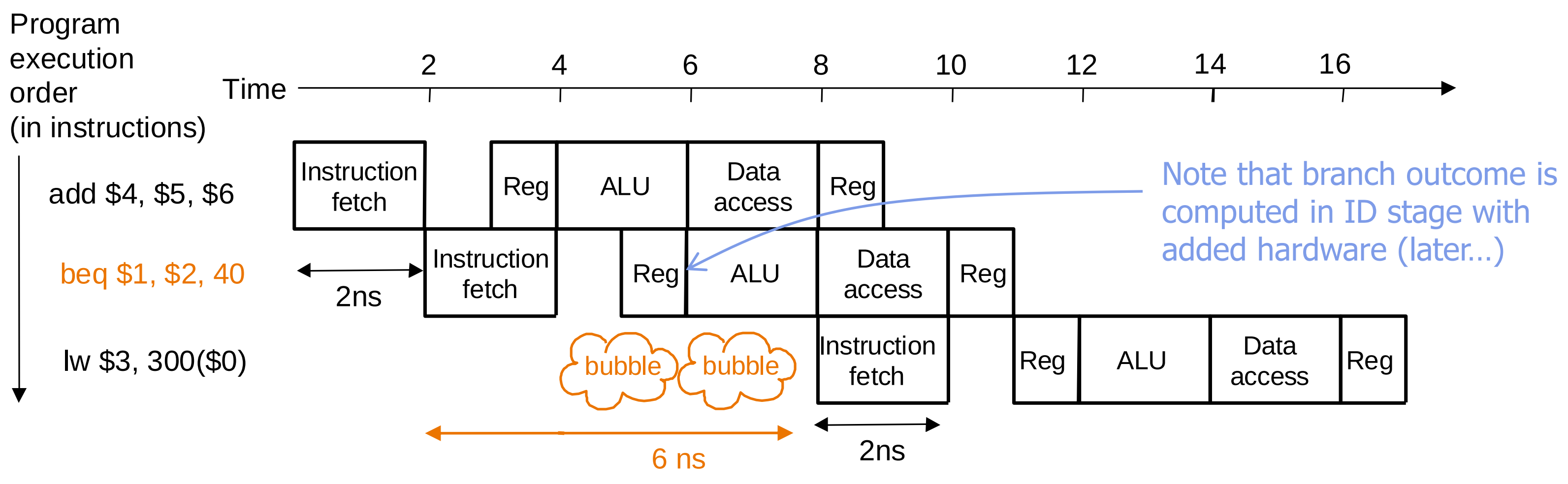
- *Structural hazard*: inadequate hardware to simultaneously support all instructions in the pipeline in the same clock cycle
- E.g., suppose *single – not separate* – instruction and data memory in pipeline below with *one read port*
  - then a structural hazard between first and fourth `lw` instructions



- *MIPS was designed to be pipelined*: structural hazards are easy to avoid!

Control Hazards

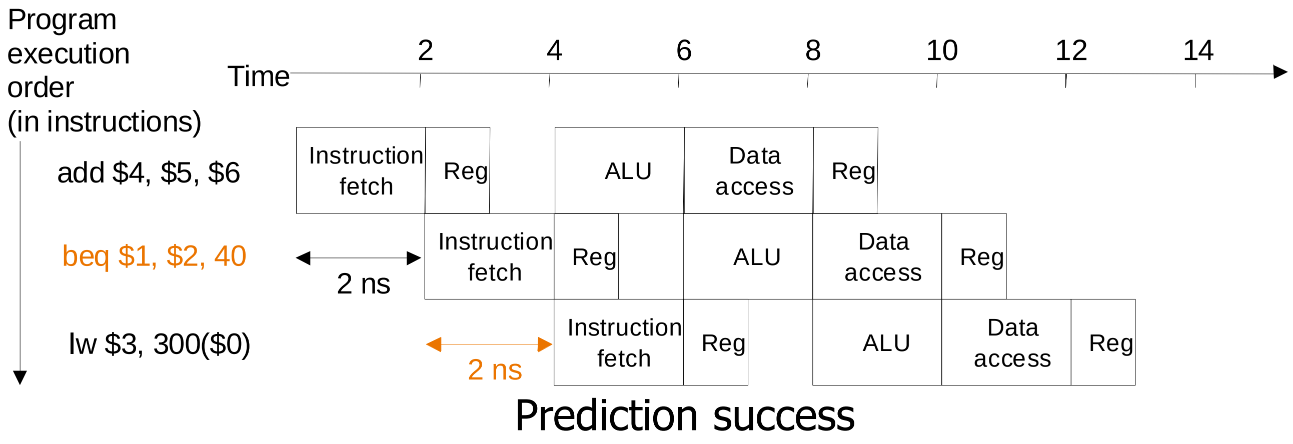
- *Control hazard*: need to make a decision based on the result of a previous instruction still executing in pipeline
- <u>Solution 1</u> *Stall* the pipeline


Program execution order (in instructions)
Time
2
4
6
8
10
12
14
16
add $4, $5, $6
beq $1, $2, 40
lw $3, 300($0)
Instruction fetch
Reg
ALU
Data access
Reg
2ns
bubble
bubble
6 ns
2ns
Note that branch outcome is computed in ID stage with added hardware (later…)

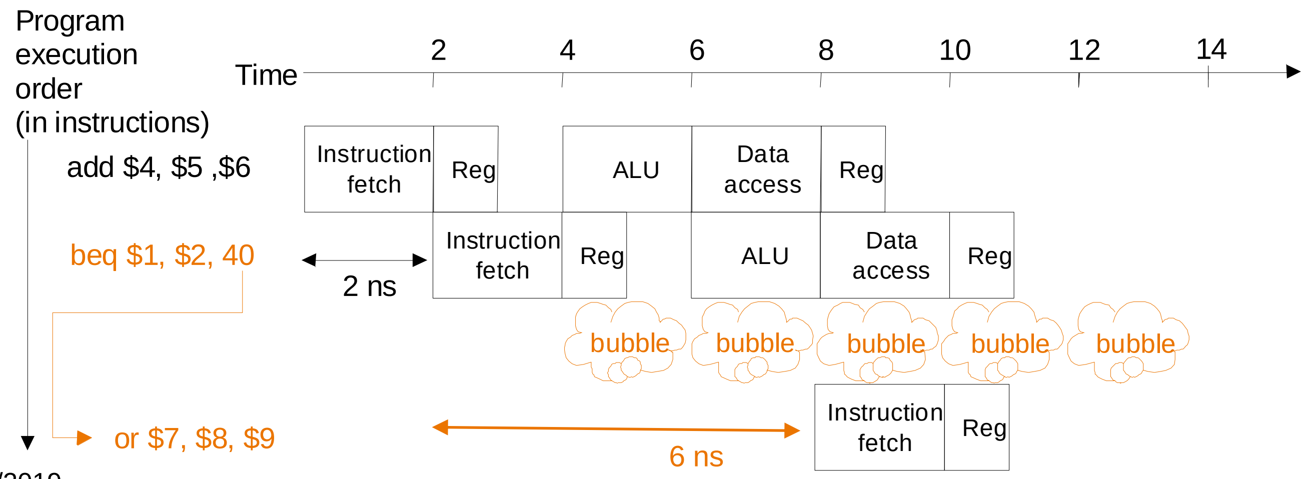
Pipeline stall

Control Hazards

- <u>Solution 2</u> *Predict* branch outcome
  - e.g., predict *branch-not-taken* :



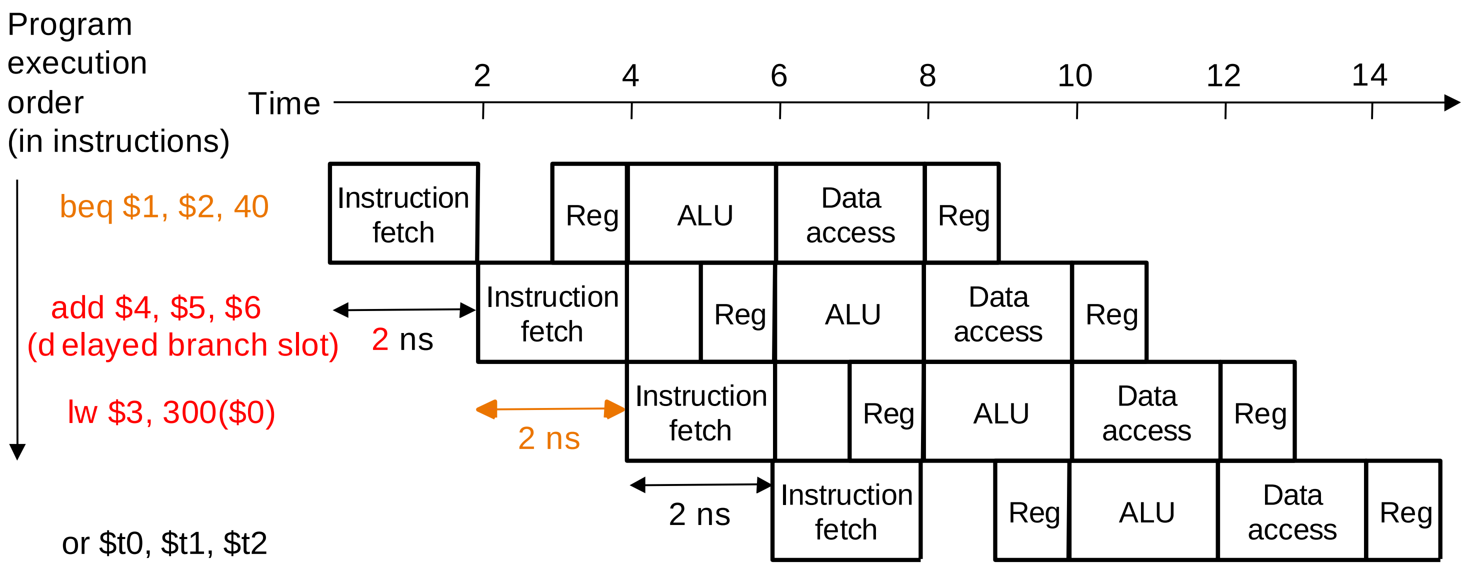
Prediction success



Prediction failure: undo (=flush) `lw`

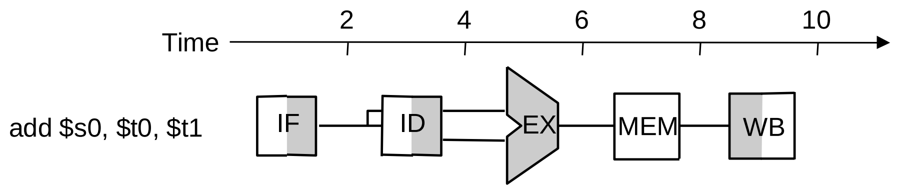
Control Hazards

- Solution 3 *Delayed branch:* always execute the sequentially next statements with the branch executing after one instruction delay – compiler's job to find a statement that can be put in the slot that is independent of branch outcome
  - MIPS does this – but it is an option in SPIM (Simulator -> Settings)

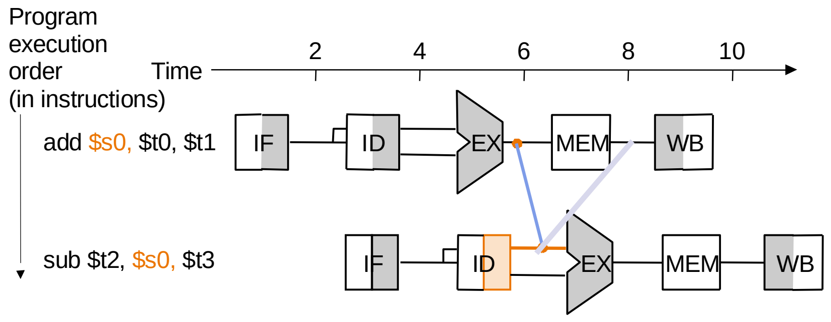


Data Hazards

- *Data hazard*: instruction needs data from the result of a previous instruction still executing in pipeline
- Solution *Forward* data if possible…



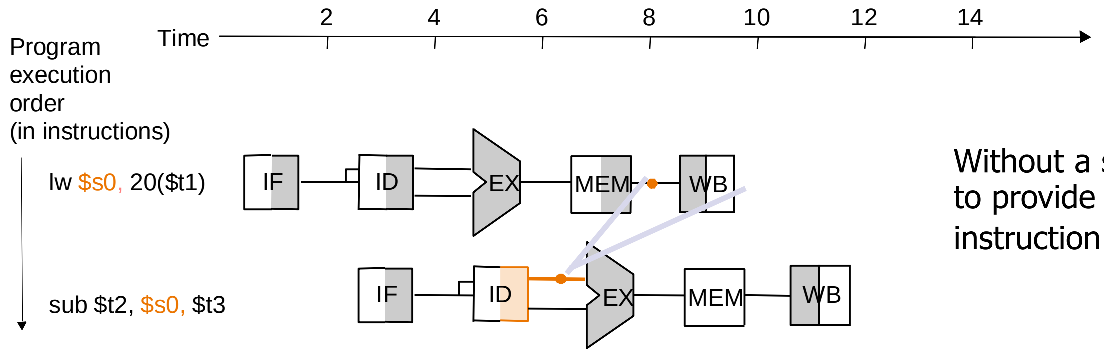
Instruction pipeline diagram: shade indicates use – left=write, right=read



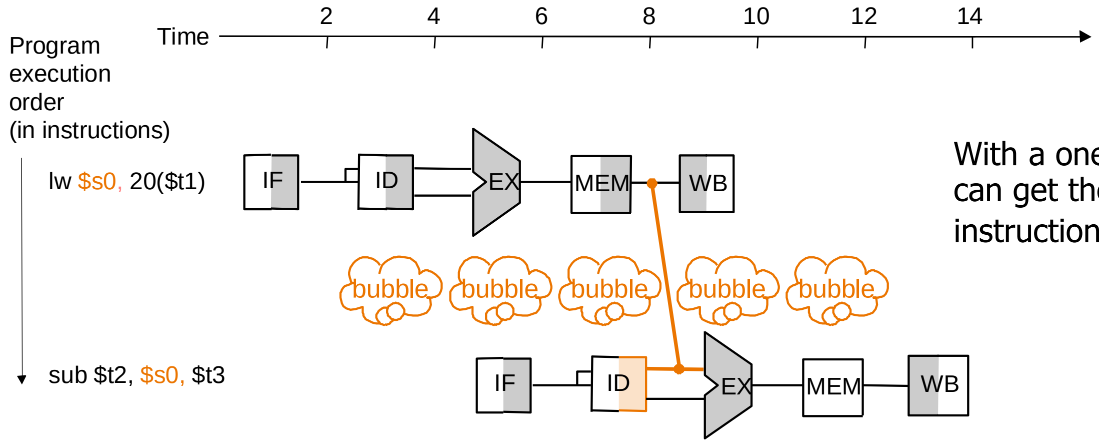
Without forwarding – blue line – data has to go back in time; with forwarding – red line – data is available in time

Data Hazards

- Forwarding may not be enough
  - e.g., if an R-type instruction following a load uses the result of the load – called *load-use data hazard*



Without a stall it is impossible to provide input to the `sub` instruction in time



With a one-stage stall, forwarding can get the data to the `sub` instruction in time

Reordering Code to Avoid Pipeline Stall (Software Solution)

- Example:

```
lw $t0, 0($t1)
lw $t2, 4($t1)
sw $t2, 0($t1)
sw $t0, 4($t1)
```

Data hazard

- Reordered code:

```
lw $t0, 0($t1)
lw $t2, 4($t1)
sw $t0, 4($t1)
sw $t2, 0($t1)
```

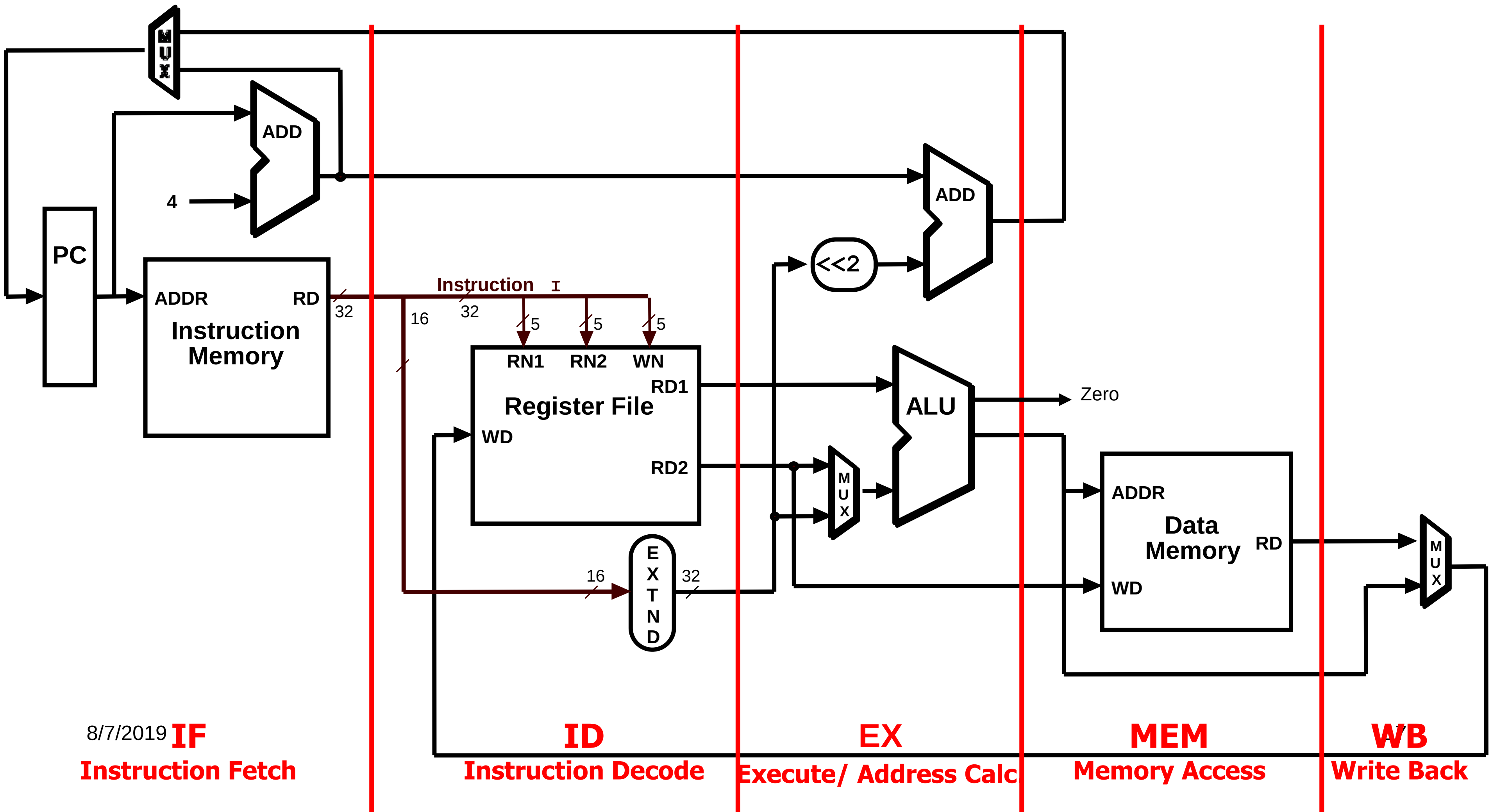
Interchanged

Pipelined Datapath

- We now move to actually building a pipelined datapath
- First recall the 5 steps in instruction execution
  1. Instruction Fetch & PC Increment (IF)
  2. Instruction Decode and Register Read (ID)
  3. Execution or calculate address (EX)
  4. Memory access (MEM)
  5. Write result into register (WB)
- Review: single-cycle processor
  - all 5 steps done in a single clock cycle
  - dedicated hardware required for each step

- *What happens if we break the execution into multiple cycles, but keep the extra hardware?*

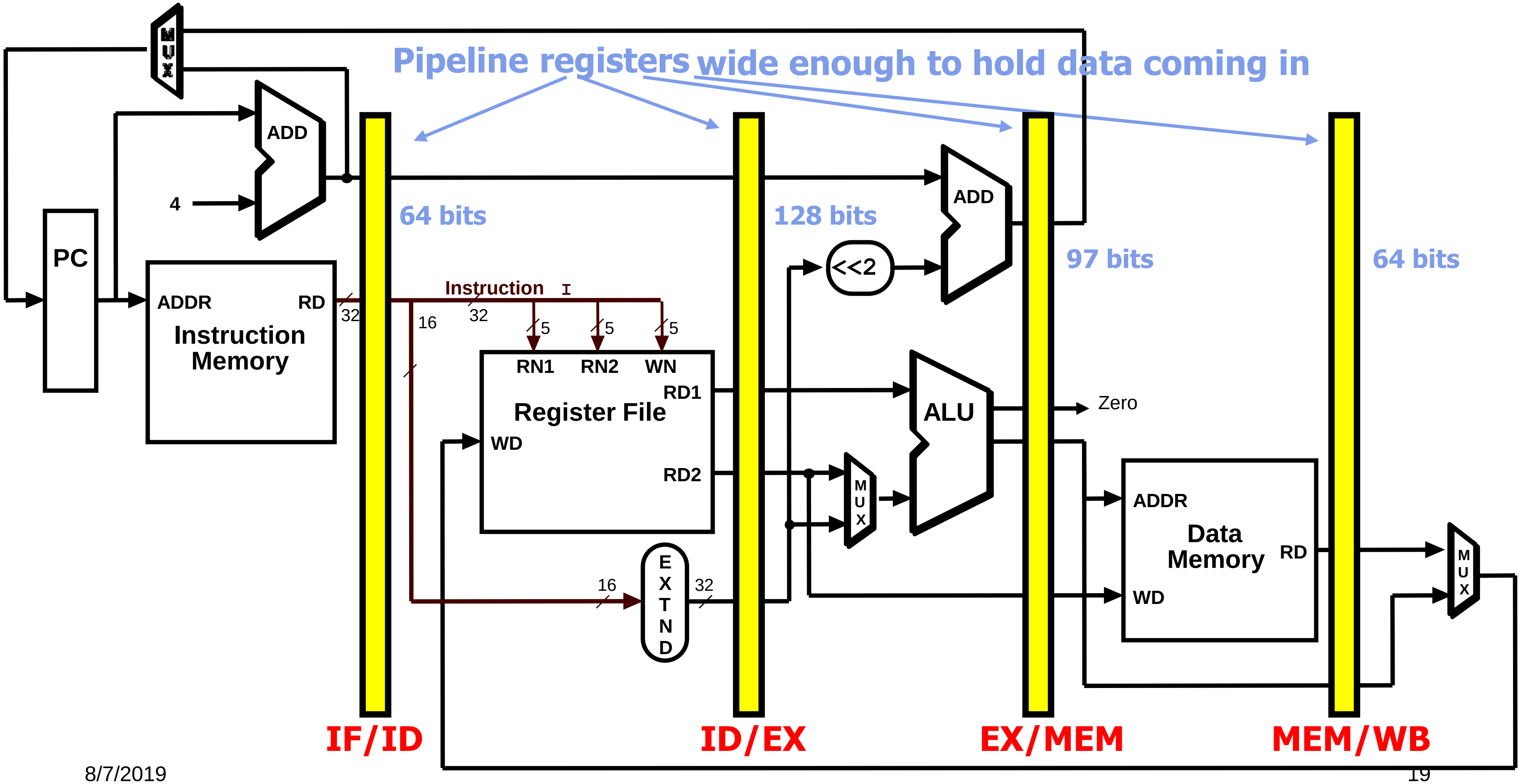
Review - Single-Cycle Datapath "Steps"



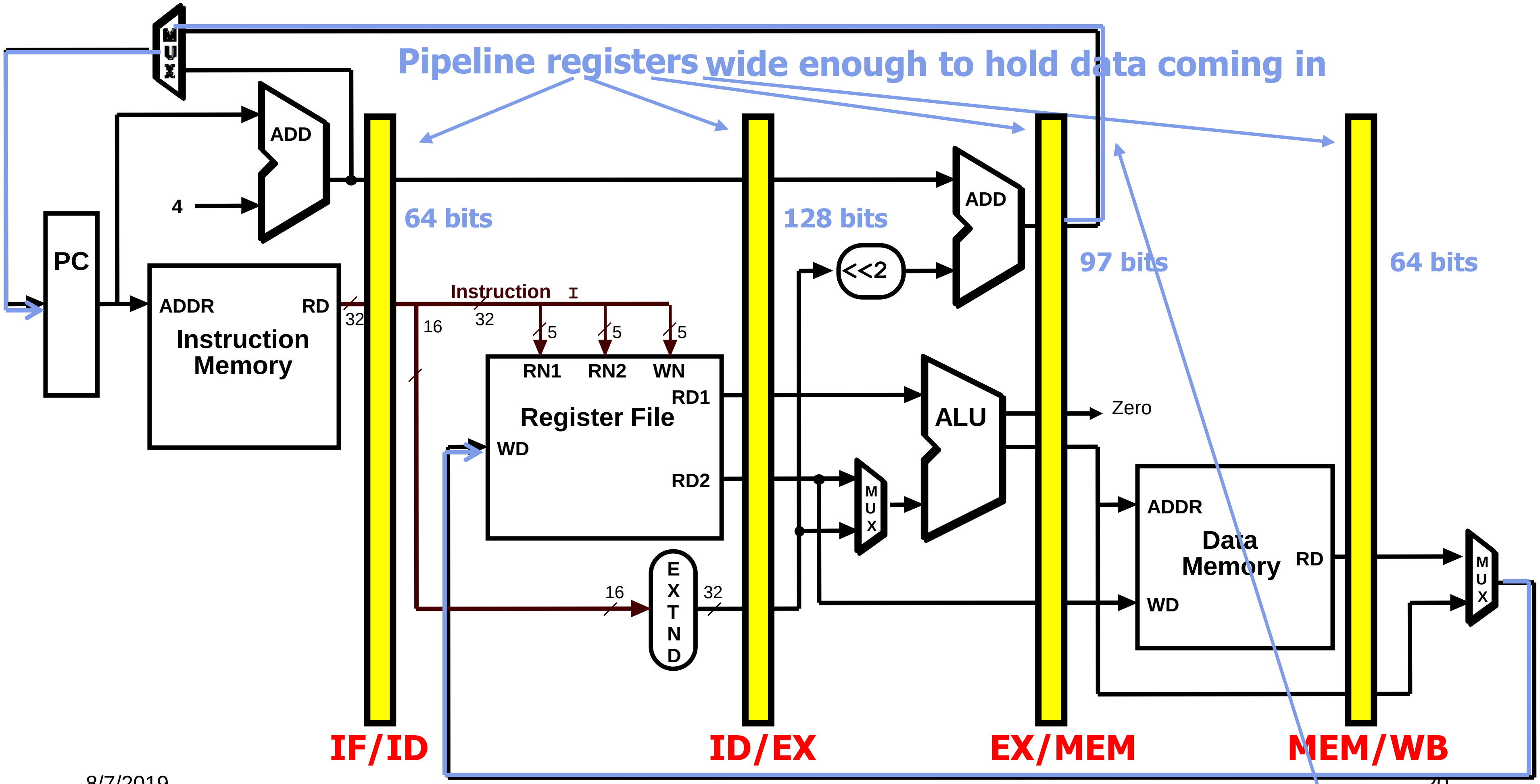
Pipelined Datapath – Key Idea

- *What happens if we break the execution into multiple cycles, but keep the extra hardware?*
  - Answer: *We may be able to start executing a new instruction at each clock cycle* - pipelining
- …but we shall need *extra* registers to hold data between cycles – *pipeline registers*

Pipelined Datapath

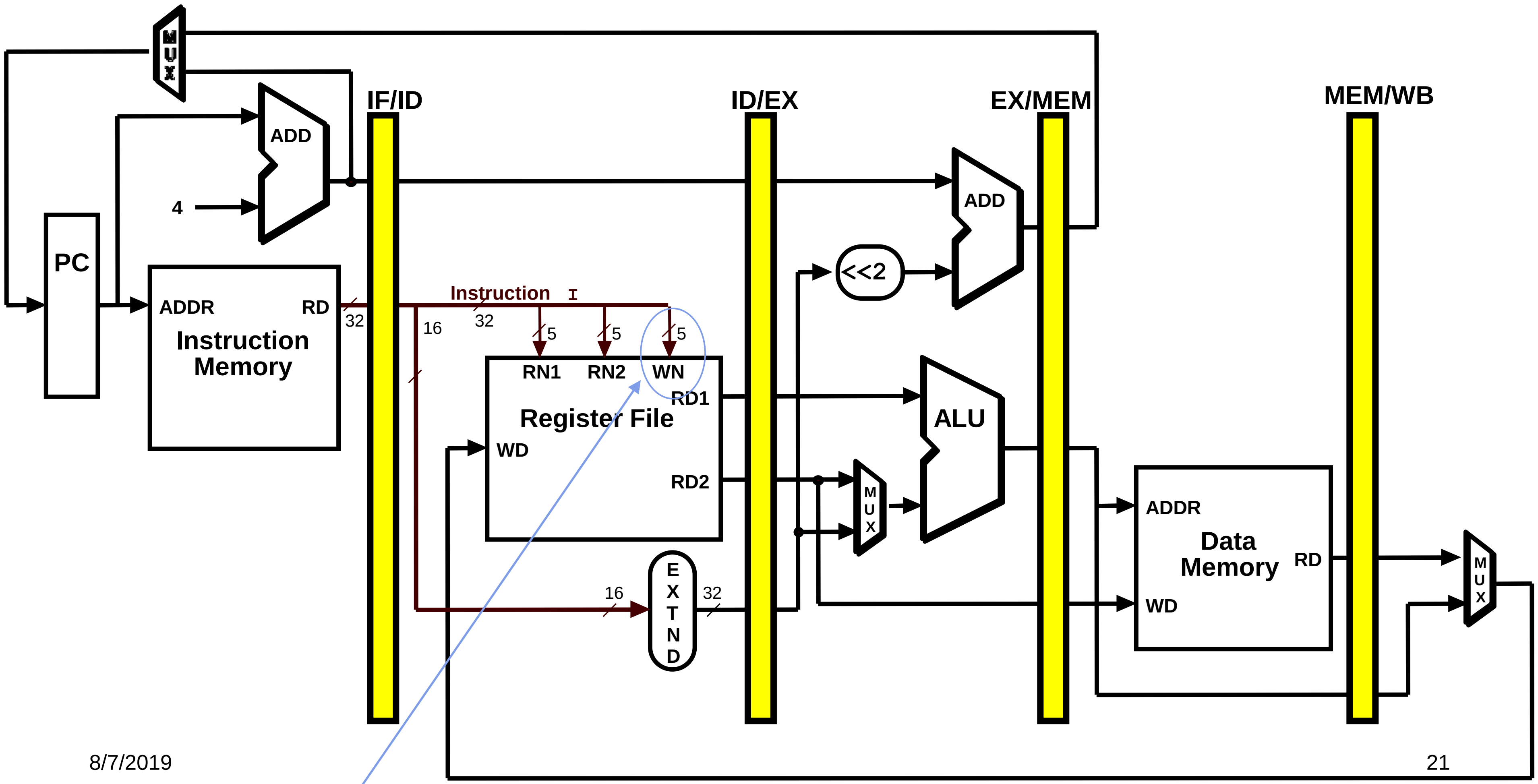


Pipelined Datapath



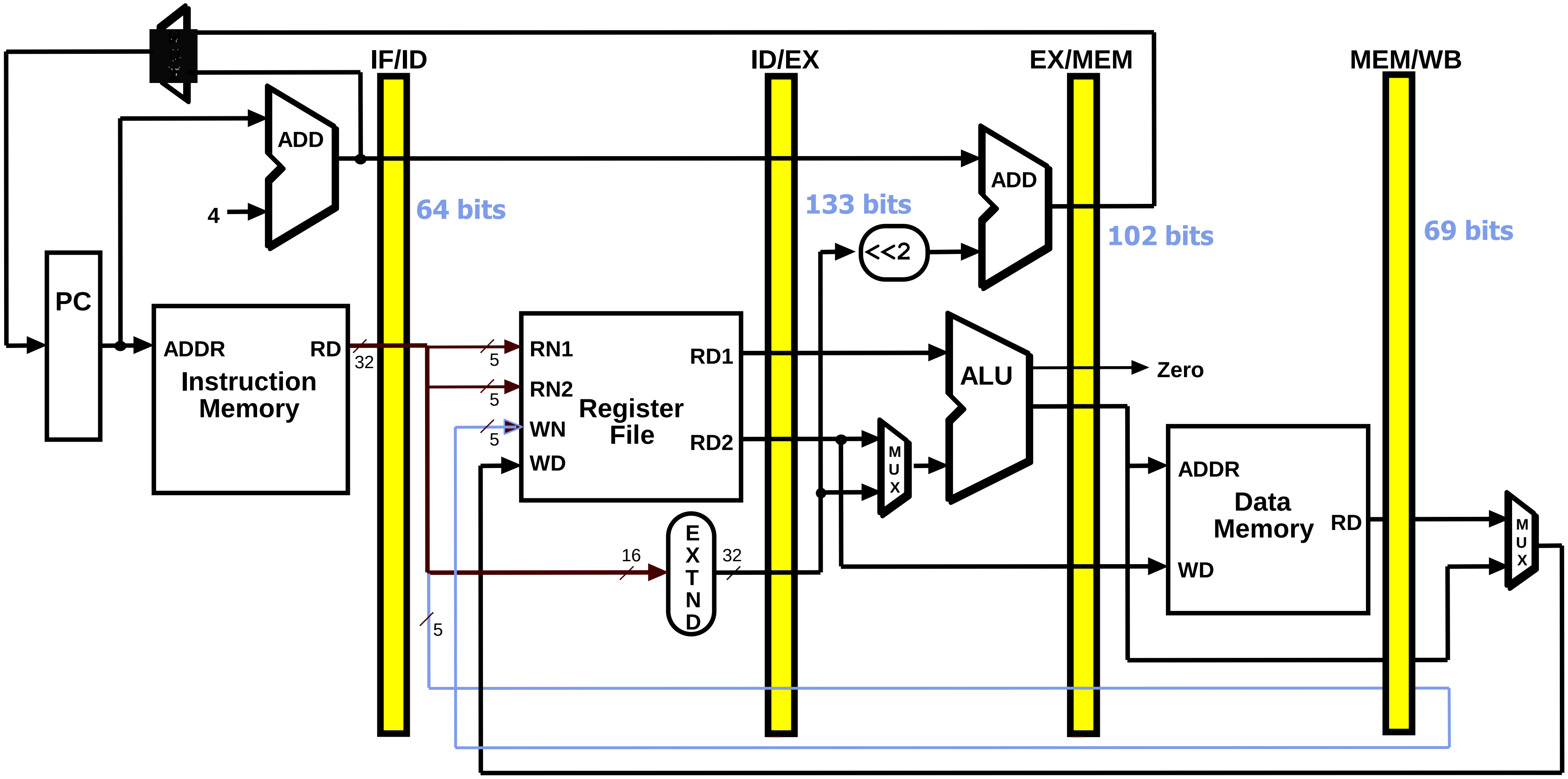
Only data flowing right to left may cause hazard…, why?

Bug in the Datapath



Write register number comes from another *later* instruction!

Corrected Datapath



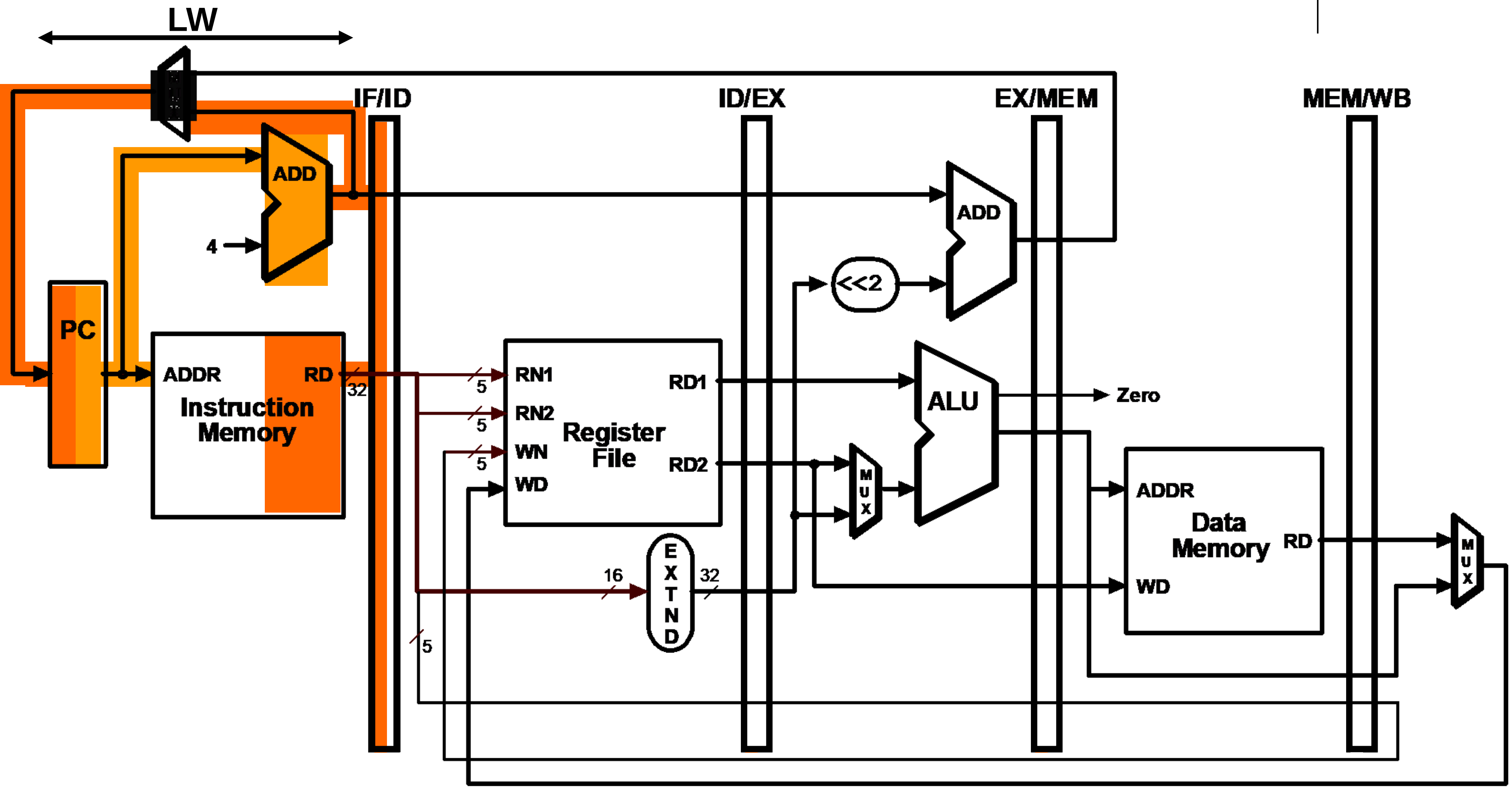
Destination register number is also passed through ID/EX, EX/MEM and MEM/WB registers, which are now wider by 5 bits

Pipelined Example

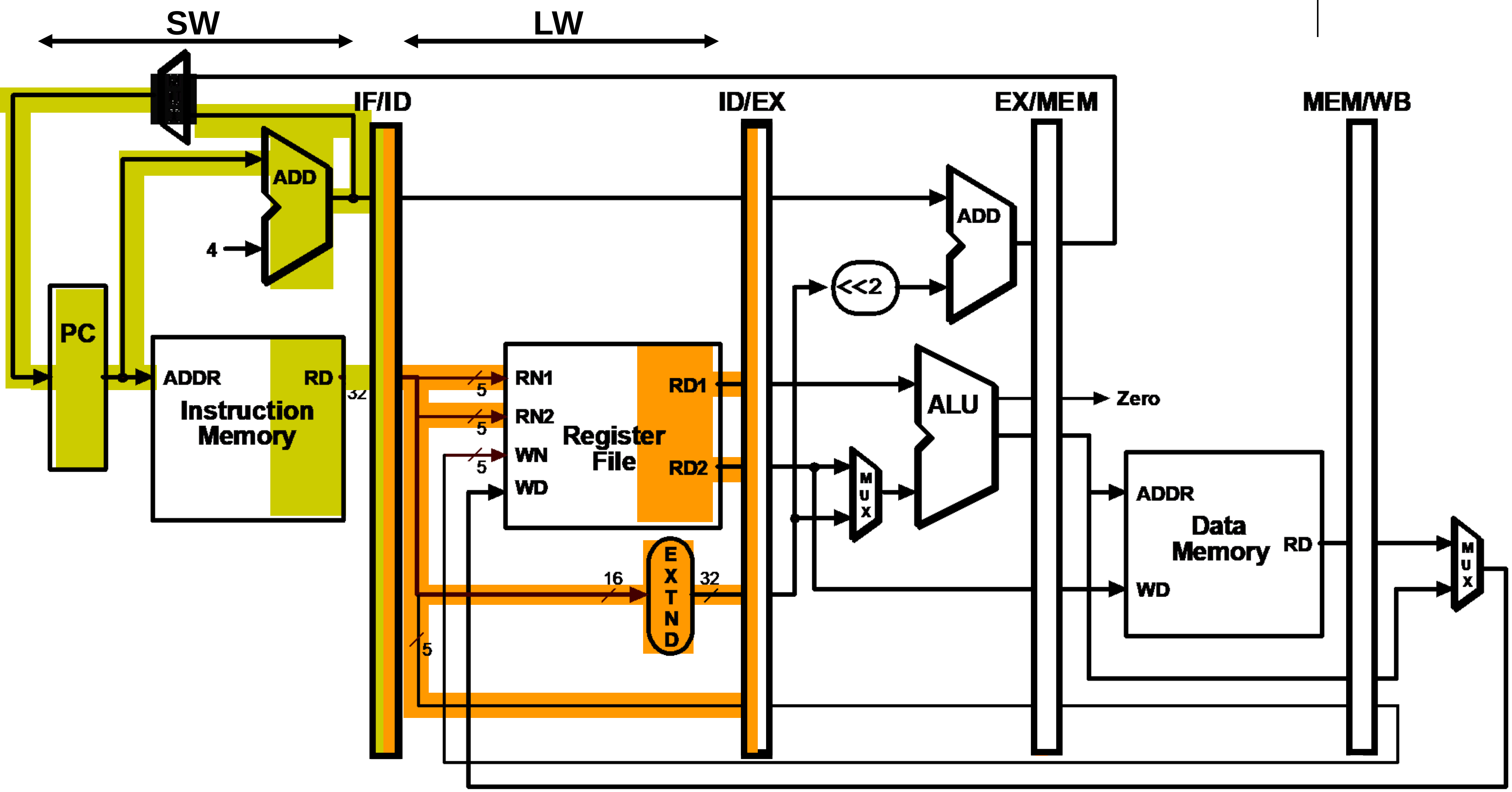
- Consider the following instruction sequence:

```
lw  $t0,  10($t1)
sw  $t3, 20($t4)
add $t5,  $t6,  $t7
sub $t8,  $t9,  $t10
```

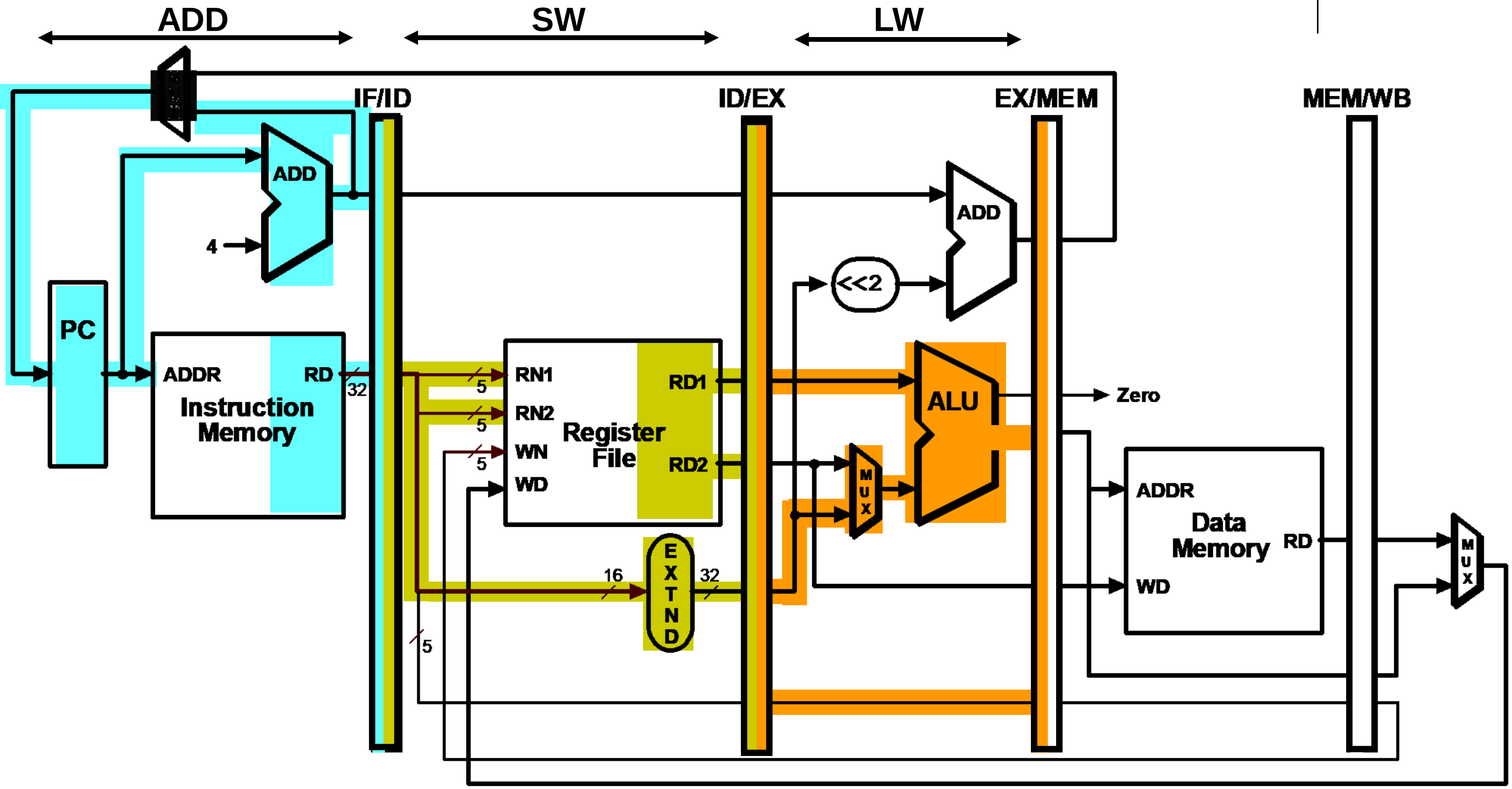
Single-Clock-Cycle Diagram: Clock Cycle 1



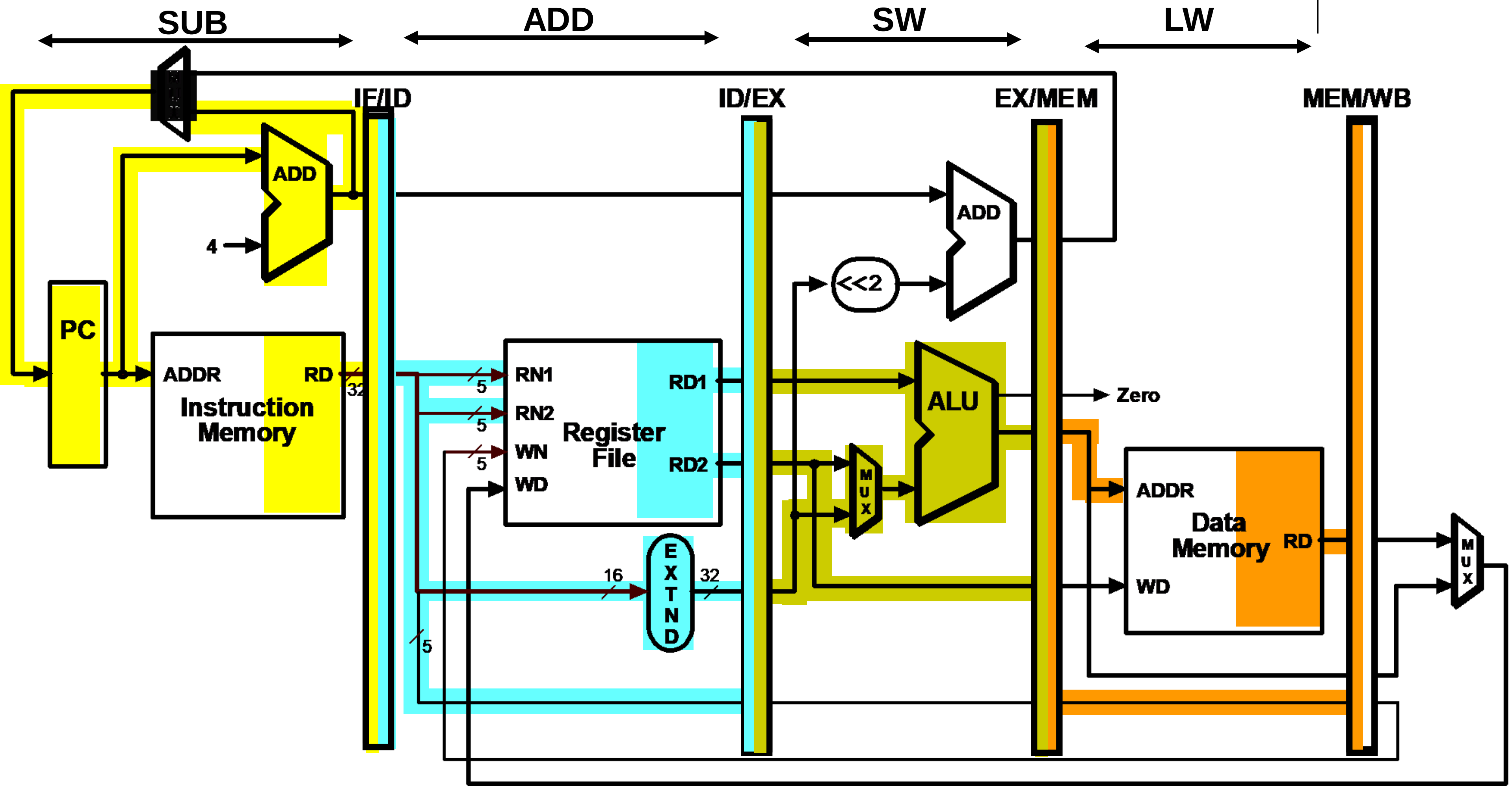
Single-Clock-Cycle Diagram: Clock Cycle 2



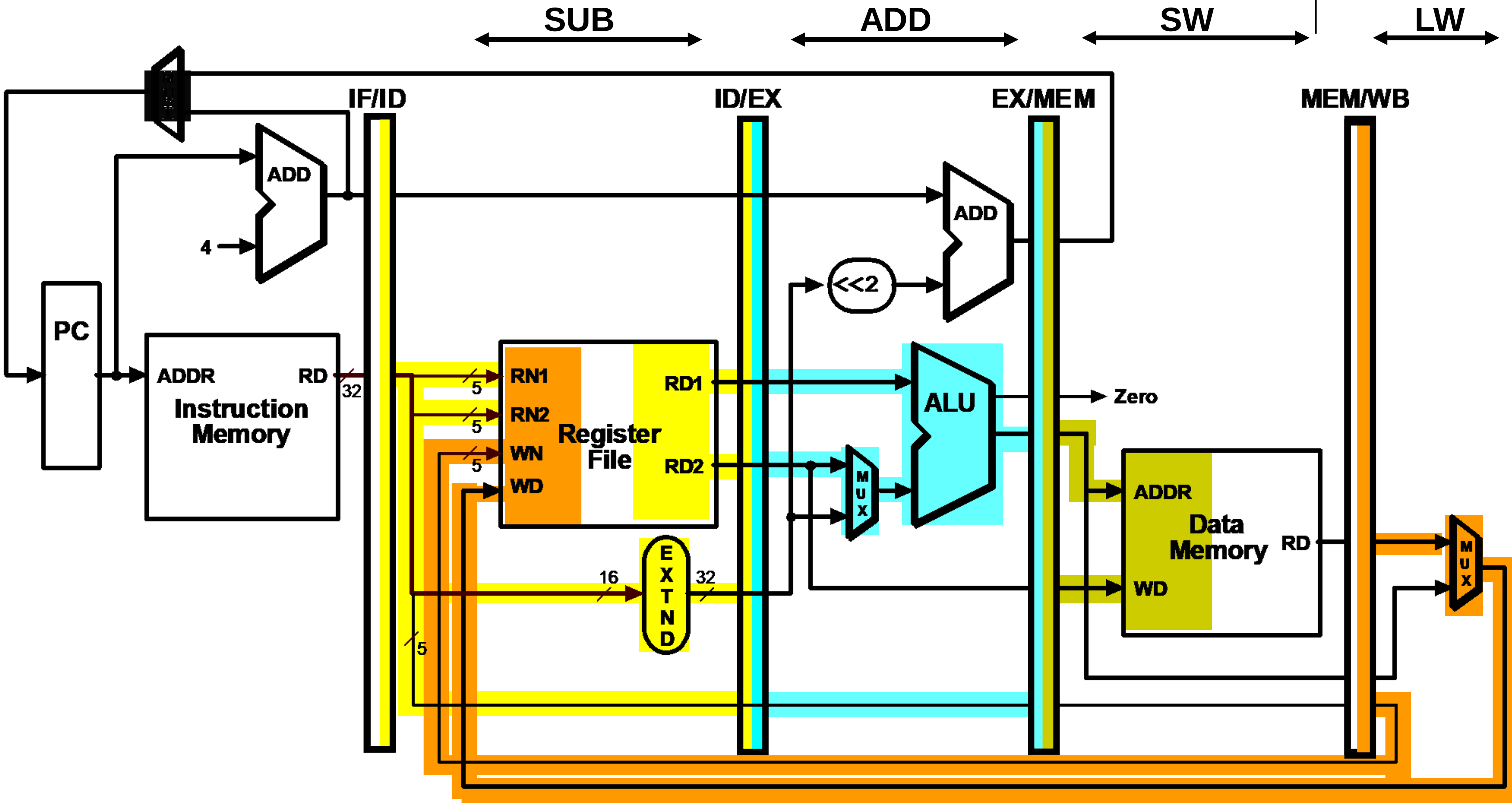
Single-Clock-Cycle Diagram: Clock Cycle 3



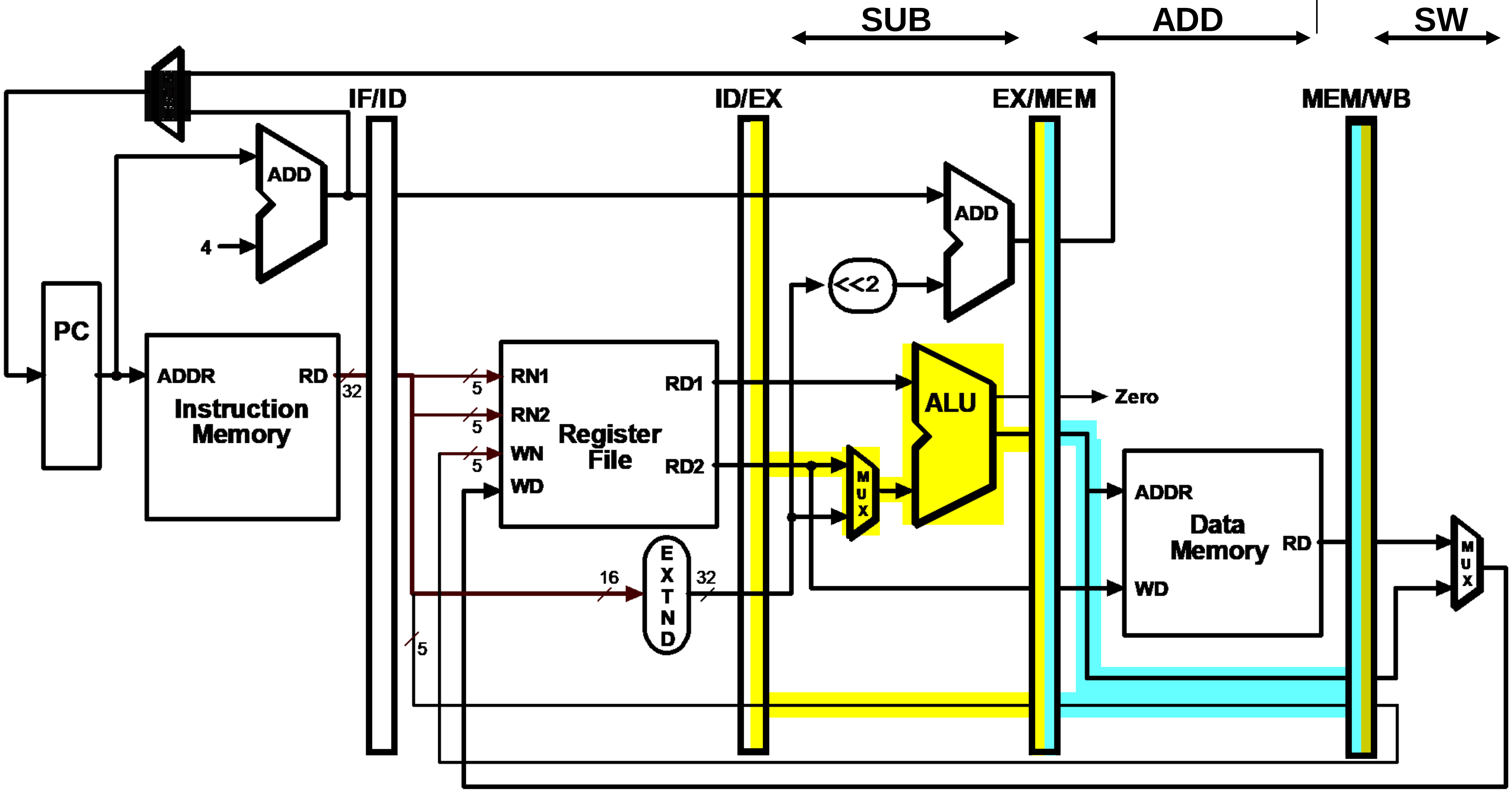
Single-Clock-Cycle Diagram: Clock Cycle 4



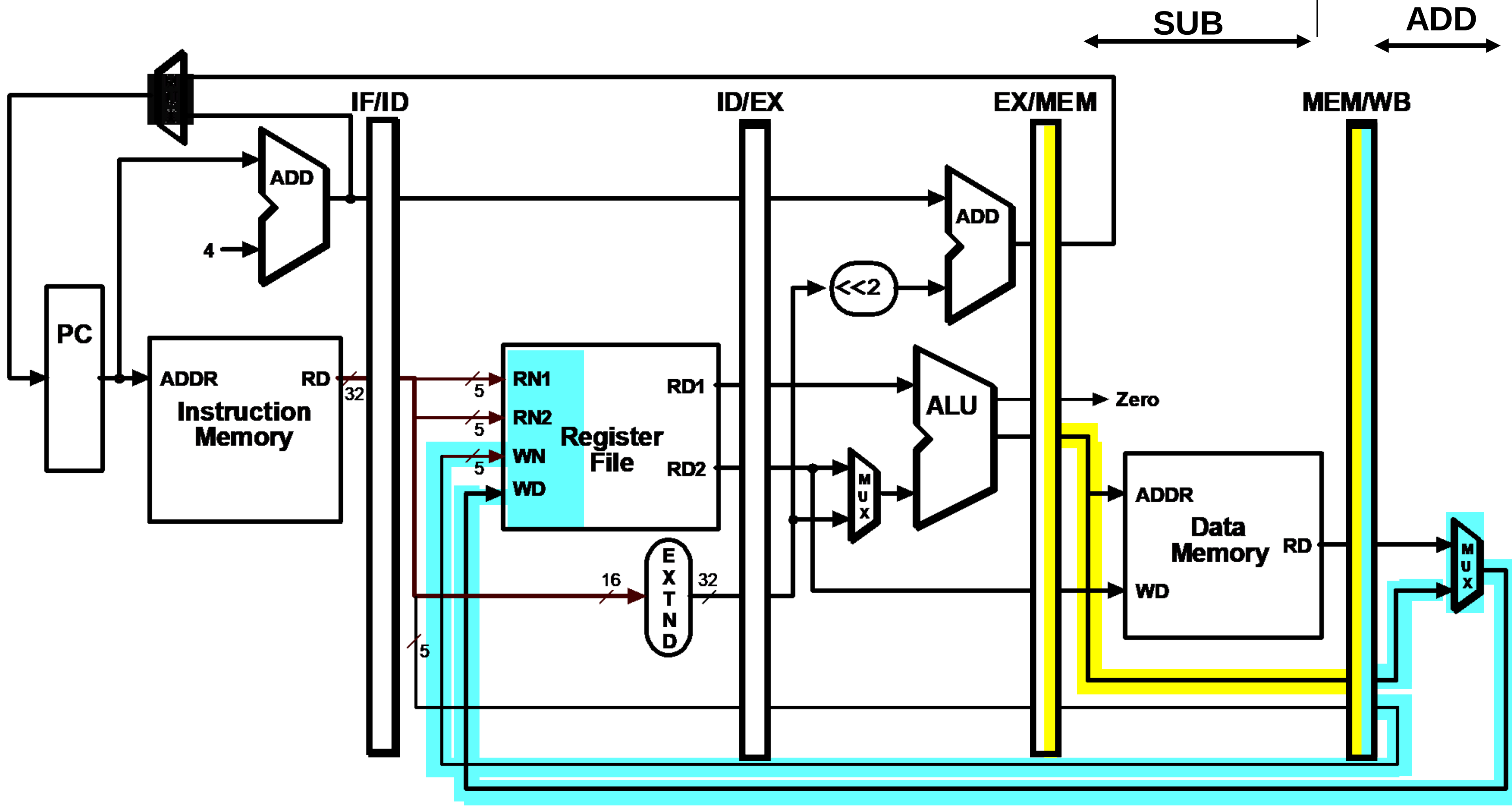
Single-Clock-Cycle Diagram: Clock Cycle 5



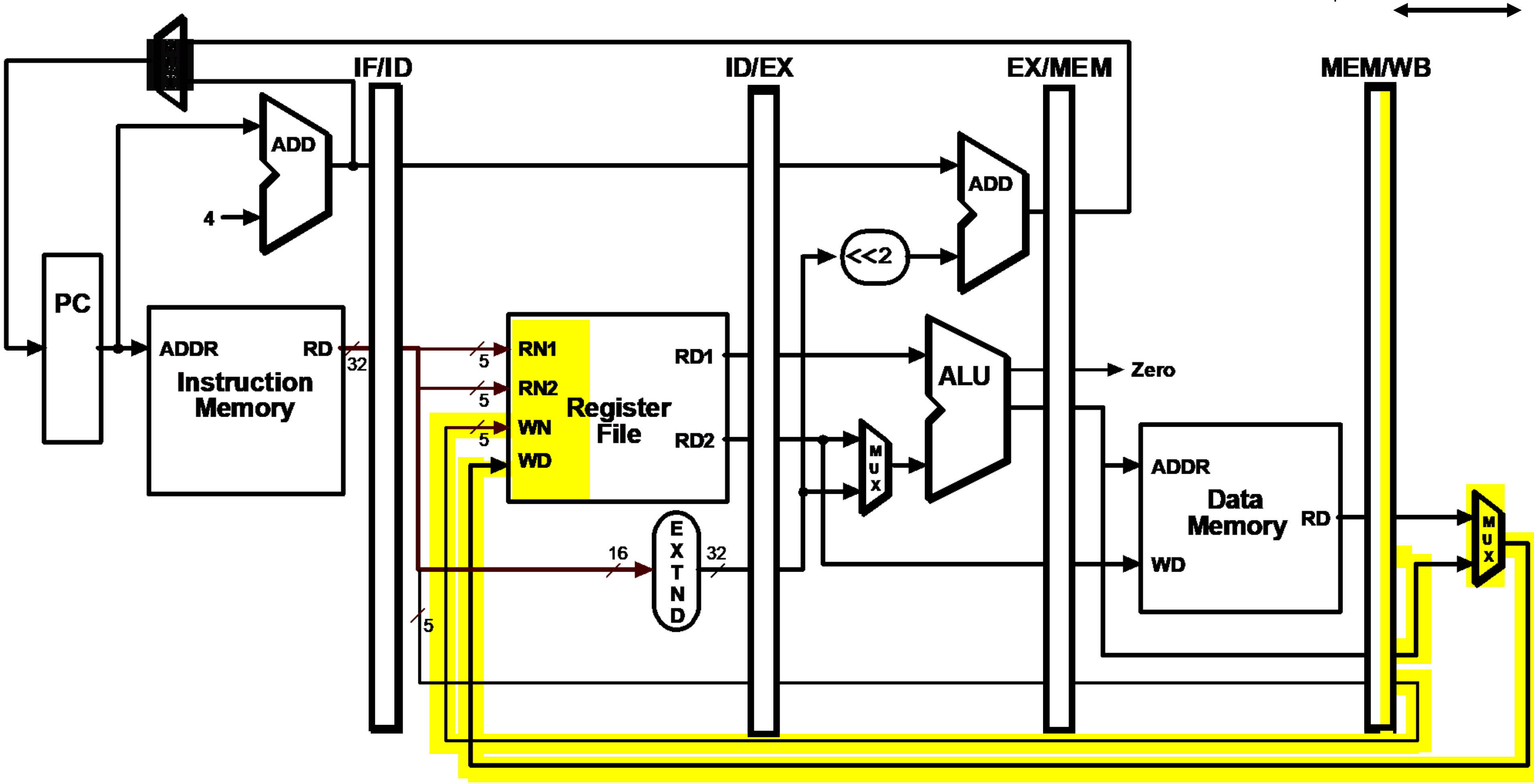
Single-Clock-Cycle Diagram: Clock Cycle 6



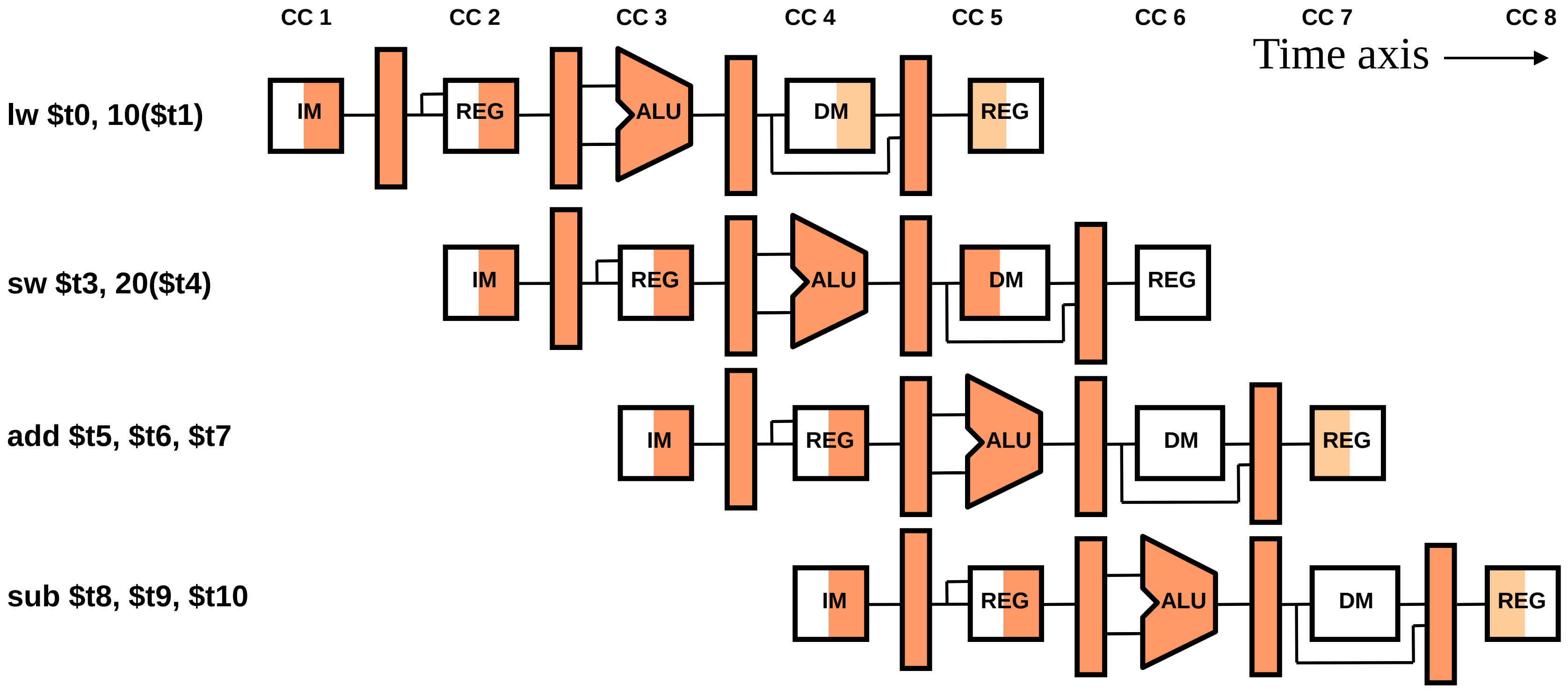
Single-Clock-Cycle Diagram: Clock Cycle 7



Single-Clock-Cycle Diagram: Clock Cycle 8



Alternative View – Multiple-Clock-Cycle Diagram



Notes

- One significant difference in the execution of an R-type instruction between multicycle and pipelined implementations:
  - register write-back for the R-type instruction is the 5th (the last write-back) pipeline stage vs. the 4th stage for the multicycle implementation. *Why?*
  - think of *structural hazards* when writing to the register file…
- Worth repeating: the *essential difference* between the pipeline and multicycle implementations is the insertion of pipeline registers to *decouple the 5 stages*
- The CPI of an *ideal pipeline* (no stalls) is 1. *Why?*

Simple Example: Comparing Performance

- *Compare performance for multicycle, and pipelined datapaths using the gcc instruction mix*
  - assume 2 ns for memory access
  - assume gcc instruction mix 23% loads, 13% stores, 19% branches, 2% jumps, 43% ALU
  - for pipelined execution assume
    - 50% of the loads are followed immediately by an instruction that uses the result of the load. This sacrifies 2 cylces.
    - 25% of branches are mispredicted
    - branch delay on misprediction is 1 clock cycle
    - jumps always incur 1 clock cycle delay so their average time is 2 clock cycles

Simple Example: Comparing Performance

- *Multicycle*: average instruction time 8.04 ns
- *Pipelined*:
  - loads use 1 cc (clock cycle) when no load-use dependency and 2 cc when there is dependency – given 50% of loads are followed by dependency the average cc per load is: 0.5*1+0.5*2=1.5
  - stores use 1 cc each
  - branches use 1 cc when predicted correctly and 2 cc when not – given 25% mis-prediction average cc per branch is 0.75*1+0.25*2=1.25
  - jumps use 3 cc each
  - ALU instructions use 1 cc each
  - therefore, average CPI is

$1.5 \times 23\% + 1 \times 13\% + 1.25 \times 19\% + 3 \times 2\% + 1 \times 43\% = 1.1825$

  - therefore, average instruction time is $1.1825 \times 2 = 2.365$ ns

Summary

- *Techniques described in this chapter to design datapaths and control are at the core of all modern computer architecture*
- Multicycle datapaths offer two great advantages over single-cycle
  - functional units can be reused within a single instruction if they are accessed in different cycles – reducing the need to replicate expensive logic
  - instructions with shorter execution paths can complete quicker by consuming fewer cycles
- Modern computers, in fact, take the multicycle paradigm to a higher level to achieve greater instruction throughput:
  - *pipelining* (next topic) where multiple instructions execute simultaneously by having cycles of different instructions overlap in the datapath
  - *the MIPS architecture was designed to be pipelined*