Design of Digital Circuits
Lecture 15: Pipelining Issues

Prof. Onur Mutlu
ETH Zurich

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Agenda for Today & Next Few Lectures

- Previous lectures
  - Single-cycle Microarchitectures
  - Multi-cycle and Microprogrammed Microarchitectures

- Yesterday
  - Pipelining

- Issues in Pipelining: Control & Data Dependence Handling, State Maintenance and Recovery, …

- Out-of-Order Execution

- Issues in OoO Execution: Load-Store Handling, …

Lecture Announcement

- Monday, April 30, 2018
- 16:15-17:15
- CAB G 61
- Apéro after the lecture ☺

- Prof. Wen-Mei Hwu (University of Illinois at Urbana-Champaign)
- D-INFK Distinguished Colloquium
- **Innovative Applications and Technology Pivots – A Perfect Storm in Computing**

- https://www.inf.ethz.ch/news-and-events/colloquium/event-detail.html?eventFeedId=40447

Readings for This Week and Next Week

- H&H, Chapter 7.5: Pipelined Processor

- H&H 7.6-7.9 (finish Chapter 7)

- Smith and Sohi, "The Microarchitecture of Superscalar Processors," Proceedings of the IEEE, 1995
  - More advanced pipelining
  - Interrupt and exception handling
  - Out-of-order and superscalar execution concepts

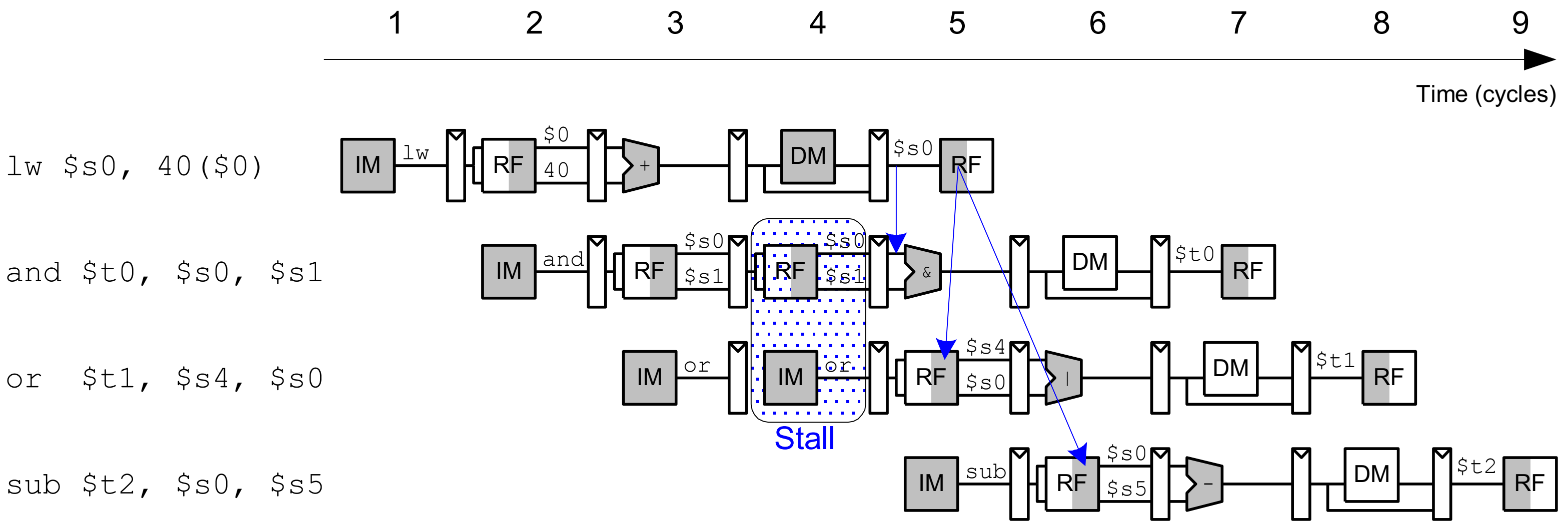
Review: How to Handle Data Dependences

- Anti and output dependences are easier to handle
  - write to the destination in one stage and in program order

- Flow dependences are more interesting

- Six fundamental ways of handling flow dependences
  - Detect and wait until value is available in register file
  - Detect and forward/bypass data to dependent instruction
  - Detect and eliminate the dependence at the software level
    - No need for the hardware to detect dependence
  - Detect and move it out of the way for independent instructions
  - Predict the needed value(s), execute "speculatively", and verify
  - Do something else (fine-grained multithreading)
    - No need to detect

Stalling



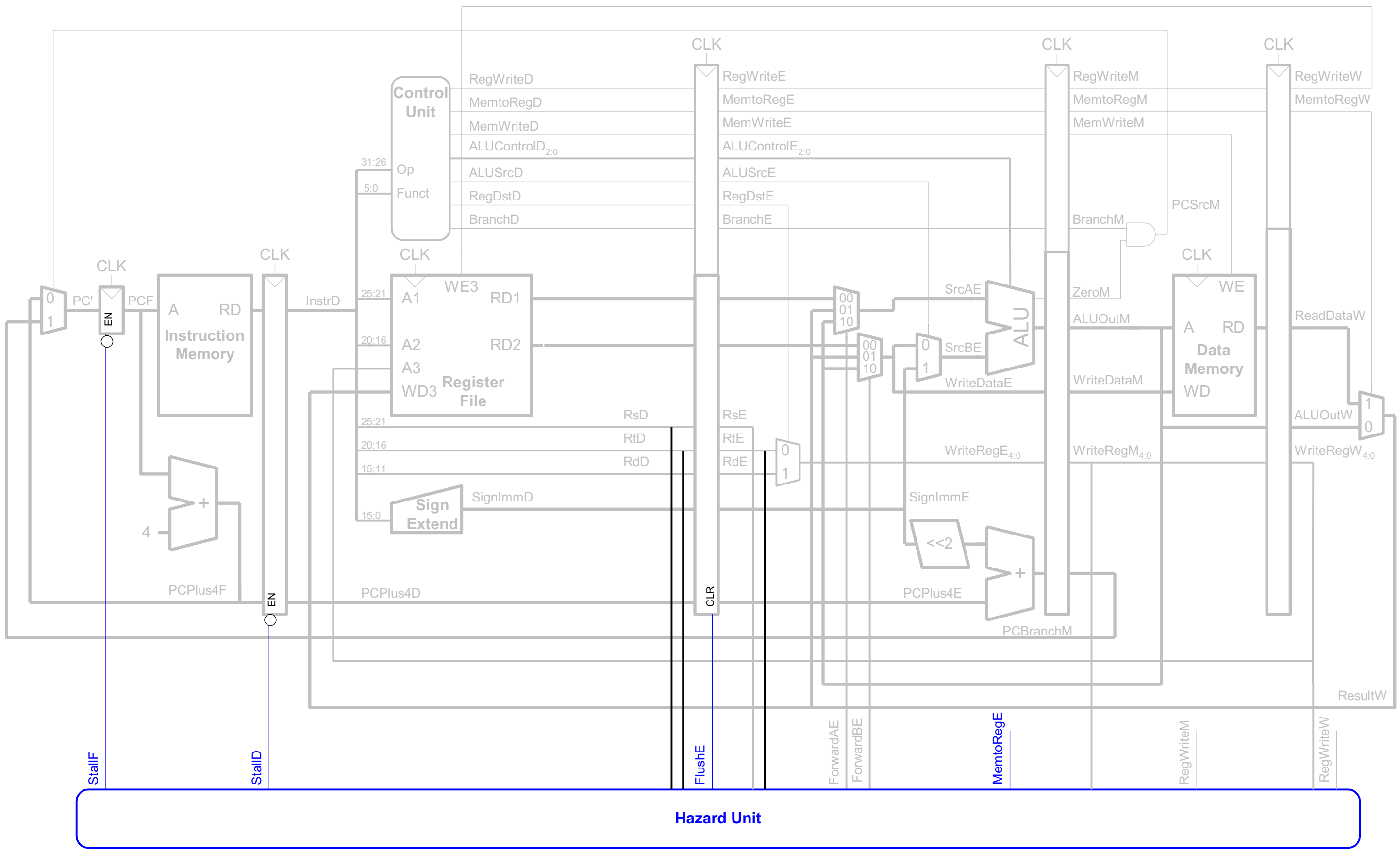
1 2 3 4 5 6 7 8 9
Time (cycles)
lw $s0, 40($0)
and $t0, $s0, $s1
or $t1, $s4, $s0
sub $t2, $s0, $s5
IM
lw
RF
$0
40
DM
$s0
and
$s1
$t0
or
$s4
$t1
sub
$s5
$t2
Stall

Stalling Hardware

- **Stalls are supported by:**
  - adding enable inputs (EN) to the Fetch and Decode pipeline registers
  - and a synchronous reset/clear (CLR) input to the Execute pipeline register
    - or an INV bit associated with each pipeline register

- **When a lw stall occurs**
  - StallD and StallF are asserted to force the Decode and Fetch stage pipeline registers to hold their old values.
  - FlushE is also asserted to clear the contents of the Execute stage pipeline register, introducing a bubble

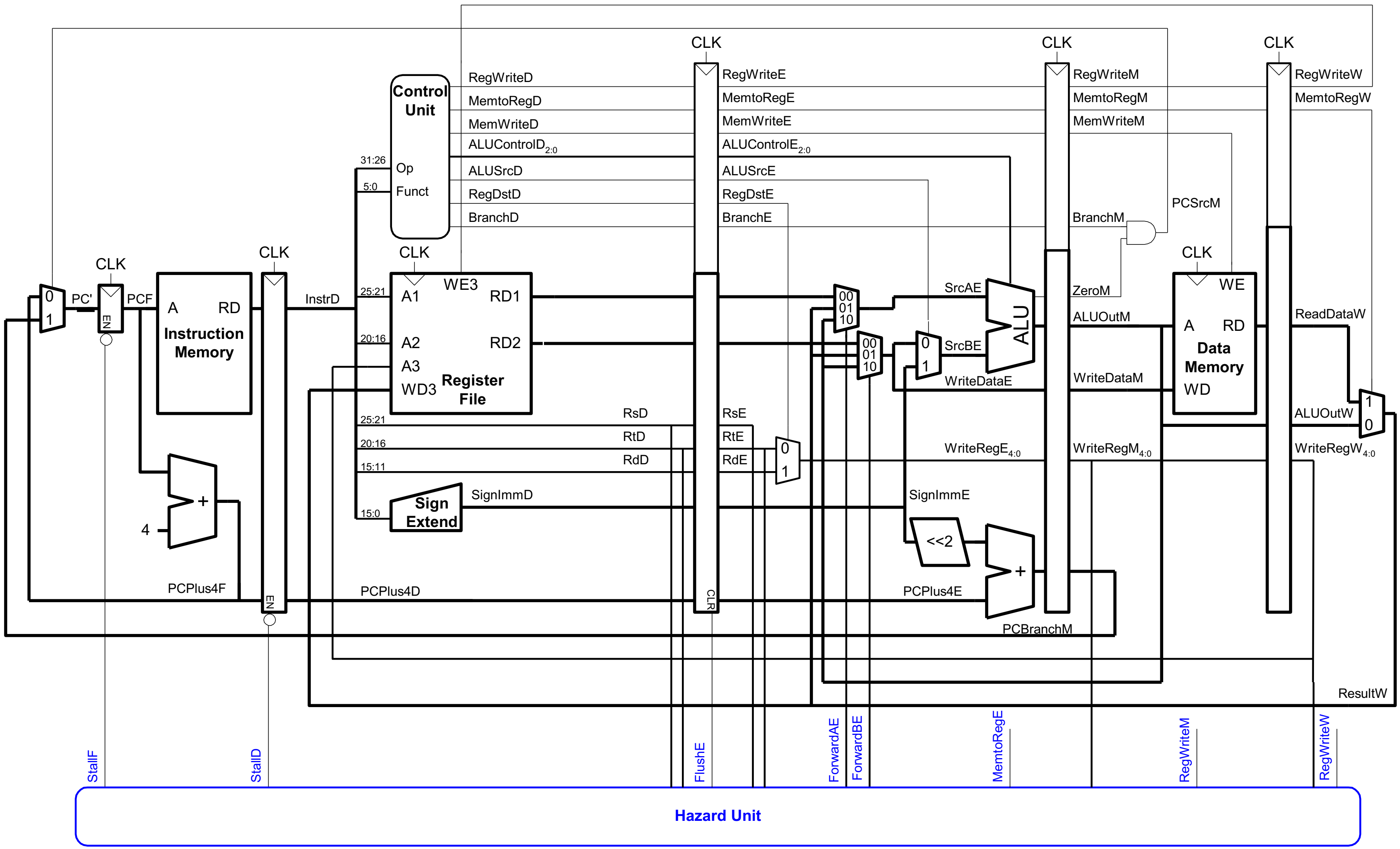
Stalling Hardware



Control Dependences

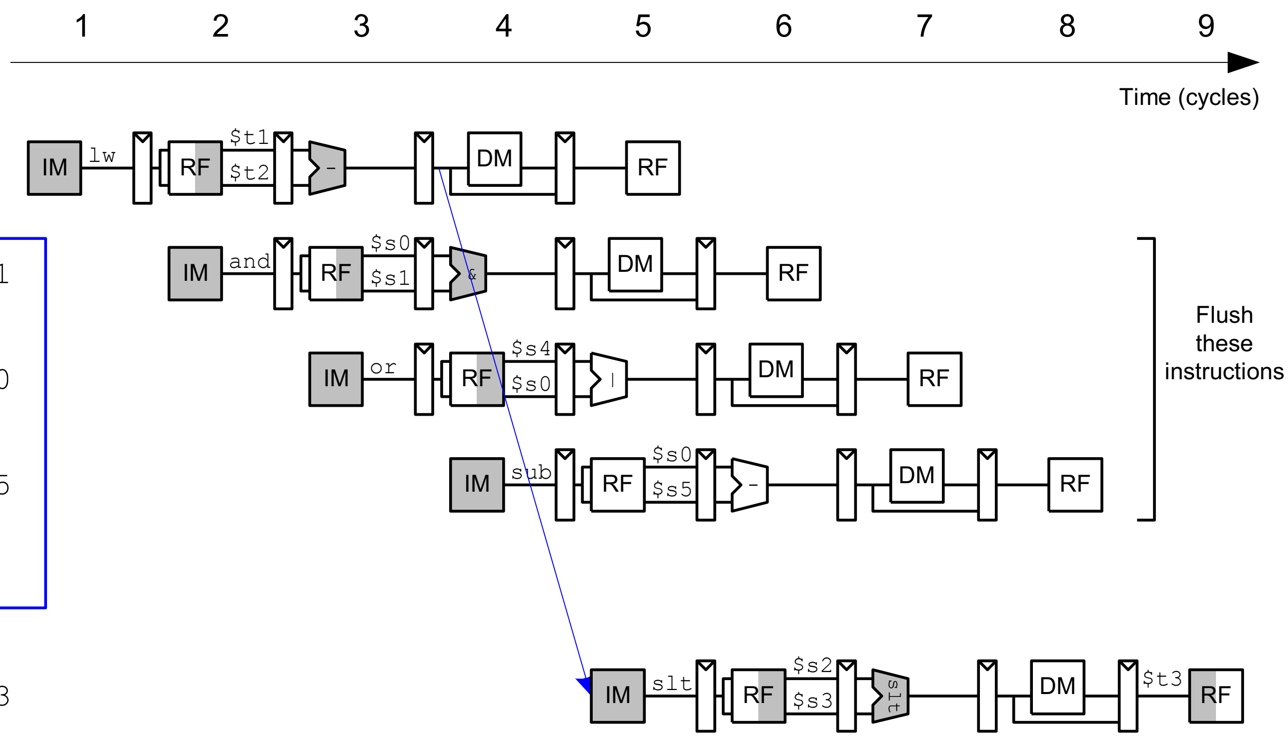
- **Special case of data dependence: dependence on PC**
- **beq:**
  - branch is not determined until the fourth stage of the pipeline
  - Instructions after the branch are fetched before branch is resolved
    - Always predict that the next sequential instruction is fetched
    - Called "Always not taken" prediction
  - These instructions must be flushed if the branch is taken
- **Branch misprediction penalty**
  - **number of instructions flushed when branch is taken**
  - May be reduced by determining branch earlier

Control Dependence: Original Pipeline

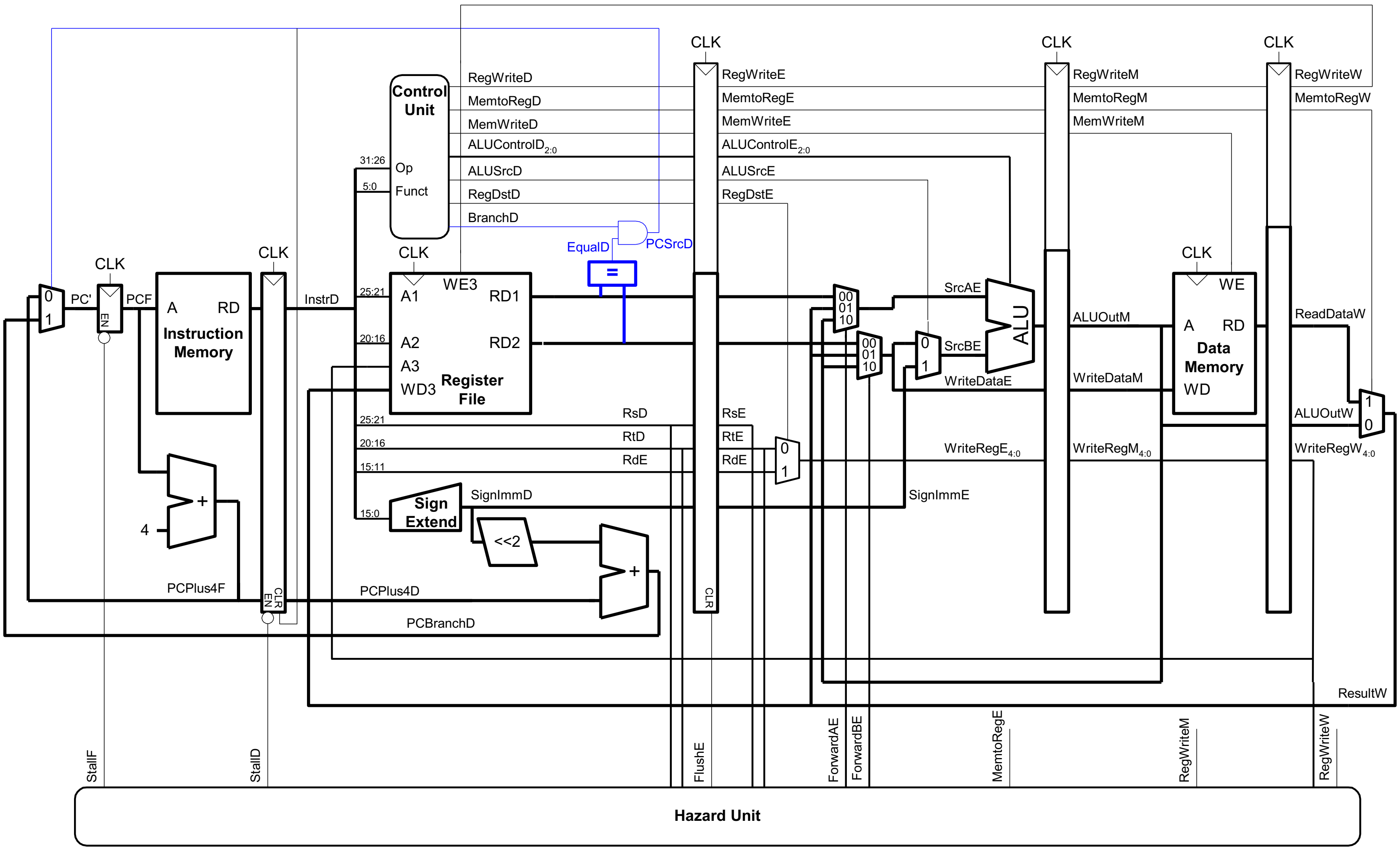


Control Dependence

```
20   beq $t1, $t2, 40
24   and $t0, $s0, $s1
28   or  $t1, $s4, $s0
2C   sub $t2, $s0, $s5
30   ...
...
64   slt $t3, $s2, $s3
```



Early Branch Resolution



Introduces another data dependency in Decode stage..

Early Branch Resolution

```
20   beq $t1, $t2, 40

24   and $t0, $s0, $s1

28   or  $t1, $s4, $s0

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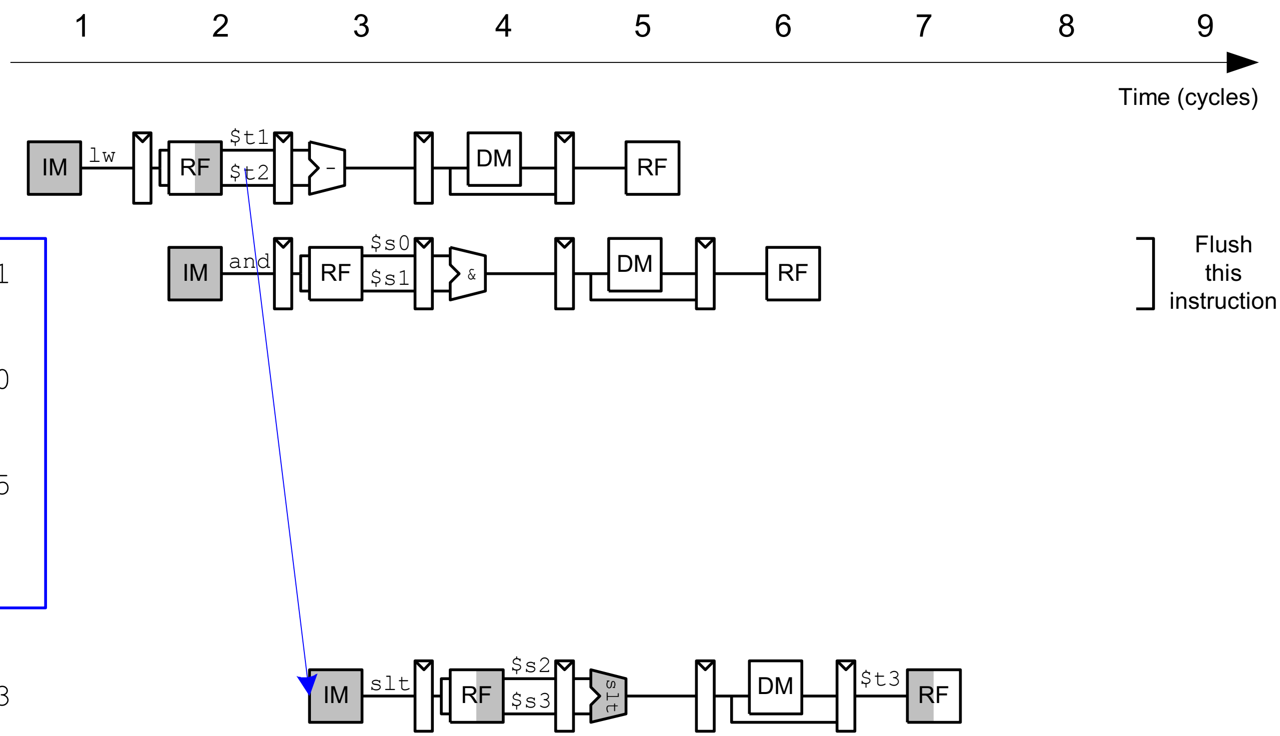
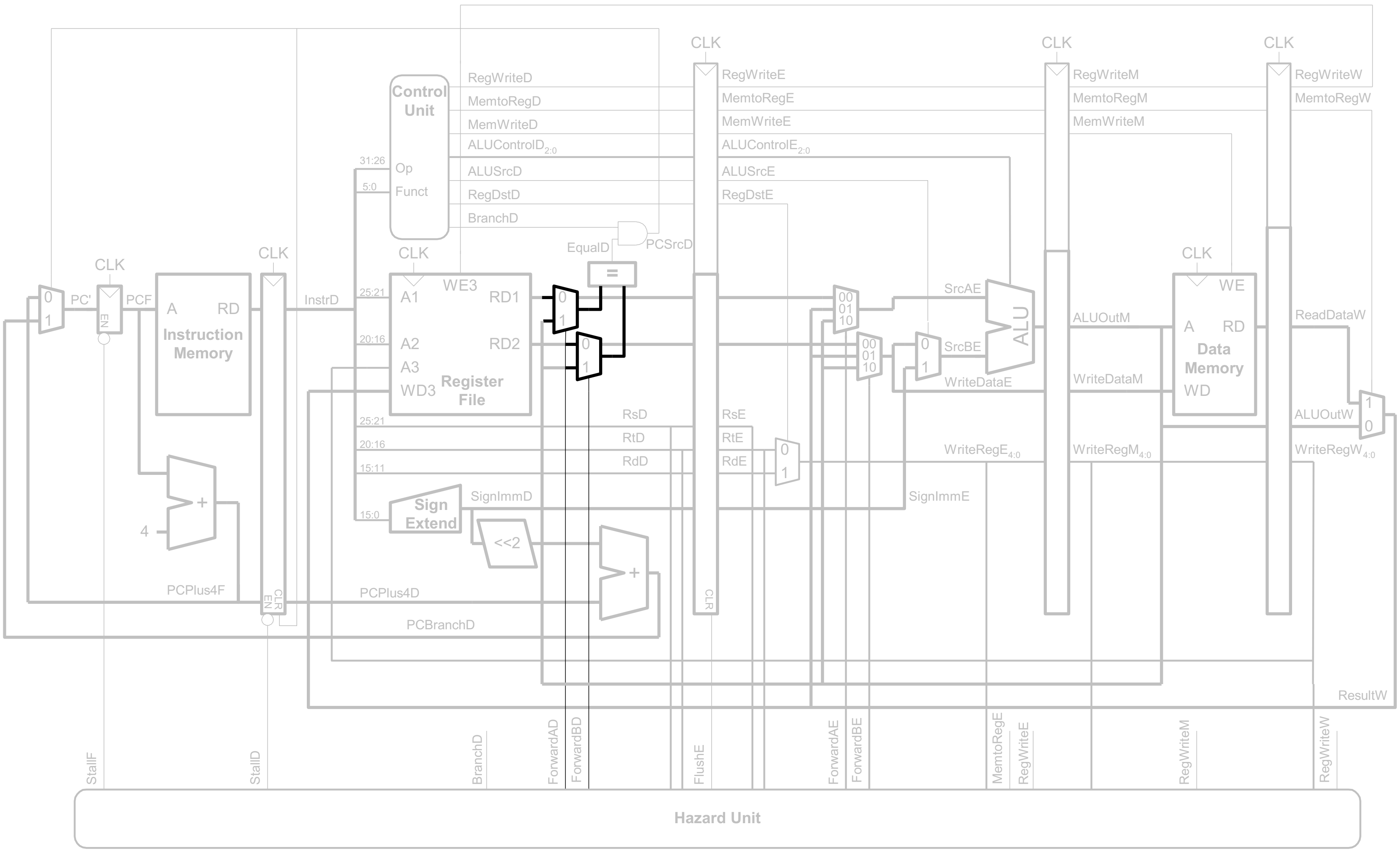


Early Branch Resolution: Good Idea?

- **Advantages**
  - Reduced branch misprediction penalty
    - → Reduced CPI (cycles per instruction)

- **Disadvantages**
  - Potential increase in clock cycle time?
    - → Higher Tclock?
  - Additional hardware cost
    - → Specialized and likely not used by other instructions

Data Forwarding for Early Branch Resolution



Data forwarding for early branch resolution.

Control Forwarding and Stalling Hardware

```
// Forwarding logic:
assign ForwardAD = (rsD != 0) & (rsD == WriteRegM) & RegWriteM;
assign ForwardBD = (rtD != 0) & (rtD == WriteRegM) & RegWriteM;

//Stalling logic:
assign lwstall = ((rsD == rtE) | (rtD == rtE)) & MemtoRegE;

assign branchstall = (BranchD & RegWriteE &
                     (WriteRegE == rsD | WriteRegE == rtD))
                     |
                     (BranchD & MemtoRegM &
                     (WriteRegM == rsD | WriteRegM == rtD));

// Stall signals;
assign StallF = lwstall | branchstall;
assign StallD = lwstall | branchstall;
assign FLushE = lwstall | branchstall;
```

Doing Better: Smarter Branch Prediction

- **Guess whether branch will be taken**
  - Backward branches are usually taken (loops)
  - Consider history of whether branch was previously taken to improve the guess

- **Good prediction reduces the fraction of branches requiring a flush**

Pipelined Performance Example

- **SPECINT2006 benchmark:**
  - 25% loads
  - 10% stores
  - 11% branches
  - 2% jumps
  - 52% R-type
- **Suppose:**
  - 40% of loads used by next instruction
  - 25% of branches mispredicted
- **All jumps flush next instruction**
- **What is the average CPI?**

Pipelined Performance Example Solution

- **Load/Branch CPI = 1 when no stall/flush, 2 when stall/flush. Thus:**
  - $CPI_{lw} = 1(0.6) + 2(0.4) = 1.4$ *Average CPI for load*
  - $CPI_{beq} = 1(0.75) + 2(0.25) = 1.25$ *Average CPI for branch*
- **And**
  - ***Average CPI*** =

Pipelined Performance Example Solution

- **Load/Branch CPI = 1 when no stall/flush, 2 when stall/flush. Thus:**
  - CPI_{lw} = 1(0.6) + 2(0.4) = 1.4 — *Average CPI for load*
  - CPI_{beq} = 1(0.75) + 2(0.25) = 1.25 — *Average CPI for branch*

- **And**
  - ***Average CPI*** = (0.25)(1.4) + *load*
    (0.1)(1) + *store*
    (0.11)(1.25) + *beq*
    (0.02)(2) + *jump*
    (0.52)(1) *r-type*

    = **1.15**

Pipelined Performance

- There are 5 stages, and 5 different timing paths:

T_c = max {

$t_{pcq} + t_{mem} + t_{setup}$	*fetch*
$2(t_{RFread} + t_{mux} + t_{eq} + t_{AND} + t_{mux} + t_{setup})$	*decode*
$t_{pcq} + t_{mux} + t_{mux} + t_{ALU} + t_{setup}$	*execute*
$t_{pcq} + t_{memwrite} + t_{setup}$	*memory*
$2(t_{pcq} + t_{mux} + t_{RFwrite})$	*writeback*

}

- The operation speed ***depends*** on the ***slowest operation***
- Decode and Writeback use register file and have only half a clock cycle to complete, that is why there is a 2 in front of them

Pipelined Performance Example

Element	Parameter	Delay (ps)
Register clock-to-Q	t_{pcq_PC}	30
Register setup	t_{setup}	20
Multiplexer	t_{mux}	25
ALU	t_{ALU}	200
Memory read	t_{mem}	250
Register file read	t_{RFread}	150
Register file setup	$t_{RFsetup}$	20
Equality comparator	t_{eq}	40
AND gate	t_{AND}	15
Memory write	$T_{memwrite}$	220
Register file write	$t_{RFwrite}$	100

$$T_c = 2(t_{RFread} + t_{mux} + t_{eq} + t_{AND} + t_{mux} + t_{setup})$$
$$= 2[150 + 25 + 40 + 15 + 25 + 20] \text{ ps}$$
$$= 550 \text{ ps}$$

Pipelined Performance Example

- **For a program with 100 billion instructions executing on a pipelined MIPS processor:**
  - CPI = 1.15
  - T_c = 550 ps

- **Execution Time** $= (\# \text{ instructions}) \times \text{CPI} \times T_c$
  $= (100 \times 10^{9})(1.15)(550 \times 10^{-12})$
  $= 63$ **seconds**

Performance Summary for MIPS arch.

Processor	Execution Time (seconds)	Speedup (single-cycle is baseline)
Single-cycle	95	1
Multicycle	133	0.71
Pipelined	63	1.51

- **Fastest of the three MIPS architectures is *Pipelined.***
- **However, even though we have 5 fold pipelining, it is not 5 times faster than single cycle.**

Questions to Ponder

- What is the role of the hardware vs. the software in data dependence handling?
  - Software based interlocking
  - Hardware based interlocking
  - Who inserts/manages the pipeline bubbles?
  - Who finds the independent instructions to fill "empty" pipeline slots?
  - What are the advantages/disadvantages of each?
    - Think of the performance equation as well

Questions to Ponder

- What is the role of the hardware vs. the software in the order in which instructions are executed in the pipeline?
  - Software based instruction scheduling → static scheduling
  - Hardware based instruction scheduling → dynamic scheduling

- How does each impact different metrics?
  - Performance (and parts of the performance equation)
  - Complexity
  - Power consumption
  - Reliability
  - …

More on Software vs. Hardware

- Software based scheduling of instructions → static scheduling
  - Compiler orders the instructions, hardware executes them in that order
  - Contrast this with dynamic scheduling (in which hardware can execute instructions out of the compiler-specified order)
  - How does the compiler know the latency of each instruction?

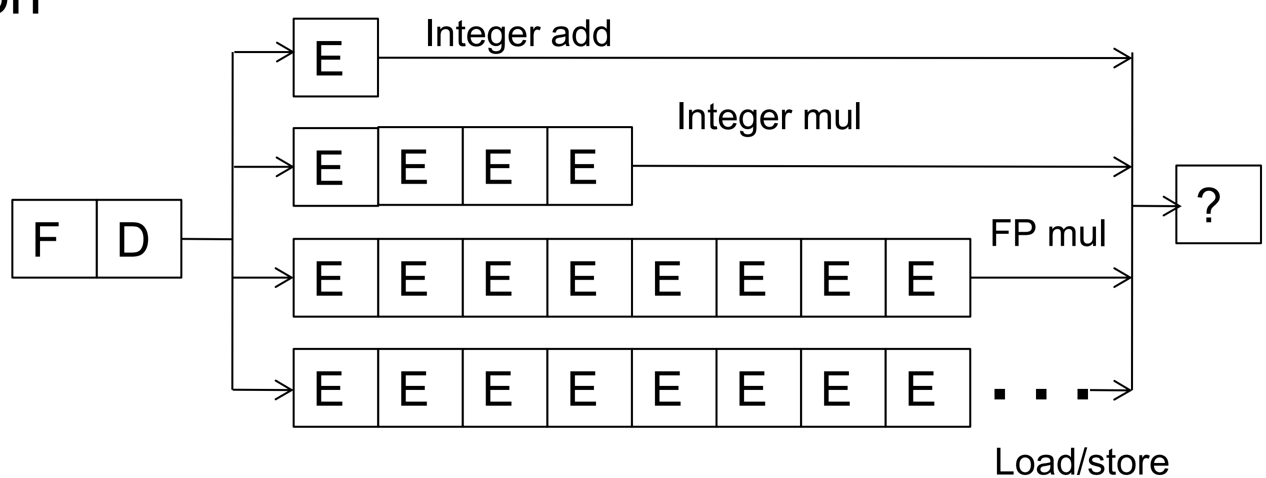
- What information does the compiler not know that makes static scheduling difficult?
  - Answer: Anything that is determined at run time
    - Variable-length operation latency, memory addr, branch direction

- How can the compiler alleviate this (i.e., estimate the unknown)?
  - Answer: Profiling

Pipelining and Precise Exceptions: Preserving Sequential Semantics

Multi-Cycle Execution

- Not all instructions take the same amount of time for "execution"
- Idea: Have multiple different functional units that take different number of cycles
  - Can be pipelined or not pipelined
  - Can let independent instructions start execution on a different functional unit before a previous long-latency instruction finishes execution



Issues in Pipelining: Multi-Cycle Execute

- Instructions can take different number of cycles in EXECUTE stage
  - Integer ADD versus FP MULtiply

FMUL R4 ← R1, R2	F	D	E	E	E	E	E	E	E	E	W				
ADD R3 ← R1, R2		F	D	E	W										
			F	D	E	W									
				F	D	E	W								
FMUL R2 ← R5, R6					F	D	E	E	E	E	E	E	E	E	W
ADD R7 ← R5, R6						F	D	E	W						
							F	D	E	W					

  - What is wrong with this picture in a Von Neumann architecture?
    - Sequential semantics of the ISA NOT preserved!
    - What if FMUL incurs an exception?

Exceptions vs. Interrupts

- Cause
  - Exceptions: internal to the running thread
  - Interrupts: external to the running thread
- When to Handle
  - Exceptions: when detected (and known to be non-speculative)
  - Interrupts: when convenient
    - Except for very high priority ones
      - Power failure
      - Machine check (error)
- Priority: process (exception), depends (interrupt)
- Handling Context: process (exception), system (interrupt)

Precise Exceptions/Interrupts

- The architectural state should be consistent (precise) when the exception/interrupt is ready to be handled

1. All previous instructions should be completely retired.

2. No later instruction should be retired.

Retire = commit = finish execution and update arch. state

Checking for and Handling Exceptions in Pipelining

- When the oldest instruction ready-to-be-retired is detected to have caused an exception, the control logic
  - Ensures architectural state is precise (register file, PC, memory)
  - Flushes all younger instructions in the pipeline
  - Saves PC and registers (as specified by the ISA)
  - Redirects the fetch engine to the appropriate exception handling routine

Why Do We Want Precise Exceptions?

- Semantics of the von Neumann model ISA specifies it
  - Remember von Neumann vs. Dataflow

- Aids software debugging

- Enables (easy) recovery from exceptions

- Enables (easily) restartable processes

- Enables traps into software (e.g., software implemented opcodes)

Ensuring Precise Exceptions in Pipelining

- Idea: Make each operation take the same amount of time

FMUL R3 ← R1, R2	F	D	E	E	E	E	E	E	E	E	W						
ADD R4 ← R1, R2		F	D	E	E	E	E	E	E	E	E	W					
			F	D	E	E	E	E	E	E	E	E	W				
				F	D	E	E	E	E	E	E	E	E	W			
					F	D	E	E	E	E	E	E	E	E	W		
						F	D	E	E	E	E	E	E	E	E	W	
							F	D	E	E	E	E	E	E	E	E	W

- Downside
  - Worst-case instruction latency determines all instructions' latency
  - What about memory operations?
  - Each functional unit takes worst-case number of cycles?

Solutions

- Reorder buffer

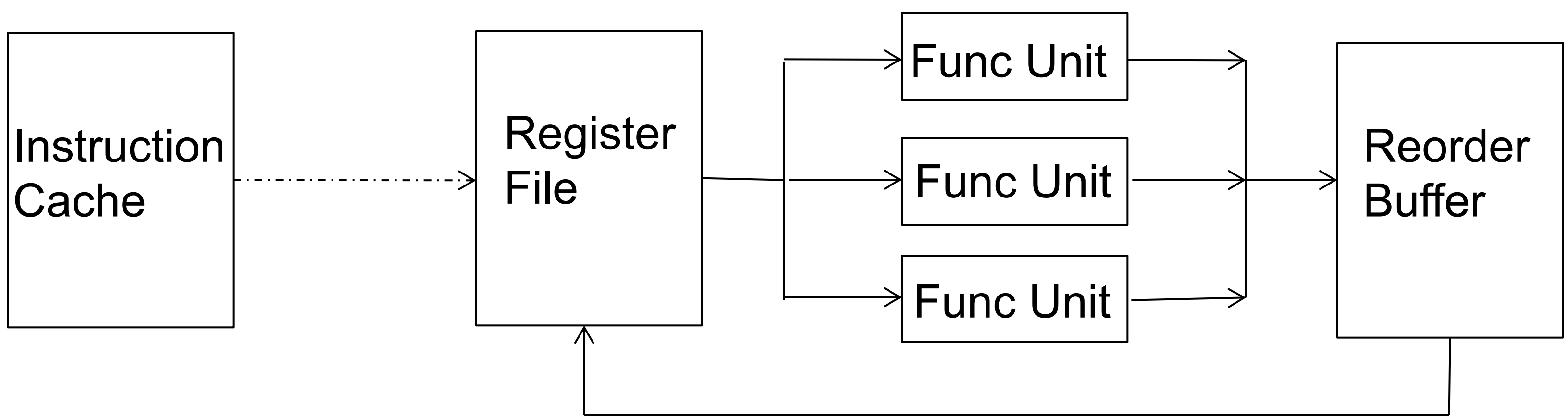
- History buffer
- Future register file
- Checkpointing

We will not cover these

- Suggested reading
  - Smith and Plezskun, "Implementing Precise Interrupts in Pipelined Processors," IEEE Trans on Computers 1988 and ISCA 1985.

Solution I: Reorder Buffer (ROB)

- Idea: Complete instructions out-of-order, but reorder them before making results visible to architectural state
- When instruction is decoded it reserves the next-sequential entry in the ROB
- When instruction completes, it writes result into ROB entry
- When instruction oldest in ROB and it has completed without exceptions, its result moved to reg. file or memory



What's in a ROB Entry?

V	DestRegID	DestRegVal	StoreAddr	StoreData	PC	Valid bits for reg/data + control bits	Exception?

- Everything required to:
  - correctly reorder instructions back into the program order
  - update the architectural state with the instruction's result(s), if instruction can retire without any issues
  - handle an exception/interrupt precisely, if an exception/interrupt needs to be handled before retiring the instruction
- Need valid bits to keep track of readiness of the result(s) and find out if the instruction has completed execution

Reorder Buffer: Independent Operations

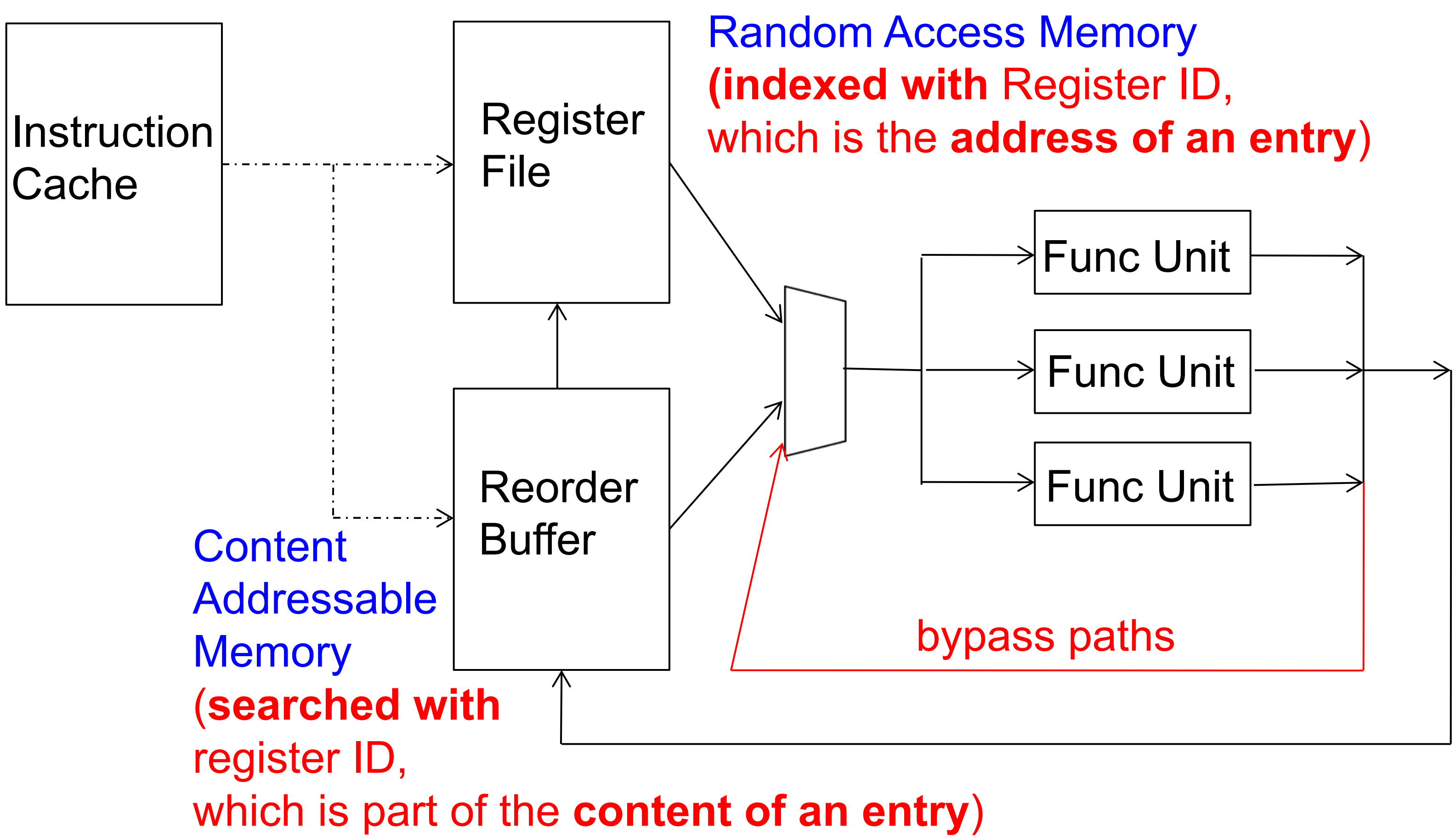
- Result first written to ROB on instruction completion
- Result written to register file at commit time

F	D	E	E	E	E	E	E	E	E	R	W						
	F	D	E	R								W					
		F	D	E	R								W				
			F	D	E	R								W			
				F	D	E	E	E	E	E	E	E	E	R	W		
					F	D	E	R								W	
						F	D	E	R								W

- What if a later operation needs a value in the reorder buffer?
  - Read reorder buffer in parallel with the register file. How?

Reorder Buffer: How to Access?

- A register value can be in the register file, reorder buffer, (or bypass/forwarding paths)



Simplifying Reorder Buffer Access

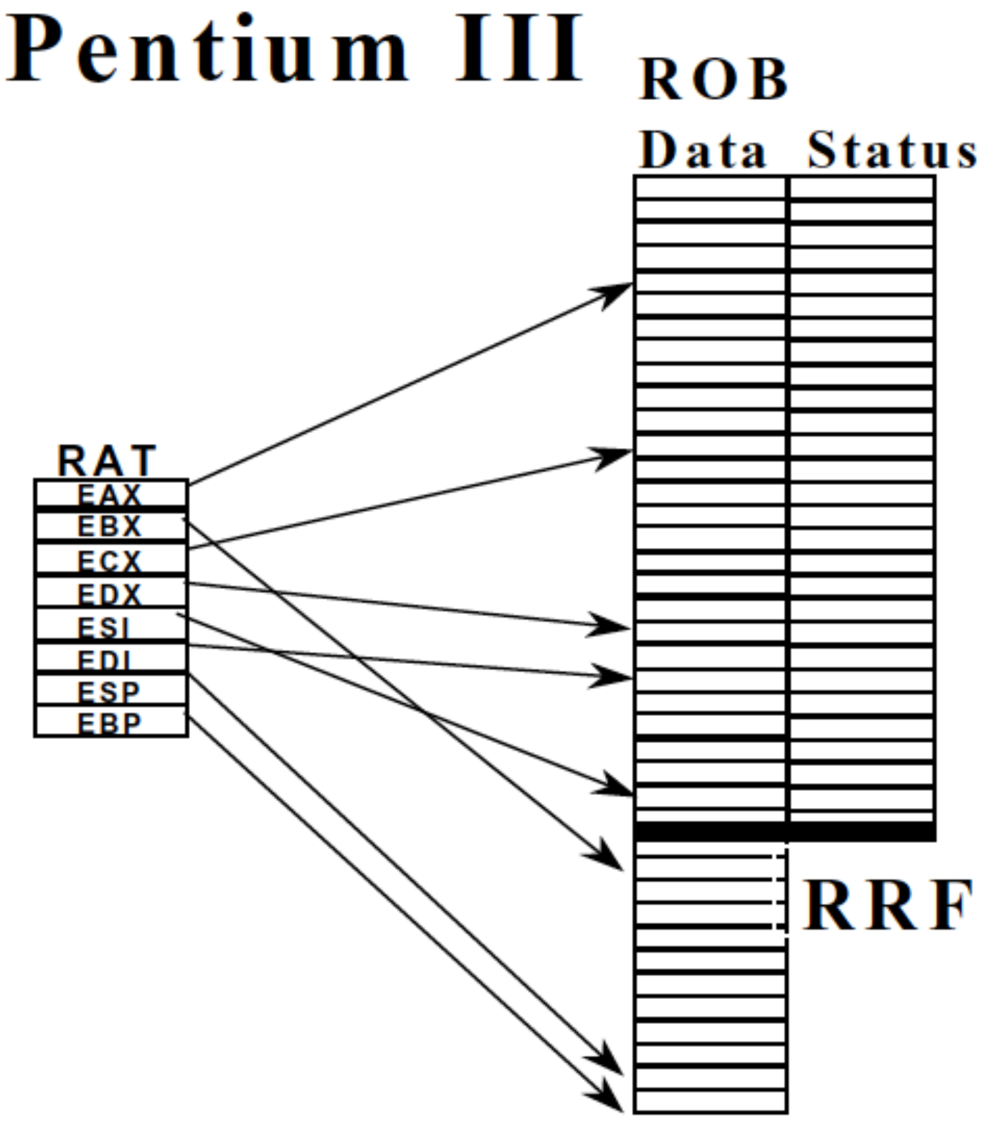
- Idea: Use indirection

- Access register file first (check if the register is valid)
  - If register not valid, register file stores the ID of the reorder buffer entry that contains (or will contain) the value of the register
  - Mapping of the register to a ROB entry: Register file maps the register to a reorder buffer entry if there is an in-flight instruction writing to the register

- Access reorder buffer next

- Now, reorder buffer does not need to be content addressable

Reorder Buffer in Intel Pentium III



Boggs et al., "The Microarchitecture of the Pentium 4 Processor," Intel Technology Journal, 2001.

Important: Register Renaming with a Reorder Buffer

- Output and anti dependencies are not true dependencies
  - WHY? The same register refers to values that have nothing to do with each other
  - **They exist due to lack of register ID's (i.e. names) in the ISA**
- The register ID is **renamed** to the reorder buffer entry that will hold the register's value
  - Register ID → ROB entry ID
  - Architectural register ID → Physical register ID
  - After renaming, ROB entry ID used to refer to the register

- This eliminates anti- and output- dependencies
  - Gives the illusion that there are a large number of registers

Renaming Example

- Assume
  - Register file has a pointer to the reorder buffer entry that contains or will contain the value, if the register is not valid
  - Reorder buffer works as described before

- Where is the latest definition of R3 for each instruction below in sequential order?

  LD R0(0) → R3

  LD R3, R1 → R10

  MUL R1, R2 → R3

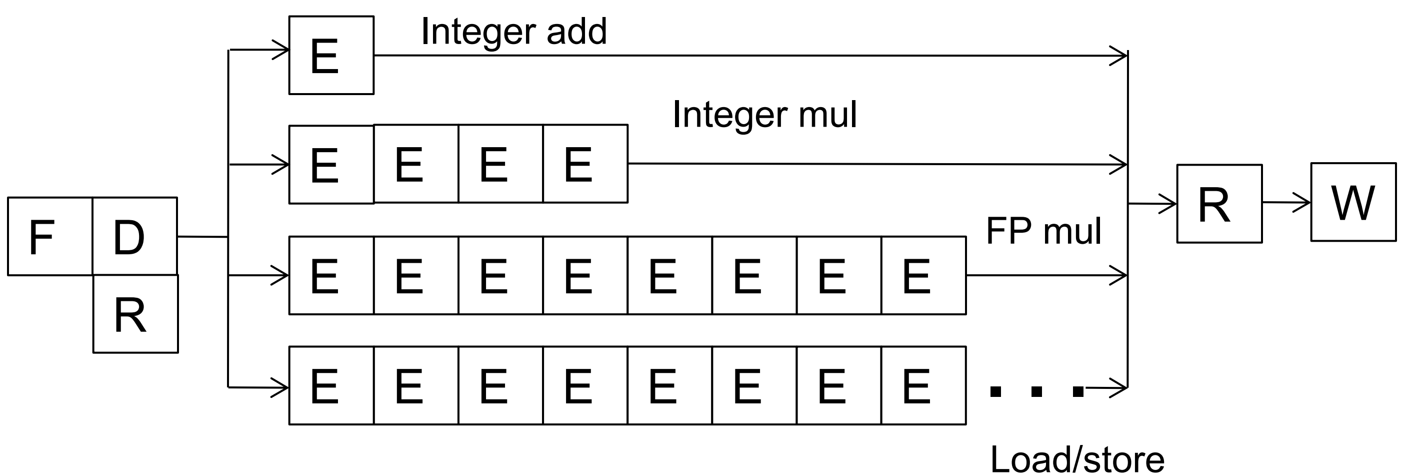
  MUL R3, R4 → R11

  ADD R5, R6 → R3

  ADD R7, R8 → R12

In-Order Pipeline with Reorder Buffer

- Decode (D): Access regfile/ROB, allocate entry in ROB, check if instruction can execute, if so **dispatch** instruction
- Execute (E): Instructions can complete out-of-order
- Completion (R): Write result to reorder buffer
- Retirement/Commit (W): Check for exceptions; if none, write result to architectural register file or memory; else, flush pipeline and start from exception handler
- In-order dispatch/execution, out-of-order completion, in-order retirement



Reorder Buffer Tradeoffs

- Advantages
  - Conceptually simple for supporting precise exceptions
  - Can eliminate false dependences

- Disadvantages
  - Reorder buffer needs to be accessed to get the results that are yet to be written to the register file
    - CAM or indirection → increased latency and complexity

- Other solutions aim to eliminate the disadvantages
  - History buffer
  - Future file
  - Checkpointing

We will not cover these

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