A Synthetic Graph Toolbox for Benchmarking the Grid of Processing Cells

Anson Fong, Yutong Wang, Rainer Dömer

Technical Report CECS-24-03
June 5, 2024

Center for Embedded and Cyber-Physical Systems
University of California, Irvine
Irvine, CA 92697-2620, USA
(949) 824-8919
ansonhf@uci.edu
http://www.cecs.uci.edu
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Abstract

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Classical computer architectures are based on the concept of utilizing a large system memory to support communication between computational cores. To remedy the memory access bottleneck that limits optimization of such systems, the Grid of Processing Cells (GPC) has been proposed as a highly scalable multicore alternative that maximizes the benefits of parallelization. This work introduces a toolbox that aims to immensely improve benchmarking productivity for the GPC model. The included tools generate random task graphs based on configurable constraints, as well as their corresponding SystemC timing simulations, C++ executables, and abstract syntax trees. The synthetic examples can be used to test the feasibility and optimization of mapping data flow applications to the GPC architecture.

1 Introduction

In most computer systems, strategies for hardware optimization have been centered around increasing clock speeds, processor counts, and cache sizes. Despite the development of sophisticated memory hierarchies, parallel processing, and other specialized solutions, most modern designs still rely on large, slow central memory modules to support its processor cores, as illustrated in Figure 1. The ever increasing memory access complexity and contention forms the memory access bottleneck, which becomes the limiting factor in optimization.

The Grid of Processing Cells (GPC) [3] has been proposed as an alternative design to maximize parallelization benefits by mitigating the memory access bottleneck. The GPC architecture uses a “checkerboard” pattern tiled by alternating processor and memory modules, as shown in Figure 2. The design allows adjacent cores to directly access neighboring memory modules, reducing the risk of memory access contention. Optimization of parallelization on such an architecture becomes limited only by the mapping of tasks onto the checkerboard.

1.1 Problem Definition

To take full advantage of this architecture, it becomes necessary to develop a pipeline for mapping applications to the GPC. Various projects in the past have manually mapped applications to the GPC architecture. These projects include an APNG encoder [4], a JPEG encoder [1] (Figure 3), a Mandelbrot Set Visualizer [5] (Figure 4), and a Canny Edge Detec-
Despite observing speedups when evaluating the execution performance of applications mapped onto the GPC, each project commented on the impracticality of manually mapping applications onto the GPC checkerboard. Thus, in the interest of accelerating benchmarking productivity and extending the architecture’s use cases, an automatic GPC Compiler (GPCC) must handle the mapping of applications onto the GPC.

The tools developed in this work seek to contribute toward the development of the GPCC by performing three tasks: synthetic graph generation, outputting SystemC simulation source code, and producing formatted inputs for the GPCC. This toolbox will help validate the feasibility of mapping configurable application structures, as well as offer a baseline for simulation comparison. In this report, we will refer to the collection of included tools as the Synthetic Graph Toolbox (SGT).

At the time of this report, the GPCC (Figure 6) requires input C++ applications to conform to a specific set of syntax and structure rules, which we will call Guided C++ (GCPP). This includes requiring that all functions be contained within a class called a Module. Inter-function communication must be completed by interacting through Channels. In this form, the GPC parser will be able to generate a GPC mapping for the application using SystemC, directly utilizing the modules and channels to represent hardware. The GPCC also requires an Application Task Graph (ATG, a modified variant of the abstract syntax tree data structure) for mapping input applications. The ATG contains information describing the control flow and dependencies within the application, as well as the local variable names and implemented functionality.
Figure 5: The SGT Toolbox
2 The SGT Executables

In the following sections, we will discuss the implementation and operation of each tool in the SGT, as well as the applications of their generated outputs.

2.1 Graph Generator

The graph generator `gg.cpp` randomly constructs directed acyclic graphs based on constraints specified in the user configuration file. The graph is represented using the vector and set data structures, storing nodes and edges respectively. Along with the ID of the nodes, we also keep track of the depth and number of outgoing edges, properties that will be useful when constructing SystemC models later. The generator constructs the graph in three stages, as shown in Figure 7.

2.1.1 Generator Algorithm

First, a primary path is created by initializing $H$ nodes and connecting them to form a singly linked list, where $H$ is the height of the graph specified in the configuration file. Next, nodes are appended randomly to the non-terminal nodes along the primary path, until the graph contains all $N$ user specified nodes. The generator is capable of generating graphs with singular and non-singular outputs, meaning the graph may terminate at one node or contain multiple terminal nodes. Should the user specify for singular output, the generator will connect appended nodes to the terminal primary node to avoid hanging nodes.

In the final stage, additional edges are randomly formed between random nodes. The generator iterates through all nodes, where it may randomly form an edge between it and a random destination node. Each node has a $3\%$ chance of forming this additional edge, by default. This probability setting can be configured by editing the threshold variable within the graph generator’s source code.

These steps ensure a random graph is generated within the constraints specified within the configuration file. The completed graph is written to a text file, which will be used by the other tools within the SGT. The user should note that the graph generator will fail if the constraints specified in the configuration file do not describe a plausible graph.

2.1.2 Input/Output

The configuration file, `gg.config`, allows for selecting a node count, a height (maximum length from
source node to terminal node or nodes), maximum edge count per node, and singular/non-singular output. A minimum of 2 nodes is required to produce output from the graph generator, given the height and maximum edge parameters always describe a plausible graph. The singular output setting is active high; setting it to 0 will yield multiple terminal nodes and setting it to 1 will yield a single terminal node.

The output text file will always specify the number of nodes in the graph on the first line, and then list the connections at each node. Each node is denoted as \( V_x[d] \), where \( x \) is the node’s ID and \( d \) is the node’s depth. A node’s depth is defined by the number of edges away it is from the source node, \( V_0 \).

### 2.1.3 Example Configuration

```plaintext
// CONFIGURATION FILE (for gg.cpp)
Nodes (min 2): 5
Height: 3
Maximum edges: 3
Singular output [0/1]: 1
```

Figure 8: Graph Configuration File

Figure 8 shows an example configuration in the configuration file, describing a graph with five nodes, maximum height of three, maximum of three edges per node, and a single terminal node. The graph generator first connects nodes \( V_0, V_1, \) and \( V_2 \) in a singly linked list, completing the primary path of the graph. Next, in this example, nodes \( V_3 \) and \( V_4 \) are appended to the primary path at random. This example shows both nodes connecting to \( V_0 \). Since the configuration file specifies for singular output, all hanging nodes are connected to the terminal node \( V_2 \). In this example, no additional edges are added. Figure 9 shows the resulting output text file, describing a graph that satisfies all constraints specified in the configuration file.

```
Nodes: 5
V0[0]: V1[1],V3[1],V4[1],
V1[1]: V2[2],
V2[2]:
V3[1]: V2[2],
V4[1]: V2[2],
```

Figure 9: Graph Output Example

### 2.2 SystemC Simulation Generators

The SGT contains two SystemC generators, `writeTLM1.cpp` and `writeTLM2.cpp`, which process the text file produced by the graph generator to generate SystemC simulation models. Each node in the generated task graph represents a function or subtask from some application, which will be assigned to a processor core. Upon conversion to a SystemC simulation, each node becomes a module within a Design-Under-Test (DUT). The two generators differ in how they handle inter-module (inter-function) communication. Both create DUTs and simulate their behavior when connected to Stimulus and Monitor modules.

The TLM1 model (Figure 10(a)) uses channels to represent communication between modules. These channels are implemented using FIFO buses. Each node is represented by a module and has dedicated channels for incoming and outgoing edges, where data is read from and written into. Since the SGT graph generator doesn’t assign any functionality to the nodes within its task graph, a configurable delay is imposed at each node to represent some computation time. This setting can be configured in the TLM configuration file, `TLM.config`, by changing the value next to Delay Factor under TLM1, which is measured in milliseconds. The generator adds code into each module to calculate the distance of the longest path from source to terminal node(s). This output is observable at the Monitor during simulation, by compiling and running the generated graph `TLM1.cpp`.

The TLM2 model (Figure 10(b)) enables a more rigorous model for inter-module communication, requiring modules to read and write data from and into memory modules, with control signals and multiplexers to facilitate parallel access. The implementation for memory modules and muxes can be found in the `lib/TLM2` folder. Nodes must register I/O sockets with memory modules, specifying access signals and addresses. The TLM2 simulation also calculates the distance of the longest path from source to terminal node(s), but utilizes more configurable delay values than TLM1. In the TLM configuration file, `TLM.config`, the memory size, read delay, and write delay of on and off chip memories can be configured. Memory size is measured in bytes, and delays are
measured in nanoseconds. Similarly to TLM1, the artificial computation time can be configured by changing the value next to **Delay Factor** under **TLM2**, which is measured in milliseconds. After compiling and running the generated `graph_TLM2.cpp` simulation, the Monitor will once again display the calculated longest path(s).

![Diagram](image)

(a) TLM1 Model

![Diagram](image)

(b) TLM2 Model

Figure 10: SystemC Model Examples

### 2.2.1 Example SystemC Model Configuration

The TLM generators both parse the text file generated by the graph generator and produce C++ simulation files. Although both TLM1 and TLM2 will support simulation with multiple terminal nodes, only TLM2 utilizes multithreading to read outputs concurrently. Thus, only the TLM2 simulation will report accurate timings at the Monitor.

Using the graph generated in Figure 9 and the configuration file settings in Figure 11, we obtain the simulations shown in Figure 12 and Figure 13. Due to the additional timing settings present in the TLM2 simulation, as well as initialization delays hidden within the source code, the stimulus takes slightly longer to propagate through the DUT and reach the Monitor.

```
// CONFIGURATION FILE (for TLM models)
[TLM1]
-- Delay Factor: 1

[TLM2]
-- Off-Chip Memory Size: 8*1024*1024
-- Off-Chip Read Delay: 100
-- Off-Chip Write Delay: 110
-- On-Chip Memory Size: 4*1024*1024
-- On-Chip Read Delay: 5
-- On-Chip Write Delay: 6
-- Delay Factor: 1
```

Figure 11: TLM Configuration File

### 2.3 Guided C++ Code Generator

To map applications to the GPC using the GPCC format, the input application must be translated into a form that the GPCC can parse. As previously stated, this form is called guided C++, and requires compartmentalizing functions into **Modules** and performing communication through **Channels**. Each **Module** creates a dedicated thread and communicates to other **Modules** by sending data through queues (channels). To perform this translation, the GCPP generator `writeGCPP.cpp` also takes the text file generated by the graph generator as input. The resulting C++ file, `graph.cpp`, contains the necessary functionality to perform the same longest-path calculation that the TLM1 and TLM2 simulations perform, as observed in Figure 14, which also uses the graph in Figure 9. The structure of the outputted `graph.cpp` closely resembles that of the TLM1 simulation (Figure 10(a)). However, the GCPP simulation is stripped of the timing information that SystemC provides.
2.4 ATG Extraction Generator

The GPCC also requires the control flow, dependencies, and functionality of an application’s functions to be extracted from the GCPP file. This data is stored in an Application Task Graph (ATG), a modified variant of an abstract syntax tree. To extract the ATG from the GCPP file generated by the GCPP generator, the ATG extraction generator `writeATG.cpp` parses the GCPP generator’s output and produces a python script, `ATG_parsed.py`. This python script populates an ATG data structure, recording the channels that each Module utilizes and the functional code within each Module. The script prints this information to the terminal when run, as seen in Figure 15 and Figure 16, which uses the GCPP code based on the graph in Figure 9. The GPCC may use the `graph.cpp` file and the data structure created by running `ATG_parsed.py` to attempt creating a GPC mapping for the task graph generated by the graph generator.

The script also generates `graph_unparse.cpp`, which is reconstructed from the ATG, and when run, yields the same output as the `graph.cpp` file generated by the GCPP generator.

2.5 Mapper Generator

The mapper generator `writerMapper.cpp` generates another python script, `mapper.py`, which is responsible for producing a visualization of the generated task graph. The mapper generator also takes the text file generated by the graph generator as input. The generated graphic for the graph in Figure 9 is shown in Figure 17.
<mapperLib.AppTaskGraph object at 0x7f92ff2b6b90>
SOURCE: graph.cpp
HEADER: 5 lines
GPCC: True
MODULES: 12

MODULE V0
  PORT QUEUE_IN<int> input
  PORT QUEUE_OUT<int> V1
  PORT QUEUE_OUT<int> V3
  PORT QUEUE_OUT<int> V4
  THREAD main (detached)
  Code: 11 lines

MODULE V1
  PORT QUEUE_IN<int> V0
  PORT QUEUE_OUT<int> V2
  THREAD main (detached)
  Code: 11 lines

MODULE V2
  PORT QUEUE_IN<int> V1
  PORT QUEUE_IN<int> V3
  PORT QUEUE_IN<int> V4
  PORT QUEUE_OUT<int> output_V2
  THREAD main (detached)
  Code: 17 lines

MODULE V3
  PORT QUEUE_IN<int> V0
  PORT QUEUE_OUT<int> V2
  THREAD main (detached)
  Code: 11 lines

MODULE V4
  PORT QUEUE_IN<int> V0
  PORT QUEUE_OUT<int> V2
  THREAD main (detached)
  Code: 11 lines

MODULE DUT
  PORT QUEUE_IN<int> DataIn
  PORT QUEUE_OUT<int> V2_out
  CHANNEL_INSTANCE QUEUE<int> V0_V1
  CHANNEL_INSTANCE QUEUE<int> V0_V3
  CHANNEL_INSTANCE QUEUE<int> V0_V4
  CHANNEL_INSTANCE QUEUE<int> V1_V2
  CHANNEL_INSTANCE QUEUE<int> V3_V2
  CHANNEL_INSTANCE QUEUE<int> V4_V2
  MODULE_INSTANCE V0 v0(DataIn,V0_V1,V0_V3,V0_V4)
  MODULE_INSTANCE V1 v1(V0_V1,V1_V2)
  MODULE_INSTANCE V2 v2(V1_V2,V3_V2,V4_V2,V2_out)
  MODULE_INSTANCE V3 v3(V0_V3,V3_V2)
  MODULE_INSTANCE V4 v4(V0_V4,V4_V2)
  Code: 2 lines

Figure 15: ATG Extraction Output [Part 1/2]
MODULE DataIn
    PORT QUEUE_IN<int> input
    PORT QUEUE_OUT<int> output
    THREAD main (detached)
    Code: 9 lines

MODULE DataOut
    PORT QUEUE_IN<int> input
    PORT QUEUE_OUT<int> output
    THREAD main (detached)
    Code: 9 lines

MODULE Platform
    PORT QUEUE_IN<int> input
    PORT QUEUE_OUT<int> V2_out
    CHANNEL_INSTANCE QUEUE<int> din_dut(1)
    CHANNEL_INSTANCE QUEUE<int> dut_V2(1)
    MODULE_INSTANCE DataIn din(input,din_dut)
    MODULE_INSTANCE DUT dut(din_dut,dut_V2)
    MODULE_INSTANCE DataOut V2(dut_V2,V2_out)
    Code: 2 lines

MODULE Stimulus
    PORT QUEUE_OUT<int> output
    THREAD main (joinable)
    Code: 7 lines

MODULE Monitor
    PORT QUEUE_IN<int> input_V2
    THREAD main (detached)
    Code: 8 lines

MODULE Top
    CHANNEL_INSTANCE QUEUE<int> stim_plat(1)
    CHANNEL_INSTANCE QUEUE<int> plat_mon_V2(1)
    MODULE_INSTANCE Stimulus stim(stim_plat)
    MODULE_INSTANCE Platform plat(stim_plat,plat_mon_V2)
    MODULE_INSTANCE Monitor mon(plat_mon_V2)
    Code: 2 lines

INSTANCE TREE:
    MODULE_INSTANCE Top top()

FOOTER: 6 lines

Figure 16: ATG Extraction Output [Part 2/2]

Figure 17: Example Graph Visualization
3 Experiments and Results

To test the SGT, each of its tools was tested on a variety of input graphs. Using the TLM configuration from Figure 11, graphs with 5, 10, 25, 50, and 100 nodes were tested, at various heights. Figure 1 displays each graph’s input attributes, the TLM1 output and timing, and the TLM2 output and timing. Figure 2 displays the GPCC simulation output, and the ATG’s reverse engineered simulation output. All of the simulations – TLM1, TLM2, GPCC, and the reverse engineered ATG – retain the input graph’s attributes. Thus, the simulation models may be used as an accurate baseline, and the GPCC and ATG can be used as test cases for the GPCC.

Table 1: SystemC Simulation Results [Part 1/2]

<table>
<thead>
<tr>
<th>Nodes</th>
<th>Height</th>
<th>TLM1</th>
<th>TLM2</th>
</tr>
</thead>
<tbody>
<tr>
<td>5</td>
<td>3</td>
<td>3 at 3ms</td>
<td>3 at 4001770ns</td>
</tr>
<tr>
<td>10</td>
<td>8</td>
<td>8 at 8ms</td>
<td>8 at 9001986ns</td>
</tr>
<tr>
<td>25</td>
<td>20</td>
<td>20 at 20ms</td>
<td>20 at 21002638ns</td>
</tr>
<tr>
<td>50</td>
<td>43</td>
<td>43 at 43ms</td>
<td>43 at 44003723ns</td>
</tr>
<tr>
<td>100</td>
<td>94</td>
<td>94 at 94ms</td>
<td>94 at 95005803ns</td>
</tr>
</tbody>
</table>

Table 2: SystemC Simulation Results [Part 2/2]

<table>
<thead>
<tr>
<th>Nodes</th>
<th>Height</th>
<th>GPCC</th>
<th>ATG Reversed</th>
</tr>
</thead>
<tbody>
<tr>
<td>5</td>
<td>3</td>
<td>3</td>
<td>3</td>
</tr>
<tr>
<td>10</td>
<td>8</td>
<td>8</td>
<td>8</td>
</tr>
<tr>
<td>25</td>
<td>20</td>
<td>20</td>
<td>20</td>
</tr>
<tr>
<td>50</td>
<td>43</td>
<td>43</td>
<td>43</td>
</tr>
<tr>
<td>100</td>
<td>94</td>
<td>94</td>
<td>94</td>
</tr>
</tbody>
</table>

Table 3: Makefile Commands

<table>
<thead>
<tr>
<th>Makefile Command</th>
<th>Function</th>
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</thead>
<tbody>
<tr>
<td>clean</td>
<td>Remove all generated files</td>
</tr>
<tr>
<td>gg</td>
<td>Runs graph generator</td>
</tr>
<tr>
<td>testTLM1</td>
<td>Produces TLM1 model</td>
</tr>
<tr>
<td>testTLM2</td>
<td>Produces TLM2 model</td>
</tr>
<tr>
<td>testGCPP</td>
<td>Produces GCPP file</td>
</tr>
<tr>
<td>mapper</td>
<td>Produces visual</td>
</tr>
<tr>
<td>ATG</td>
<td>Extracts ATG</td>
</tr>
</tbody>
</table>

4 Conclusion

Various application have been manually mapped onto the GPC architecture in an effort to benchmark its design. Despite the significant speedups observed in these experiments, manually mapping applications onto the GPC checkerboard is impractical. This has led to the need to develop a compiler, GPCC, for automatically mapping arbitrary data flow applications onto the GPC. To quickly evaluate the feasibility of mapping various application structures onto the GPC using the GPCC, the SGT can be used to generate graphs, produce baseline simulations, and format GPCC inputs.

Furthermore, the SGT can assist the GPCC in becoming operational by automatically producing large quantities of test cases, streamlining testing and debugging. With a functioning GPCC, applications can begin taking full advantage of the highly parallel GPC architecture.

References


