

Embedded System Design and Modeling

EE382V, Fall 2011

Lab #2 Exploration

Part (a) due: October 17, 2011 (11:59pm)
Part (b) due: October 24, 2011 (11:59pm)
Part (c) due: October 31, 2011 (11:59pm)
Part (d) due: November 7, 2011 (11:59pm)

Instructions:

- Please submit your solutions via Blackboard. Submissions should include a lab report (single PDF) and a single Zip or Tar archive with the source and supplementary files (code should include a README and has to be compilable and simulatable by running 'make' and 'make test', respectively).
- You are allowed to work in teams of up to three people and you are free to switch partners between labs and the project. Please submit one solution per team.

Digital Camera Design Space Exploration

The purpose of this lab is to perform design space exploration and to bring the digital camera example down to an (optimal) implementation using the System-On-Chip Environment (SCE).

SCE is installed next to the SpecC tools on the ECE LRC Linux servers. Instructions for accessing and setting up SCE and the tutorial are posted on the class website:

http://www.ece.utexas.edu/~gerstl/ee382v_f11/docs/SCE_setup.pdf

Again, once logged in (e.g. remotely via `ssh -X` and make sure to have an X11 server running locally), you need to setup the environment:

```
module load sce
```

SCE comes with an extensive tutorial and it is highly recommended to go through the first part of the tutorial that demonstrates SCE's system exploration and synthesis capabilities on a GSM Vocoder design example. The tutorial instructions are available as part of the SCE installation (see below) and online at:

<http://www.cecs.uci.edu/~cad/publications/tech-reports/2003/TR-03-41.tutorial.pdf>

Note, however, that the tutorial is based on an older version of SCE. As such, some steps have changed and communication design steps have been expanded. A list of errata with all modified and added tutorial steps necessary for the current SCE version is available on the class website:

http://www.ece.utexas.edu/~gerstl/ee382v_f10/docs/SCE_Tutorial_Errata.pdf

To run the tutorial, setup a local working directory for the tutorial demo, launch the SCE GUI and follow the steps of the tutorial document:

```
mkdir demo
cd demo
setup_demo
(open SCE_Tutorial/sce-tutorial.pdf or browse SCE_Tutorial/html/)
(open SCE_Tutorial_Errata.pdf, see above)
sce &
```

Go through the tutorial up to and including Section 3.

We are now ready to load the digital camera specification model into SCE and start the analysis, exploration and refinement process. We start from the SpecC code that you developed as a result of Lab #1. A reference solution can be found under:

`/home/projects/courses/fall_11/ee382v_17190/digicam.tar.gz`

(a) Profile, analyze and estimate the digicam specification model:

1. Open SCE in the digital camera directory and create a new project “digicam.sce” (Project→New, Project→SaveAs...). Adjust the simulator and compiler options as needed. Set the simulation command to
`/usr/bin/time ./%e && diff -s test_1.jpg goldgen.jpg`
 Set the compiler verbosity level to 3 and the warning level to 2.
2. Import the *digicam.sc* specification model into SCE and add it to the project. Rename the model in the project window to *DigicamSpec*.
3. Compile and simulate the model to validate its correctness.
4. Browse the graphical hierarchy chart. Expose all levels of hierarchy and submit a printout of the chart of the complete specification model (Window→Print... to file *DigicamSpec.ps*).
5. Profile (Validation→Profile) the model and generate the bar graph for the raw Computation profile of all behaviors in the *JpegEncoder* part of the design. Submit a printout of the computation graph (Window→Print... to file *DigicamRawProfile.ps*).
6. Allocate a single PE of *ARM7_TDMI* type and a single PE of *HW_Standard* type, using default parameters (100MHz clock frequency). Reanalyze (Validation→Analyze) the design and generate the bar graph for the HW/SW Computation profile of all behaviors in the *JpegEncoder* part of the design. Submit a printout of the computation graph (Window→Print... to file *DigicamSpecProfile.ps*).

(b) We are now ready to go through the computation (architecture and scheduling) exploration and refinement process. The goal is to find an optimal realization on a system architecture consisting of up to three ARM processors or hardware accelerators:

1. Allocate two custom hardware PEs of *HW_Virtual* type and name them *CCD* and *FLSH*. Those two custom hardware blocks are placeholders for the controllers implementing the I/O with the external CCD sensor and flash memory. As such, map the *ReadBlock* and *WriteBlock* behaviors onto the *CCD* and *FLSH* PEs, respectively.
2. Enable the channel view (Synthesis→Show Channels) and map the *dctin* and *dataout* input and output queues at the *Design* level into the *CCD* and *FLSH* PEs, respectively. This is necessary because we want to have the two I/O blocks implement the dedicated input and output buffers associated with the queues. In general, mapping a complex channel into a PE means that the channel will result in a specific implementation being synthesized as part of that PE. Unmapped complex channels, on the other hand, will simply be resolved into their basic elements without any guarantees about a particular buffer realization, for example.
3. Allocate between 1 and 3 PEs of *ARM7_TDMI* or *HW_Standard* type (with default parameters, i.e. 100MHz clock frequency) and explore possible mapping options of *JpegEncoder* behaviors onto 1, 2, or 3 PEs. Make sure to reprofile and reanalyze the

design (Validation→Evaluate) every time you change the allocation or mapping. Perform architecture refinement for every feasible design alternative.

4. Explore various feasible scheduling strategies for each allocated ARM processor in each architecture alternative. You can choose between static and round-robin or priority-based dynamic scheduling (with various task priority assignments) of parallel behaviors mapped to the same PE. Note that you should not schedule (i.e. select *None* under dynamic scheduling) ARM processors with only one mapped behavior. Do not schedule any of the I/O hardware units (*CCD* or *FLSH*). Perform scheduling refinement for every feasible design alternative.
 5. Compile and simulate all generated scheduled architecture models. Record the simulated encoding times for each alternative and plot the design space as points in an encoding time vs. cost graph. Assume that an ARM PE and a hardware accelerator PE have a cost of 100 and 150, respectively. What is the best design?
- (c) Identify at least three promising candidate architectures. We can then go into the communication design (network exploration and communication synthesis) process to synthesize the best designs down to a TLM and PAM realization:
1. Open network allocation to define the overall network topology. Busses for each ARM processor in the system should already be pre-allocated and ARM processors should be pre-connected as masters on their respective busses. Connect the *CCD* and *FLSH* hardware PEs as slaves on the same bus as the ARM processor running their direct communication partners (i.e. *Dct* and *Huff* behaviors, respectively). Note that “slave0” connectivity is reserved by the ARM processor itself and should never be used.
 2. Connect any hardware accelerators as masters, slaves or masters & slaves to any necessary busses. As an alternative to communication over the *AHB* busses, you can freely allocate *DblHndShkBus* instances for separate, dedicated connection between any custom hardware blocks (including the I/O blocks *CCD* or *FLSH*).
 3. If there is more than one ARM (and hence more than one bus) in the system, allocate transducer CEs of *T_Custom* type to bridge and connect busses as necessary (where transducers are slaves on each bus they connect to). Note that transducers by default only have one port but additional ports can be created by right-clicking on the transducer name in the Connectivity tab and selecting Add port....
 4. Perform network refinement and explore different custom packet sizes. By default, each packet going through a transducer can only hold 1 byte. An increased packet size can reduce communication overhead if larger blocks of data are transferred over any transducers in the design. What is the optimal packet size (and why)?
 5. Assign the link parameters for each channel on each bus. You can freely choose the interrupt/synchronization scheme. However, due to the mux-based architecture of the ARM/AMBA AHB bus being used, addresses need to be assigned to match the slave connectivity. Specifically, channels served by a particular “slave*N*” have to be assigned a bus address in the range between $0 \times N0000000 - 0 \times Nffffff$ (otherwise, you will see a deadlock in the PAM simulation). Note that right-clicking into the link parameter dialog and selecting Autofill addresses... should automatically assign proper default addresses.

6. Perform communication refinement to generate both a transaction-level and pin-accurate model of each design. Compile and simulate each model to record the final encoding delays. How much percent communication overhead does each design have?
 7. Browse the hierarchy (View→Chart) and source (View→Source) of one of the generated models. Specifically, take a look at the model of an ARM processor that SCE inserts. Can you identify the model of the interrupt controller, the modeling of processor suspension and interrupt handling in the processor core, and the OS model? Compare the generated models to the manually refined ones you develop in Homework 3. Other than the processor model, what differences can you make out?
- (d) In the final step, we will synthesize the final software binaries for all ARM target processor in our selected candidate designs. To validate final software execution, we will then run the binaries on an instruction-set simulation (ISS) based virtual platform model of each design:
1. We will use a uCOS-II real-time operating system (RTOS) for each ARM in the system. uCOS only supports priority scheduling. As such, make sure that all ARM processors in your candidate designs either use priority-based dynamic scheduling or do not use an OS at all (i.e. have *None* selected). In the former case, make sure that all tasks have unique priorities assigned (required by uCOS).
 2. Select Synthesis→C Code Generation to perform backend software synthesis for each ARM processor in your design. In the dialog, select the ARM processor you want to synthesize and use the default parameters for cross-compiler and target OS. Generate an output model with ISS reintegration each. You can choose between a fully cycle-accurate SWARM ISS or a fast functional OVP ISS with only rough timing. Generate simulations with both types of ISSs and record the differences in simulation times and simulated encoding delays. Repeat C code generation until all ARM processors in the design have been replaced with their reintegrated ISS models.
 3. Before we can simulate the software code, we need to cross-compile the generated source code into a final target binary. Change into each subdirectory with generated code and compile the executable:

```
cd ARMx
make
```
 4. Compile and simulate the design. The code will now run the real binary in an instruction-accurate simulator for the ARM processor(s). You might see some IRQ messages flying by as the ISS is running, but in the end the simulation should stop after some time when the pictures are encoded. Congratulations, we achieved a full-system co-simulation of the actual target software binary together with its surrounding hardware for the complete SoC! Plot the final cost vs. performance for each alternative in a design space graph similar to (b)5. Compare the final encoding times to the previous PAM simulation result, how much differences are there?

Submit a lab report that documents all your steps and includes a discussion and analysis of your results and observations. Record and document the changes and trends in model complexities (File→Statistics), simulation runtimes and simulated encoding delays between different steps and models in the design process. Assuming that a SWARM simulation provides cycle-accurate results, show the tradeoffs in simulation speed vs. accuracy of different design models. What conclusions can you draw?

Finally, what is the optimal architecture, and why is it better than others? Explain and discuss the differences in performance you see between different designs.

Bonus for extra credit: given free reign, can you come up with a better design, e.g. by making modifications to the input specification model or by changing the clock frequency of custom hardware accelerators (where hardware cost is 1.5 times the frequency in MHz)?