HiPEAC 2020 20-22 January, 2020, Bologna, Italy



#### CERBERO H2020 Project – Tutorial: Design Flow for Heterogeneous Embedded Computing Infrastructures

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Horizon 2020 European Union funding for Research & Innovation

• Here is a Martian robot





- Here is a Martian robot
  - it has wheels, a robotic arm, many sensors, and a complex control and computing system

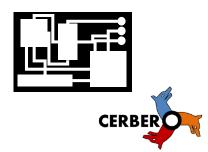


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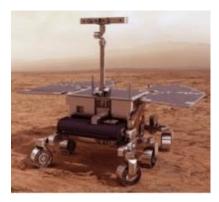




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- Here is what can happen to this robot

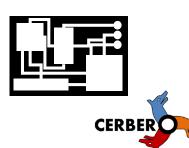


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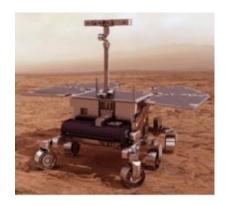




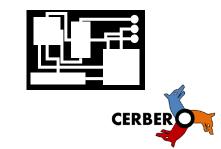
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- Here is what can happen to this robot
  - one of its cameras can be occluded



**∳-**))







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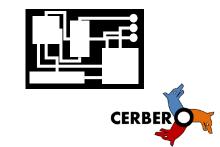
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  - one of its cameras can be occluded
  - one of its wheels can be blocked



**₩-)**)







#### • Here is a Martian robot

- it has wheels, a robotic arm, many sensors, and a complex control and computing system
- Here is what can happen to this robot
  - one of its cameras can be occluded
  - one of its wheels can be blocked
  - one **arm** segment can be stuck

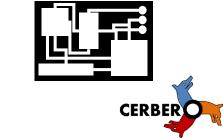


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- it has wheels, a robotic arm, many sensors, and a complex control and computing system
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  - one **arm** segment can be stuck
  - one **motor** can overheat



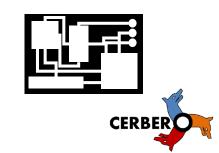
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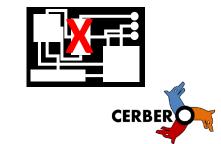
#### • Here is a Martian robot

- it has wheels, a robotic arm, many sensors, and a complex control and computing system
- Here is what can happen to this robot
  - one of its cameras can be occluded
  - one of its wheels can be blocked
  - one arm segment can be stuck
  - one **motor** can overheat
  - on **processing** itself, a region of hardware can be temporarily or permanently unavailable
    - in particular because of ionizing particles











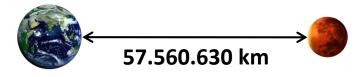
- How do we resume the mission in case of problems?
  - or at least use **remaining robot capacities** for future operations?





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- By the way, radio-controlling is not feasible
  - light return trip to earth is 9 minutes so ...



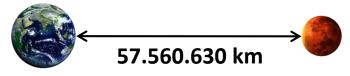




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  - light return trip to earth is 9 minutes so ...
- Proposition
  - Self-adaptation support and CERBERO tooling
  - HW/SW reconfiguration for reliability and performance









## **Ultimate Goal: Self-Adaptation Support**

Self-adaptation: *runtime* action *changing structure, functionality and/or parameters of a system*, according to environment, user or self-sensing info.

[F.D. Macías-Escrivá, et al. "Self-adaptive systems: A survey of current approaches, research challenges and applications" In Expert Systems with Applications, 2013]

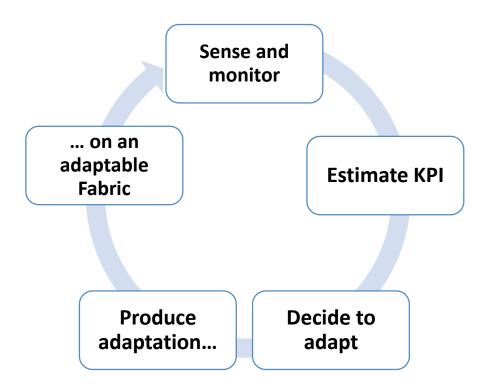




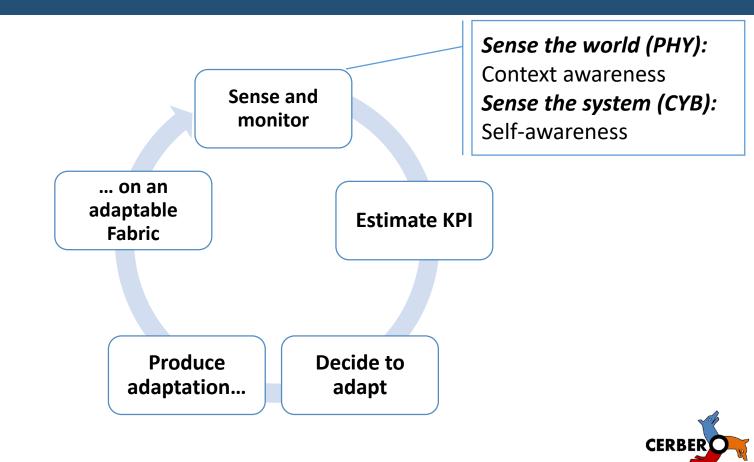
System self-adaptation: awareness + reconfiguration.

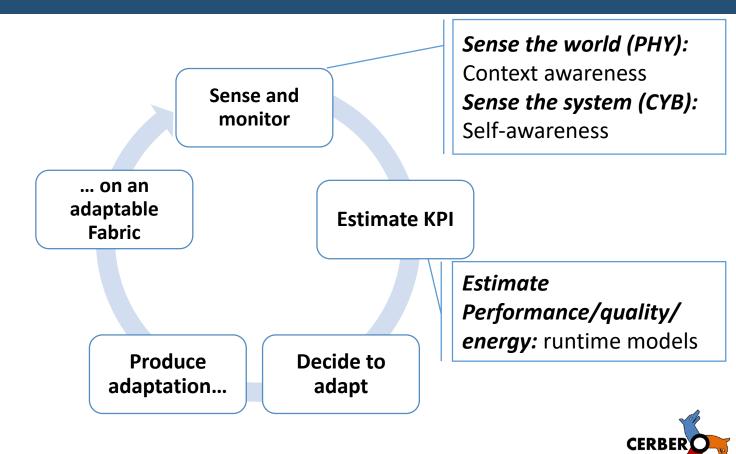
- Reconfiguration → decided *inside the CPS* by a smart *self-adaptation manager (hierarchy of managers)*.
- Decisions → based on run-time Key Performance Indicators (KPIs) measurements and estimations.

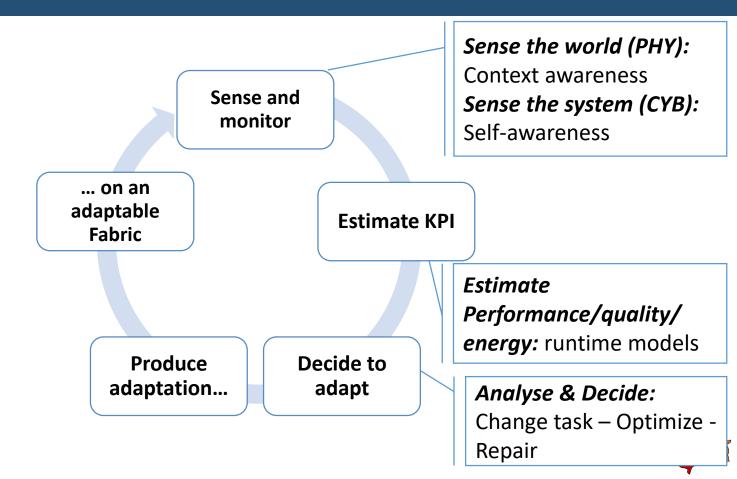


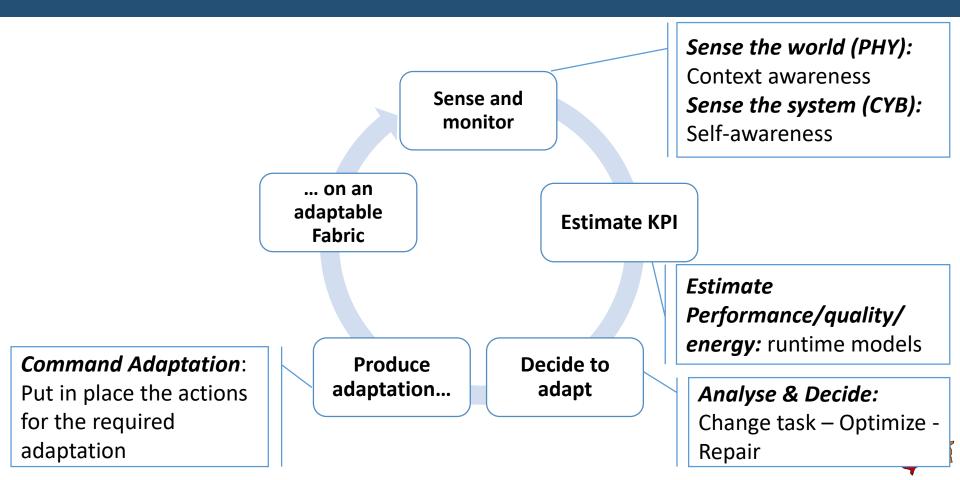


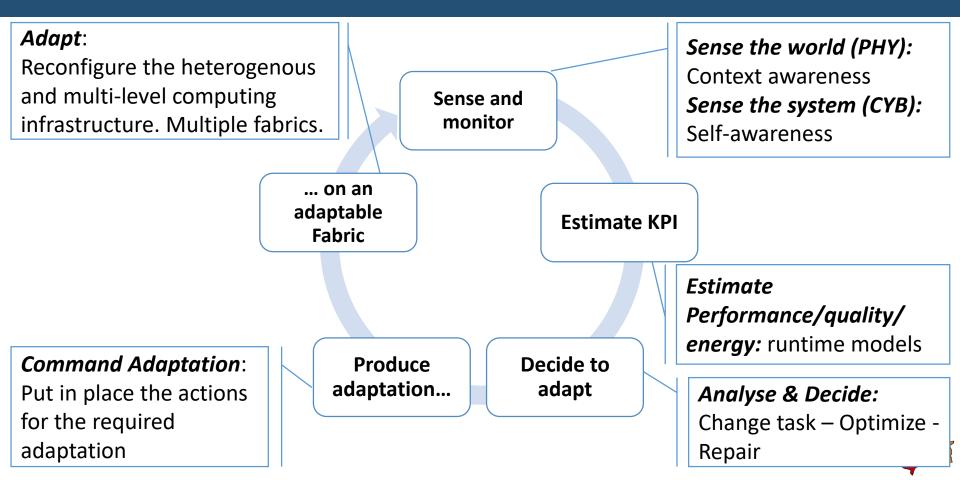




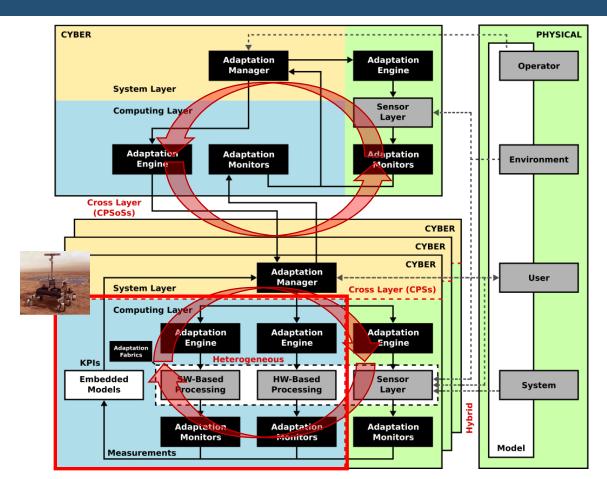






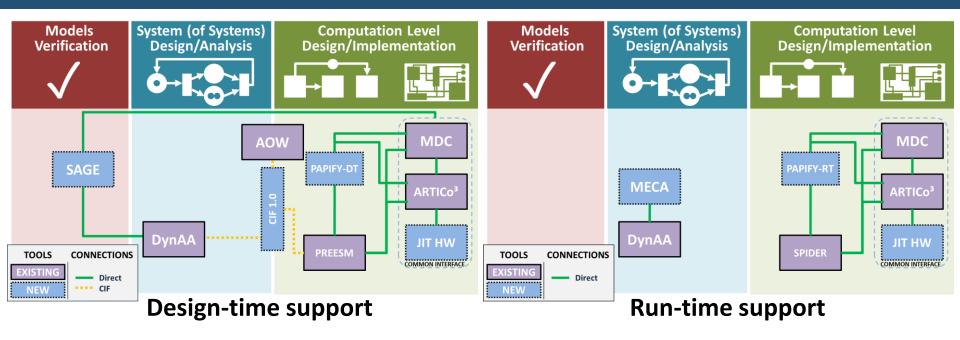


### **CERBERO Self-Adaptive Multi-Level Infrastructure**



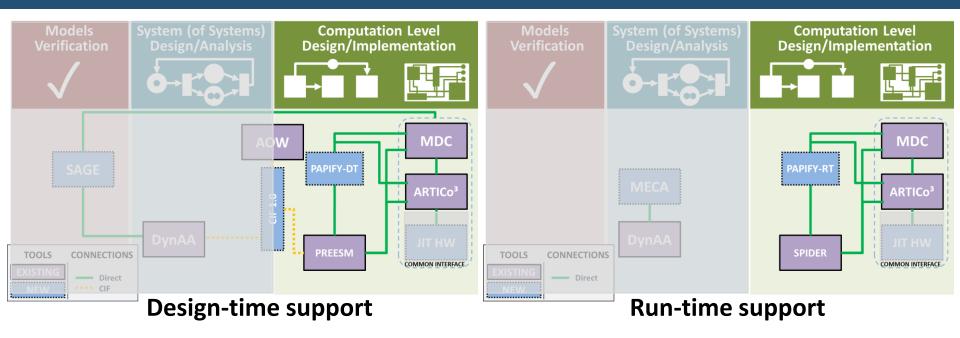


### **CERBERO Framework**

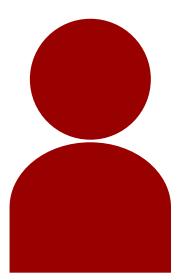




### **CERBERO Framework**

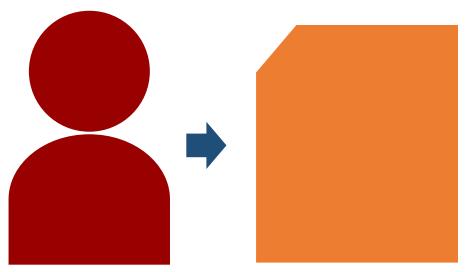






**Developer** 





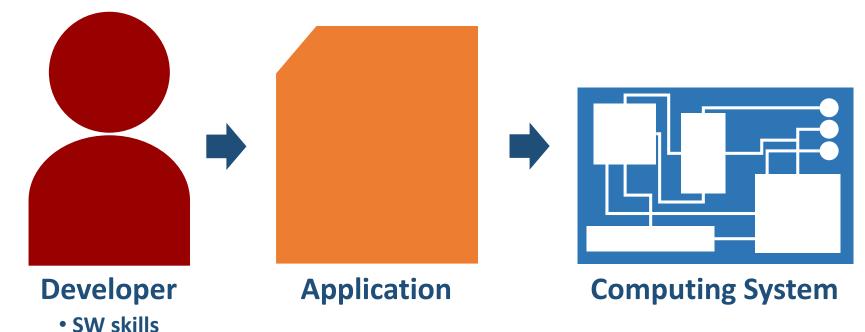
### Developer

• SW skills

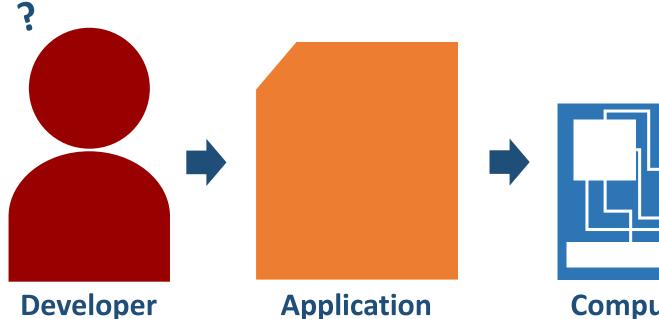
#### **Application**



HW notions



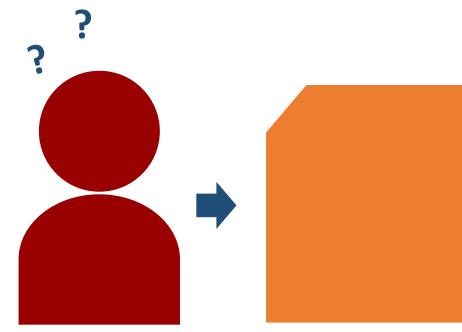
CERBER



- SW skills
- HW notions

#### **Application**



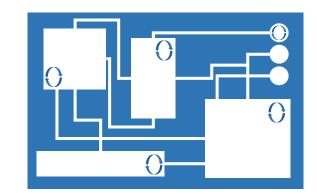


#### Developer

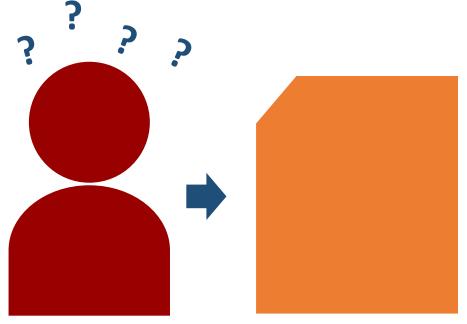
- SW skills
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#### **Application**

Adaptivity







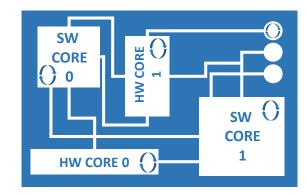
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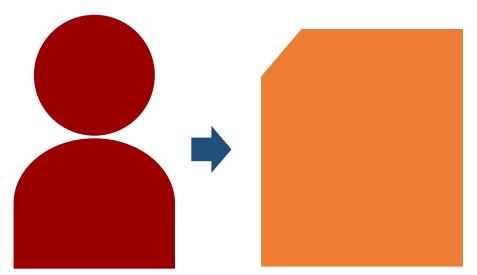
#### **Application**

#### Adaptivity

Heterogeneity





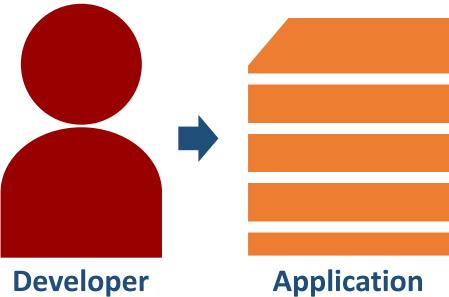


#### Developer

- SW skills
- HW notions

#### **Application**

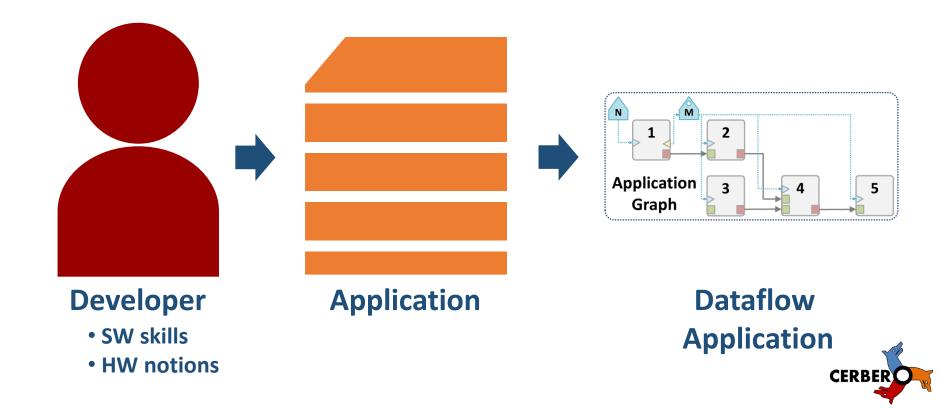


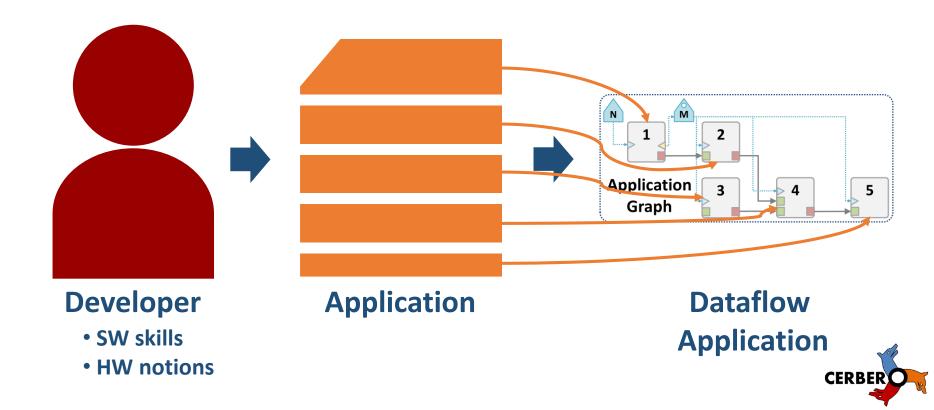


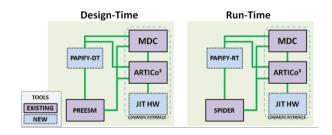
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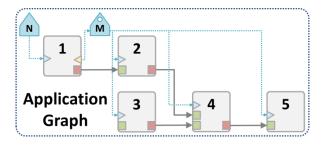
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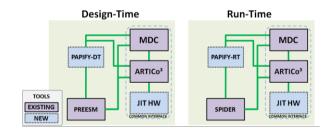


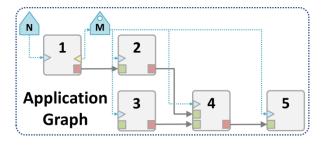




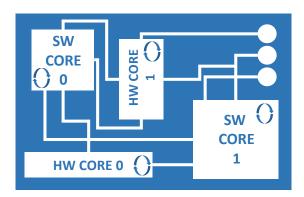






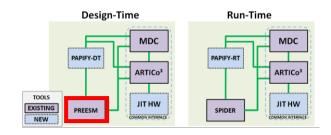


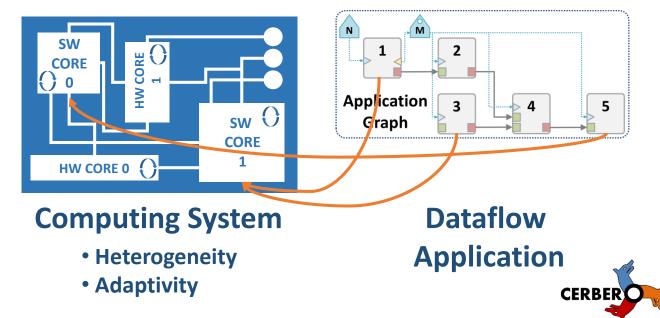
Dataflow Application



- Heterogeneity
- Adaptivity

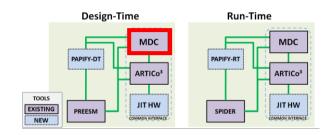
• Parallel SW Code Generation and Mapping

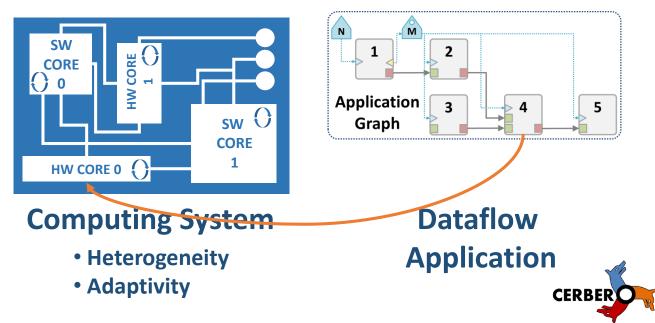




Parallel SW Code
Generation and Mapping
Deployment of HW CGR
Accelerator (fast reconf.)

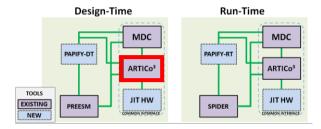


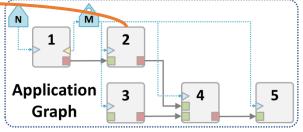




Parallel SW Code
Generation and Mapping
Deployment of HW CGR
Accelerator (fast reconf.)
Deployment of HW DPR
Multi-Accelerator (slow reconf., HW reuse)

SW CORE 0 HW CORE 0





**Computing System** 

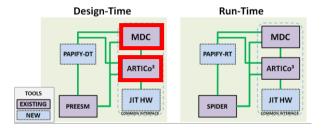
- Heterogeneity
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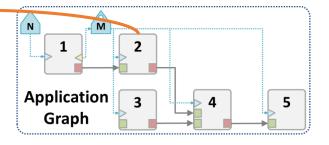
Dataflow Application

 Parallel SW Code **Generation and Mapping**  Deployment of HW CGR M Accelerator (fast reconf.) Deployment of HW DPR **Multi-Accelerator (slow** reconf., HW reuse)

> Optionally with CGR inside (slow or fast reconf for Ŵ adaptation)

SW 1 CORE CORE 0 () ₹ sw O CORE 1 HW CORE 0





#### **Computing System**

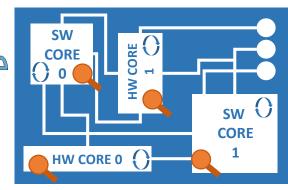
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Dataflow **Application** CERBER

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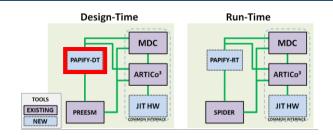
- Optionally with CGR inside (slow or fast reconf for Ŵ adaptation)
- Instrumentation for monitoring

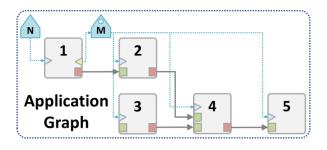




#### **Computing System**

- Heterogeneity
- Adaptivity





Dataflow **Application** CERBER

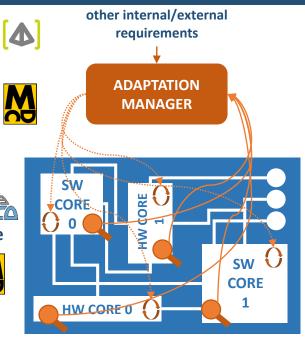
Parallel SW Code
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Deployment of HW CGR
Accelerator (fast reconf.)
Deployment of HW DPR
Multi-Accelerator (slow reconf., HW reuse)

- Optionally with CGR inside (slow or fast reconf for adaptation)
- Instrumentation for



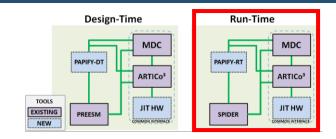


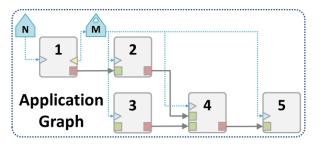
• Run-time management and self-adaptation (not covered in the tutorial)



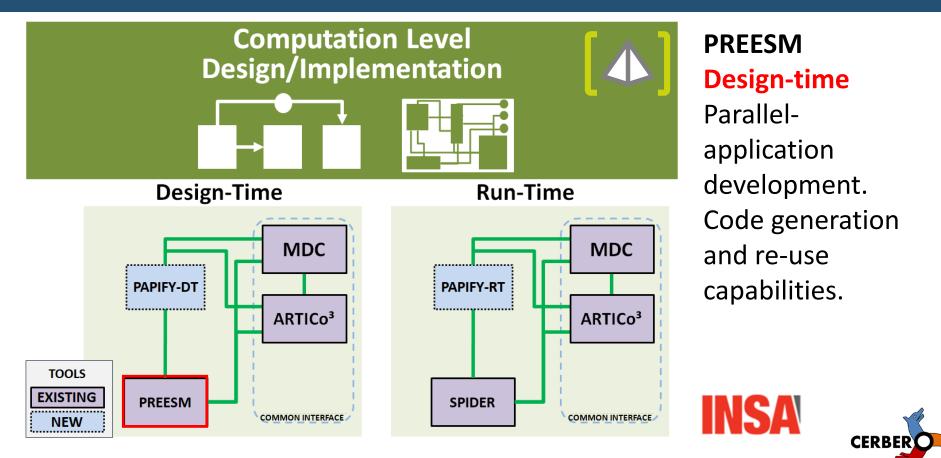
#### **Computing System**

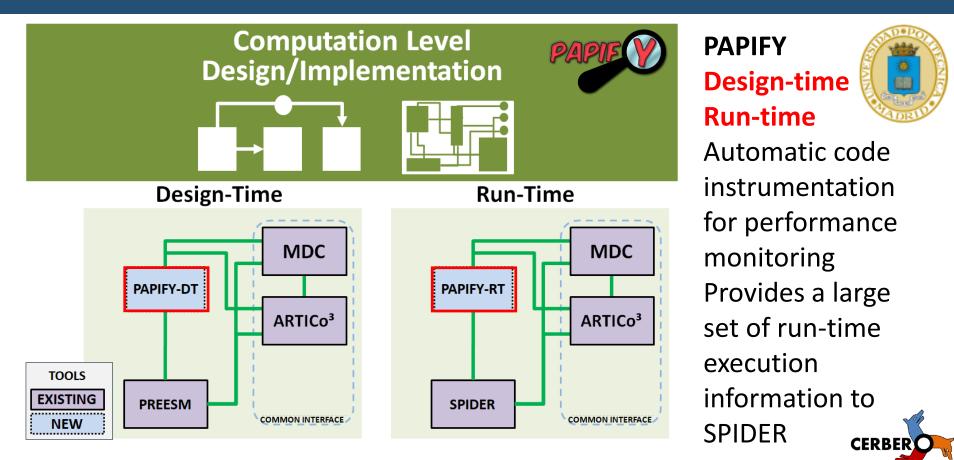
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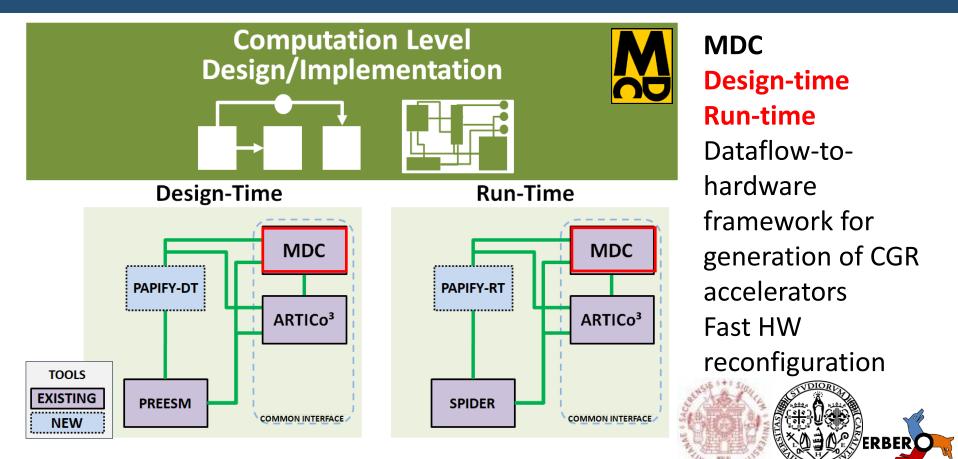


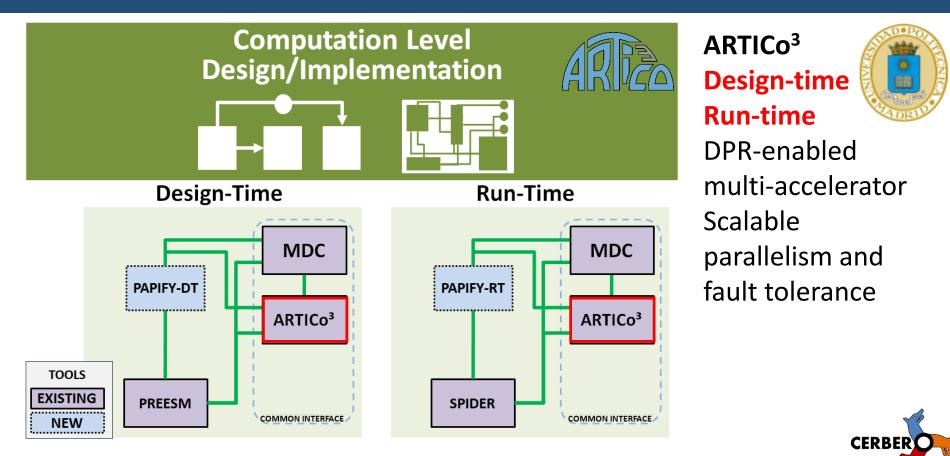


Dataflow Application

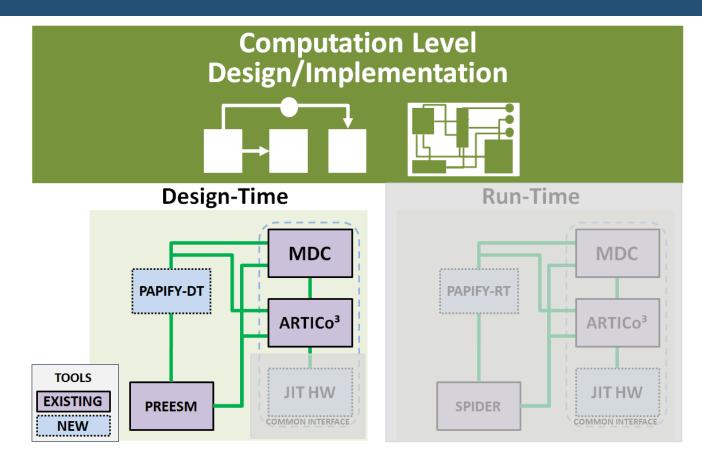




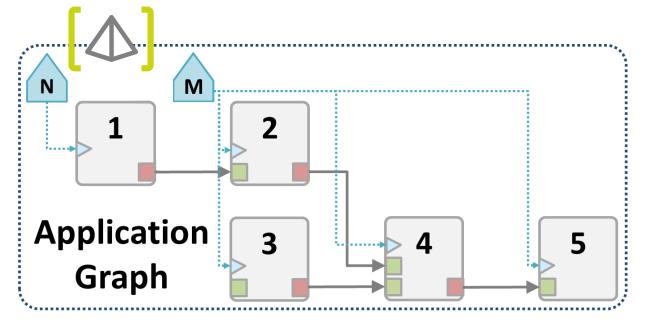




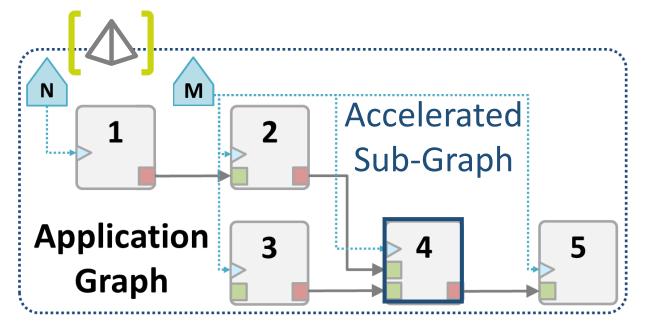
### **CERBERO Framework – Self-Adaptive System Design**



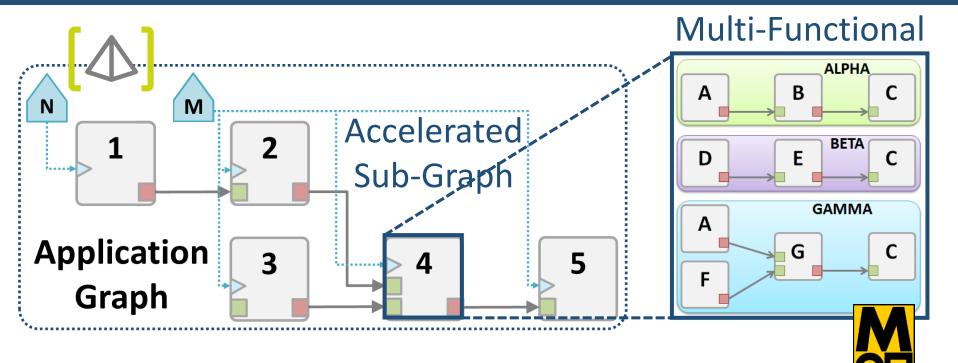




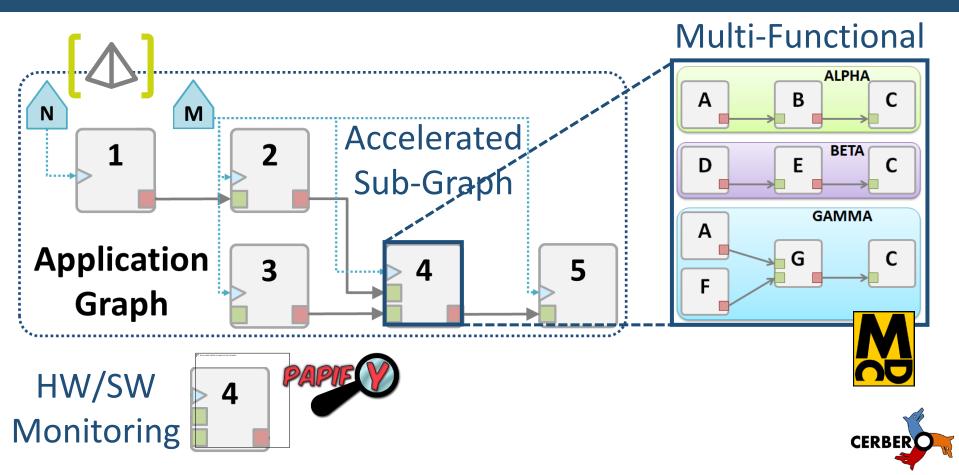


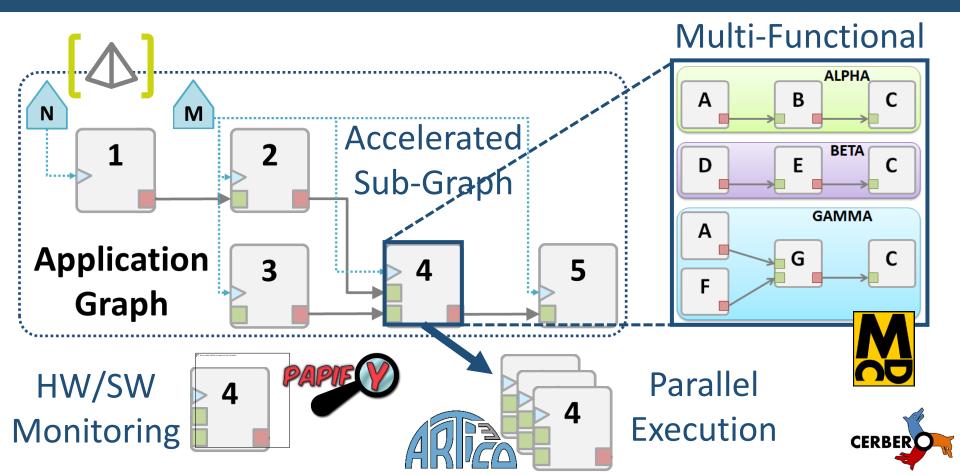










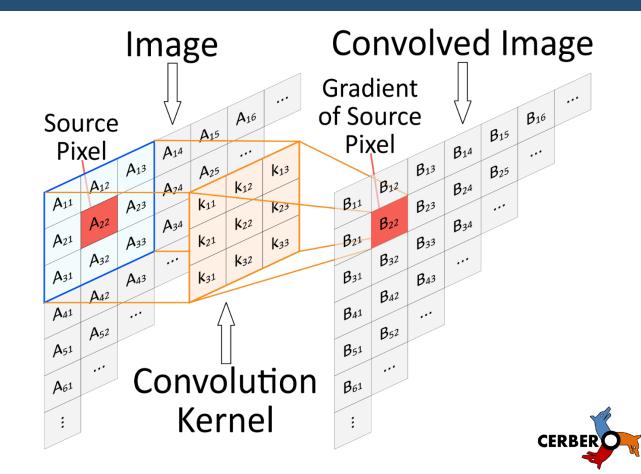


### **Tutorial Use Case**

**Sobel Operator** 

 $\mathbf{G}=\sqrt{{\mathbf{G}_x}^2+{\mathbf{G}_y}^2}$ 

$$\mathbf{G}_x = egin{bmatrix} +1 & 0 & -1 \ +2 & 0 & -2 \ +1 & 0 & -1 \end{bmatrix} \ \mathbf{G}_y = egin{bmatrix} +1 & +2 & +1 \ 0 & 0 & 0 \ -1 & -2 & -1 \end{bmatrix}$$

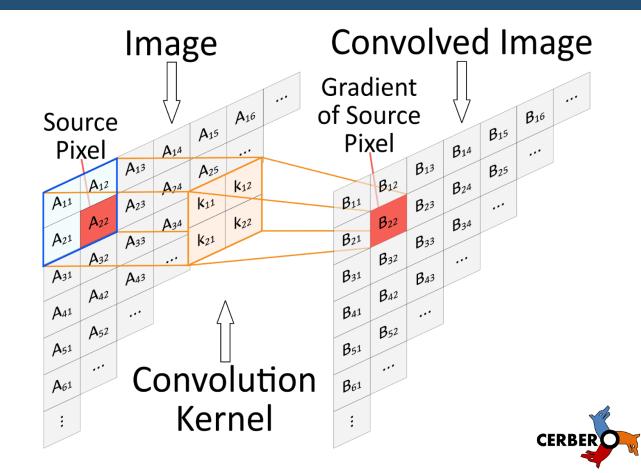


### **Tutorial Use Case**

**Roberts Operator** 

$$\mathbf{G}=\sqrt{{\mathbf{G}_x}^2+{\mathbf{G}_y}^2}$$

$$G_x = egin{bmatrix} 0 & +1 \ -1 & 0 \end{bmatrix} \ G_y = egin{bmatrix} +1 & 0 \ 0 & -1 \end{bmatrix}$$



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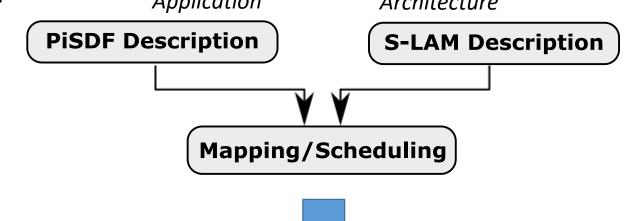
### Hardware/Software Model-Based Design for Design Space Exploration and Code Generation



Horizon 2020 European Union funding for Research & Innovation

## PREESM

• Y co-design approach: keep architecture and application separate. Application Architecture

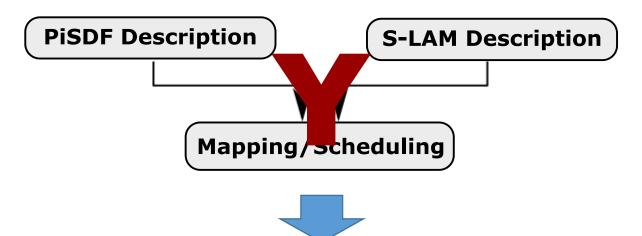


#### **AUTOMATIC CODE GENERATION for RAPID PROTOTYPING**



## PREESM

• Y co-design approach: keep architecture and application separate.

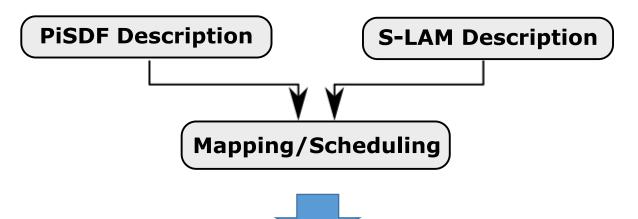


#### AUTOMATIC CODE GENERATION for RAPID PROTOTYPING



## PREESM

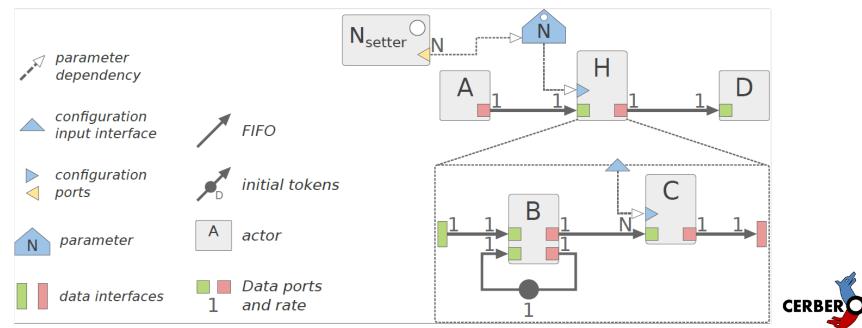
• Y co-design approach: keep architecture and application separate.



AUTOMATIC CODE GENERATION for RAPID PROTOTYPING for MPSoCs (CPUs + FPGA)

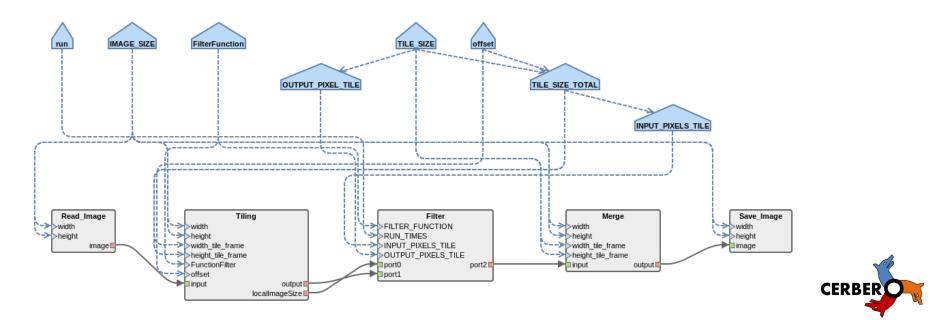
## **PiSDF: Parameterized and Interfaced SDF**

#### • Semantics:

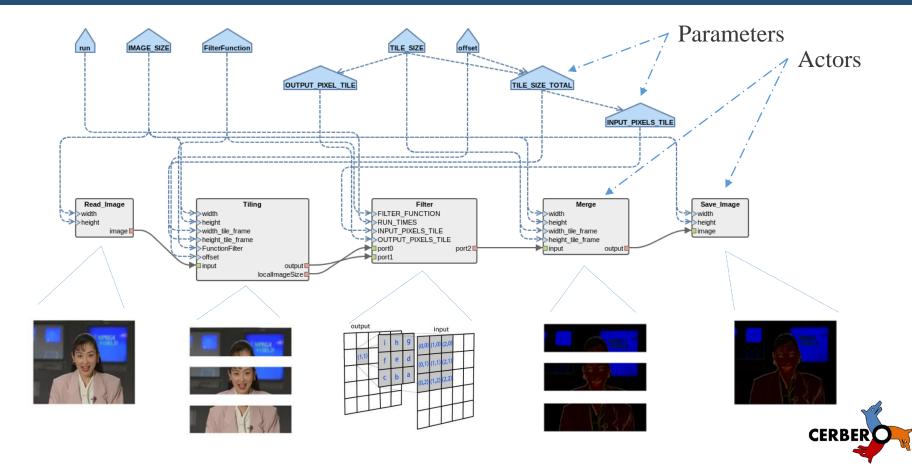


## **PiSDF: Parameterized and Interfaced SDF**

• Application :

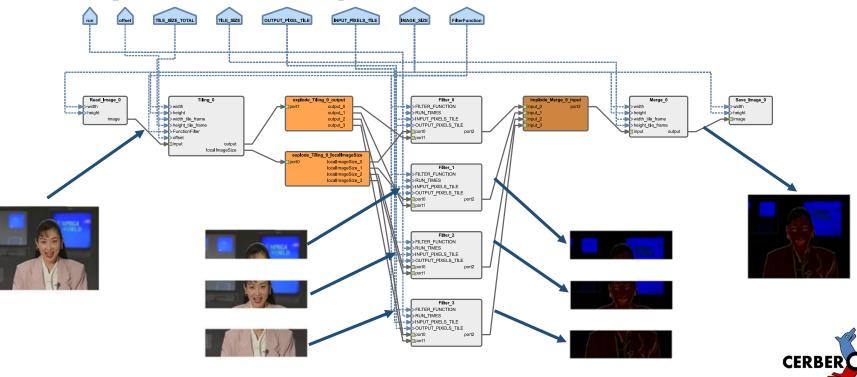


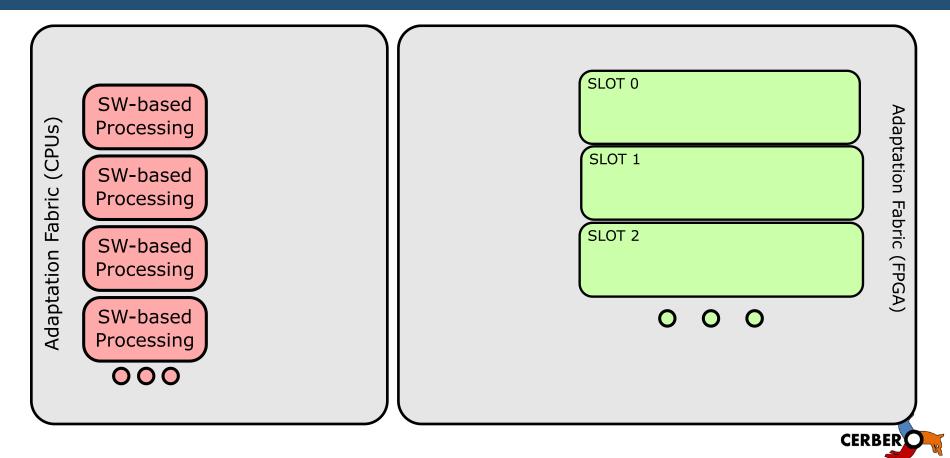
# **Actor Specification**

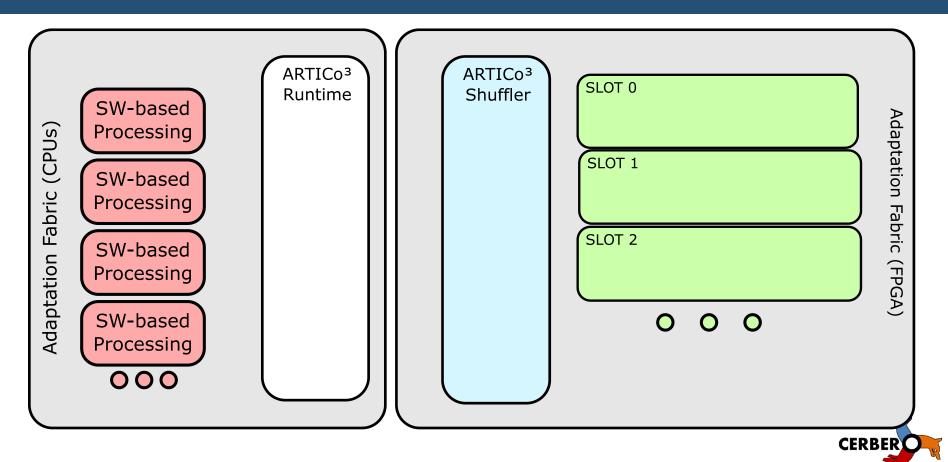


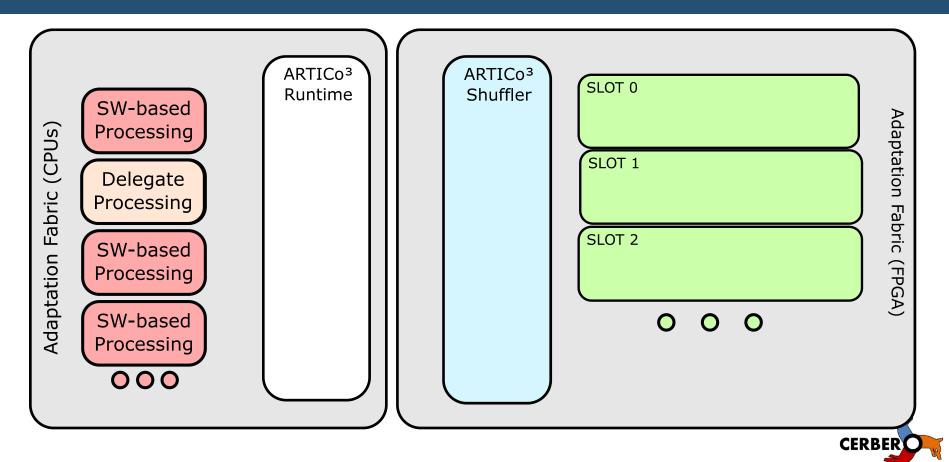
# **Exposed Parallelism**

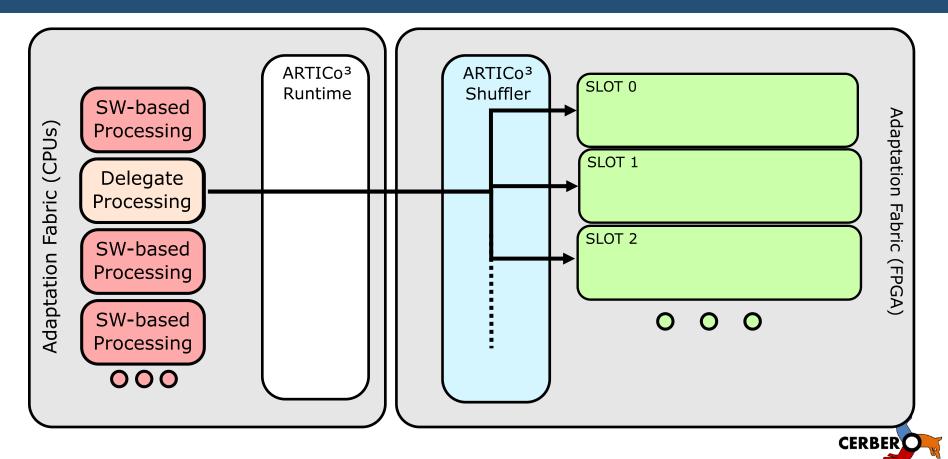
**Equivalent single-rate graph** where each edge has equal production and consumption rates of token.

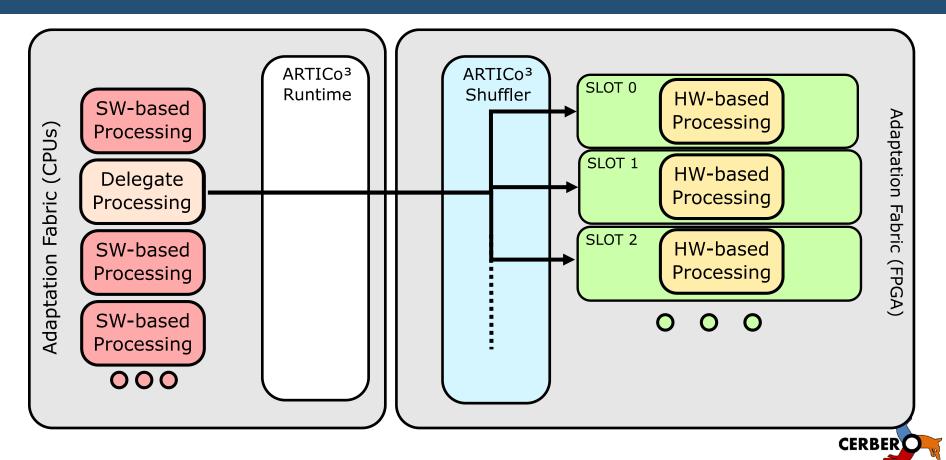






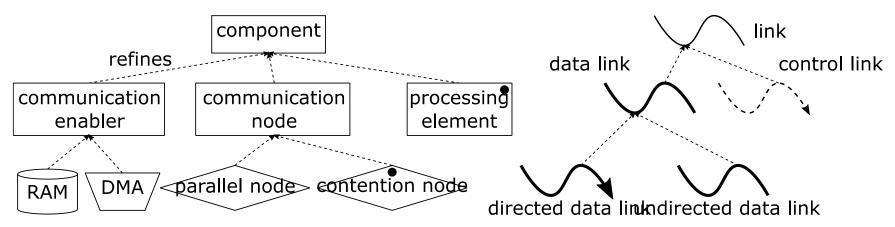






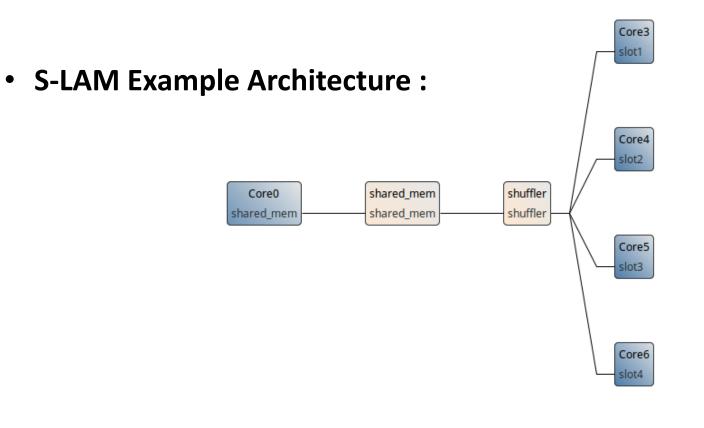
## S-LAM: System-Level Architecture Model

• S-LAM typology:





## **S-LAM: System-Level Architecture Model**





# **PREESM Mapping and Scheduling**

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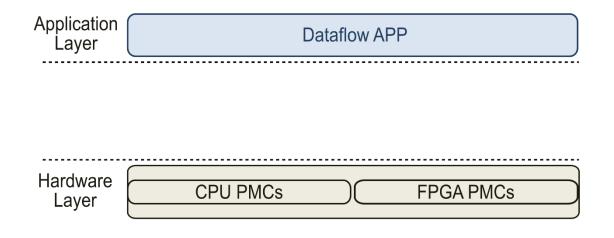


## **System Performance Monitoring**



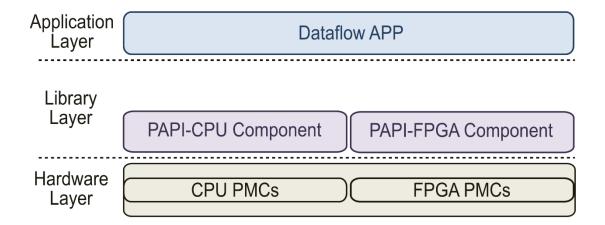
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### **CERBERO Monitoring: PAPIFY**



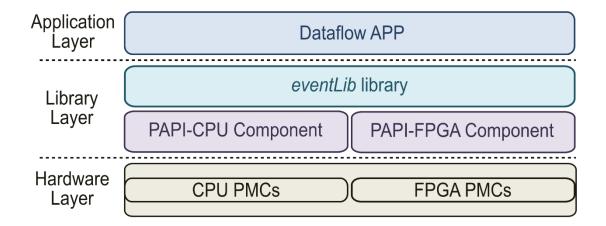


### **CERBERO Monitoring: PAPIFY**

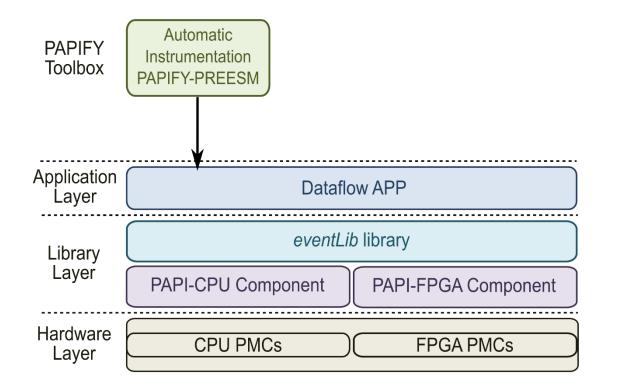




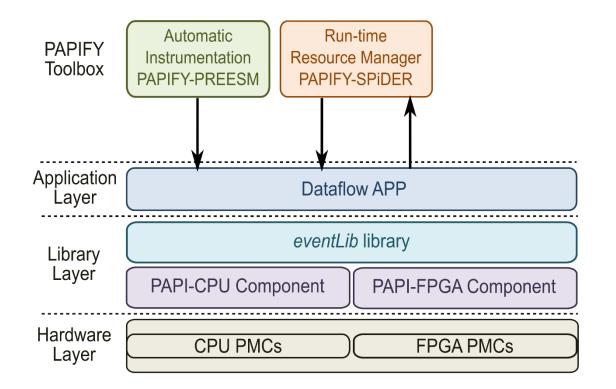
### **CERBERO Monitoring: PAPIFY**



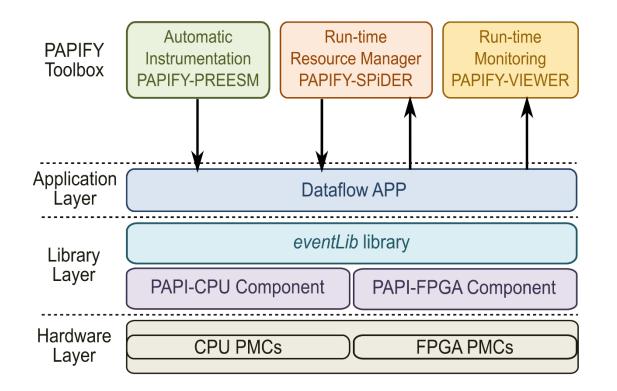














configure\_papify\_actor(...); configure\_papify\_PE(...);

// Configure monitoring of each actor
// Configure each PE



```
configure_papify_actor(...);
configure_papify_PE(...);
```

// Configure monitoring of each actor
// Configure each PE

actor\_execution();

. . .

// Execute the actor



```
configure papify actor(...);
configure papify PE(...);
```

// Configure monitoring of each actor // Configure each PE

```
event start(...);
                              // Start monitoring PAPI events
event_start_papify_timing(...); // Start monitoring timing
```

```
actor execution();
```

. . .

```
// Execute the actor
```

```
event_events(...);
event_stop_papify_timing(...); // Stop monitoring timing
event write file(...);
```

```
// Stop monitoring PAPI events
// Dump monitoring info
```



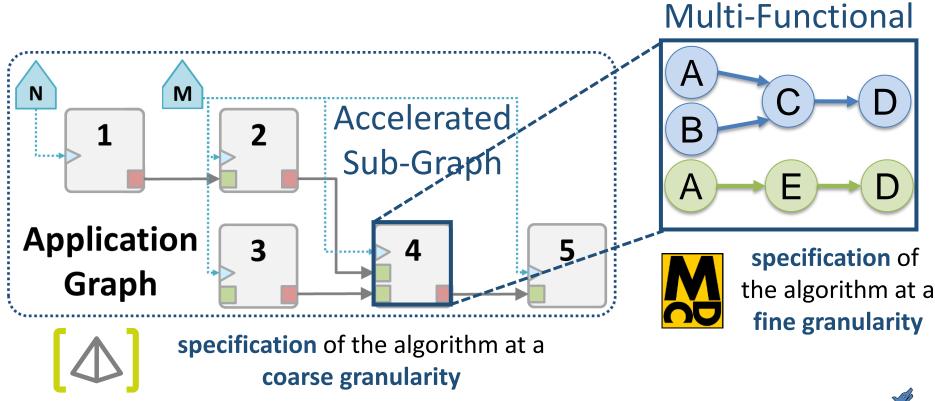
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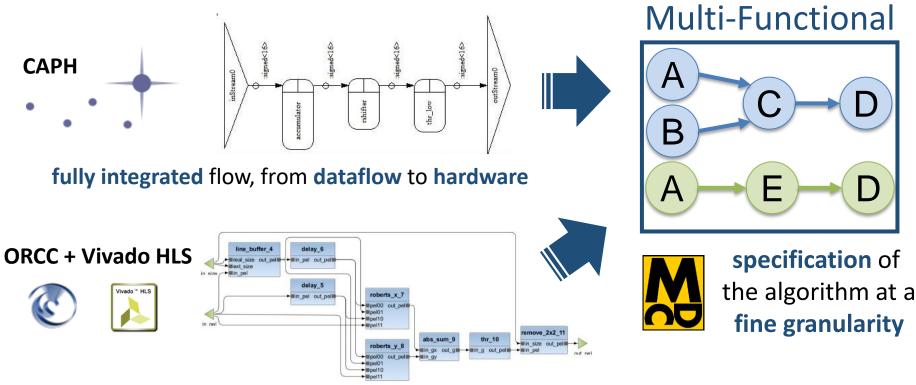
#### **Creating Hardware Accelerators with DPR and CGR**



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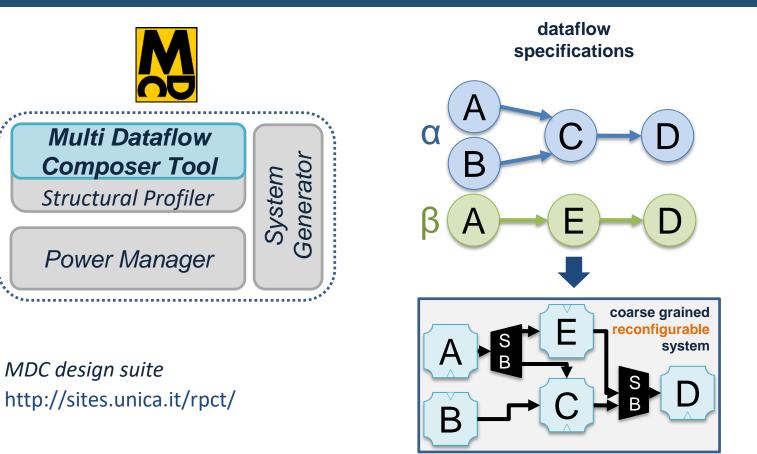






two steps flow: ORCC for dataflow network, Vivado HLS deals for actors hardware code generation

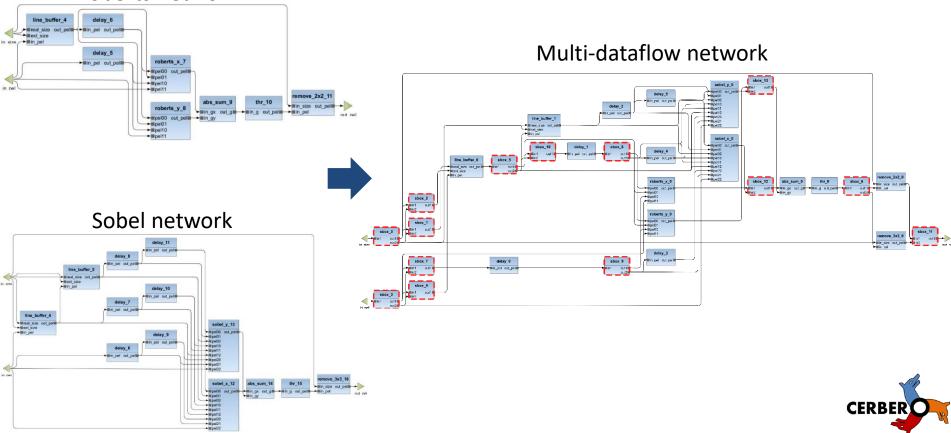


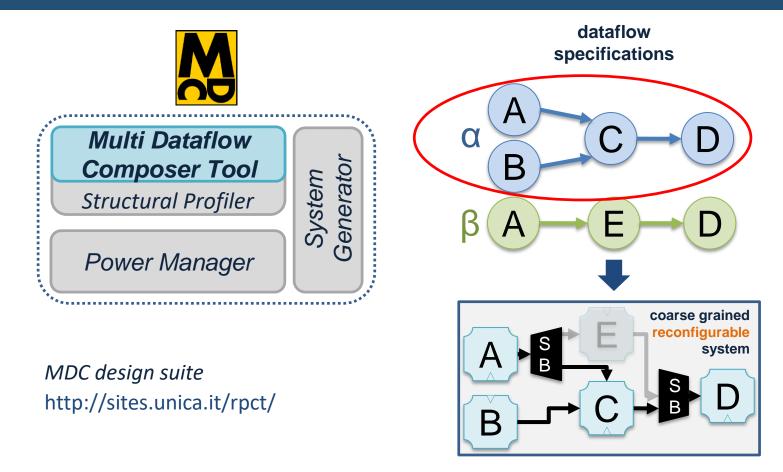




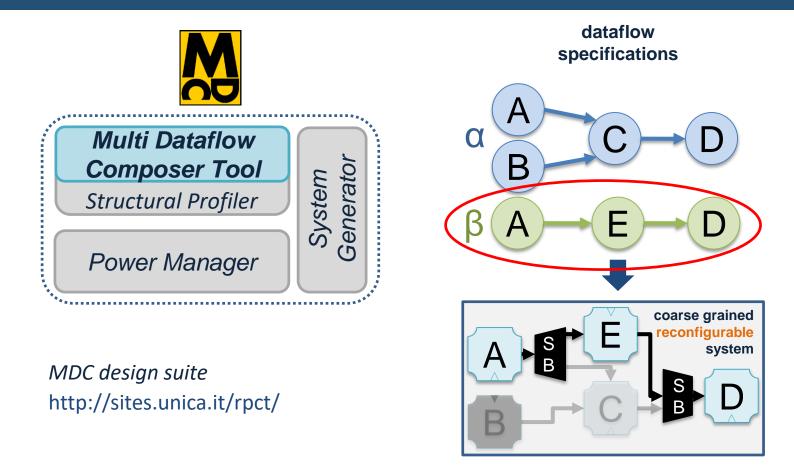
## **MDC: Merging**

**Roberts network** 

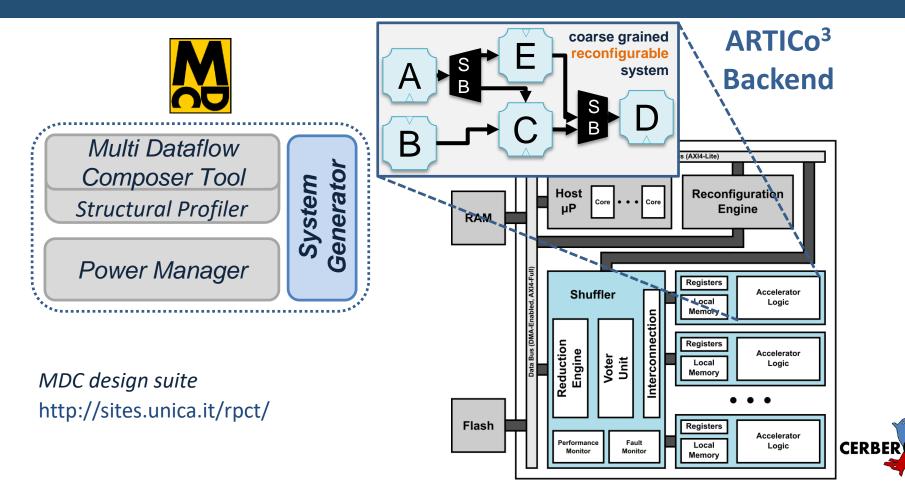




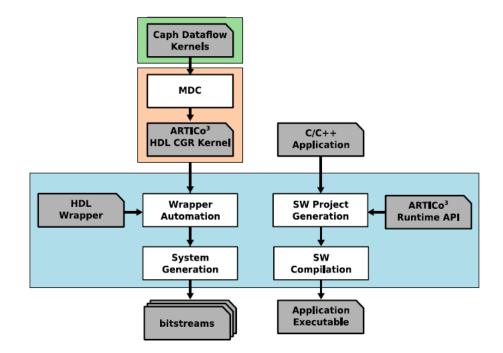






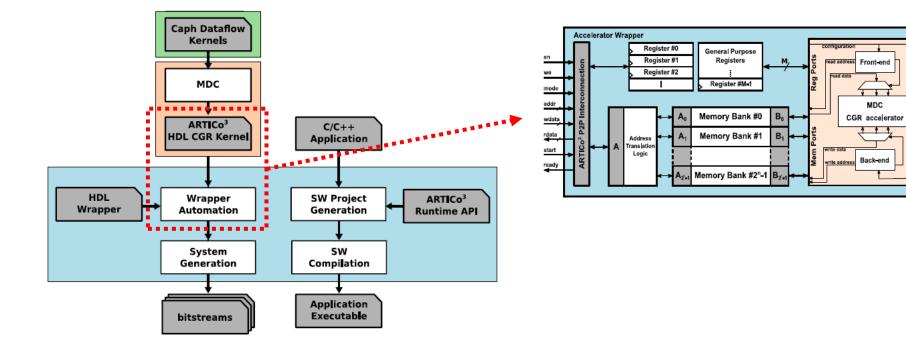


## **ARTICo<sup>3</sup>** Design Flow



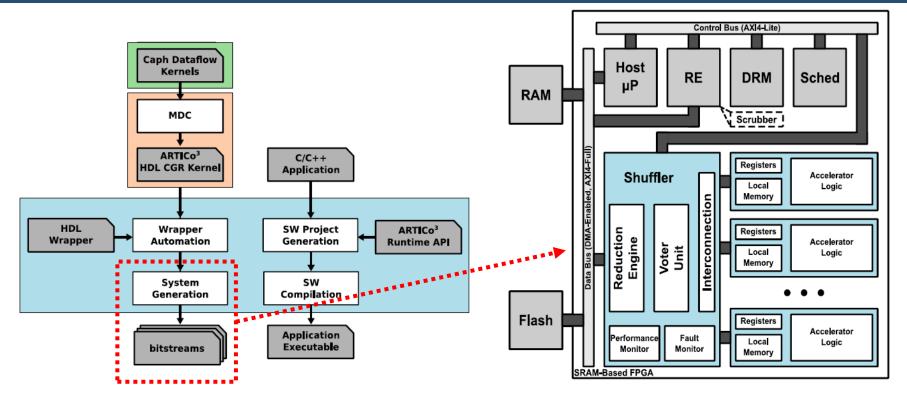


# **ARTICo<sup>3</sup>** Design Flow



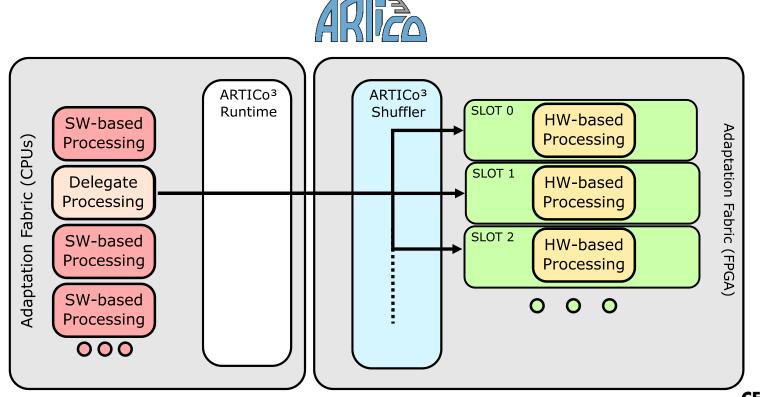


## **ARTICo<sup>3</sup>** Design Flow



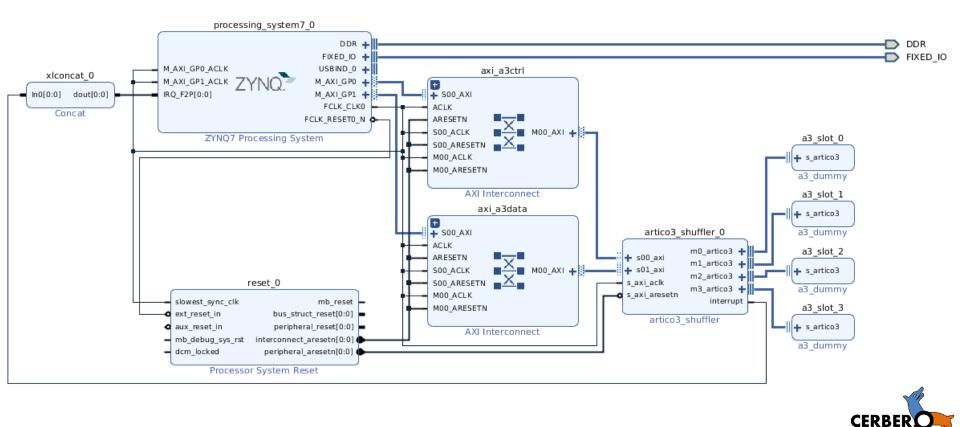


## Heterogeneous Device

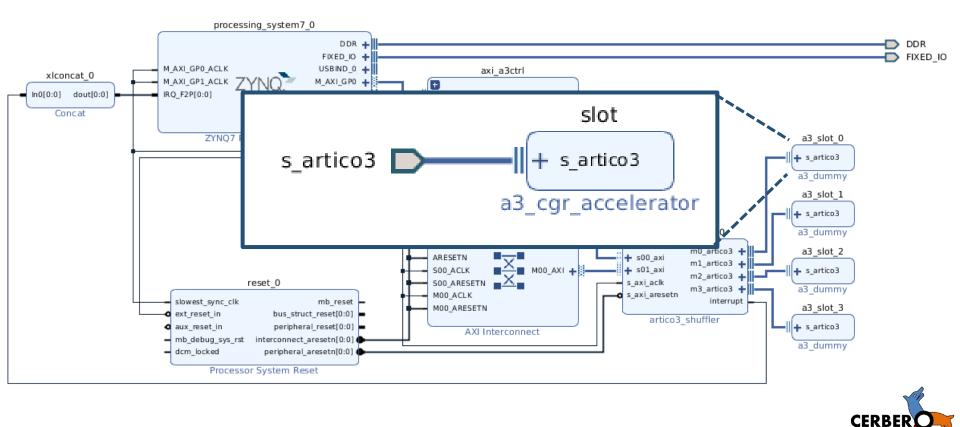


CERBER

#### Architecture Overview in Vivado



#### Architecture Overview in Vivado



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#### CERBERO H2020 Project – Tutorial: Design Flow for Heterogeneous Embedded Computing Infrastructures



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## **Additional Slides**

