Digital Signal Processors: fundamentals & system design

Lecture 3

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CERN

Topical CAS/Digital Signal Processing
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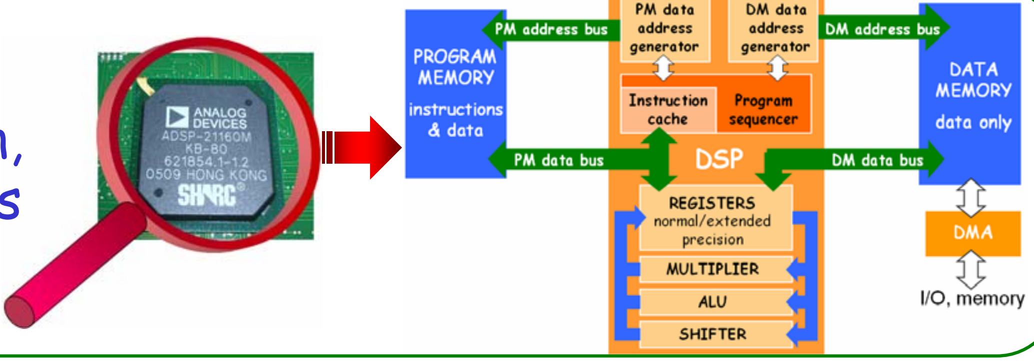
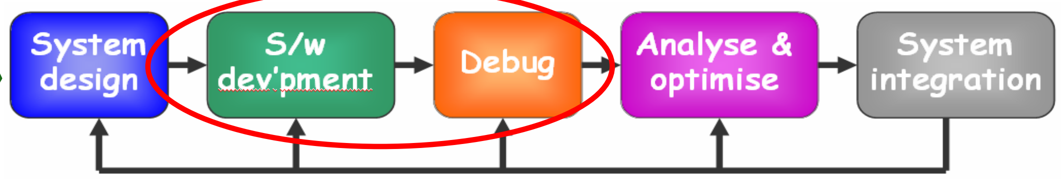
Lectures plan

Lecture 1

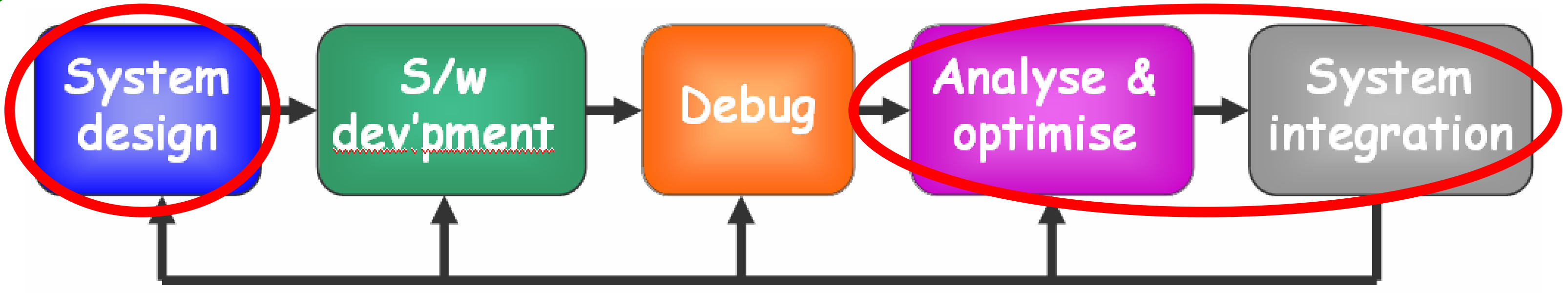
introduction, evolution, DSP core + peripherals





Lecture 2

DSP peripherals (cont'd), s/w dev'pment & debug.



Lecture 3 System optimisation, design & integration.

Lecture 3 - outline

Chapter 8: RT design flow – analysis & optimisation

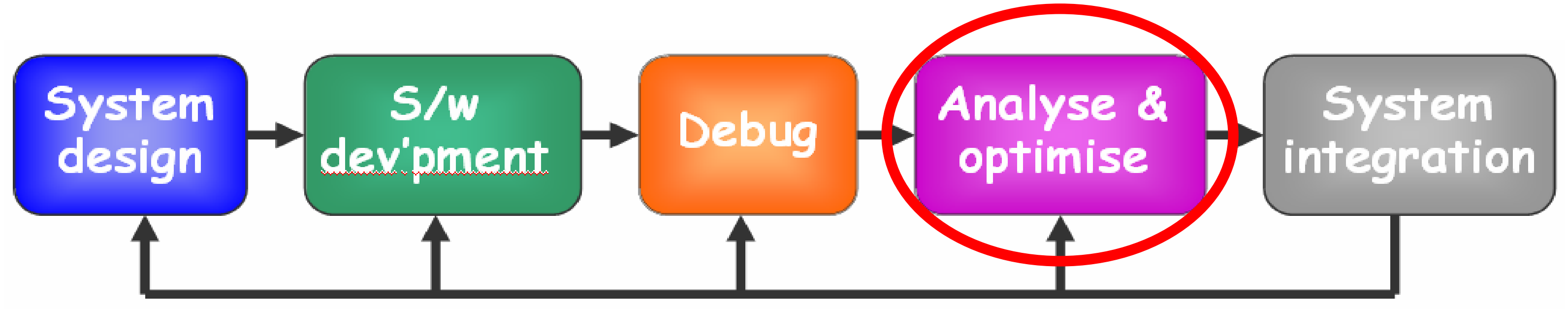
Chapter 9: RT design flow – system design

Chapter 10: RT design flow – system integration

Chapter 11: Putting it all together …

Chapter 8 topics

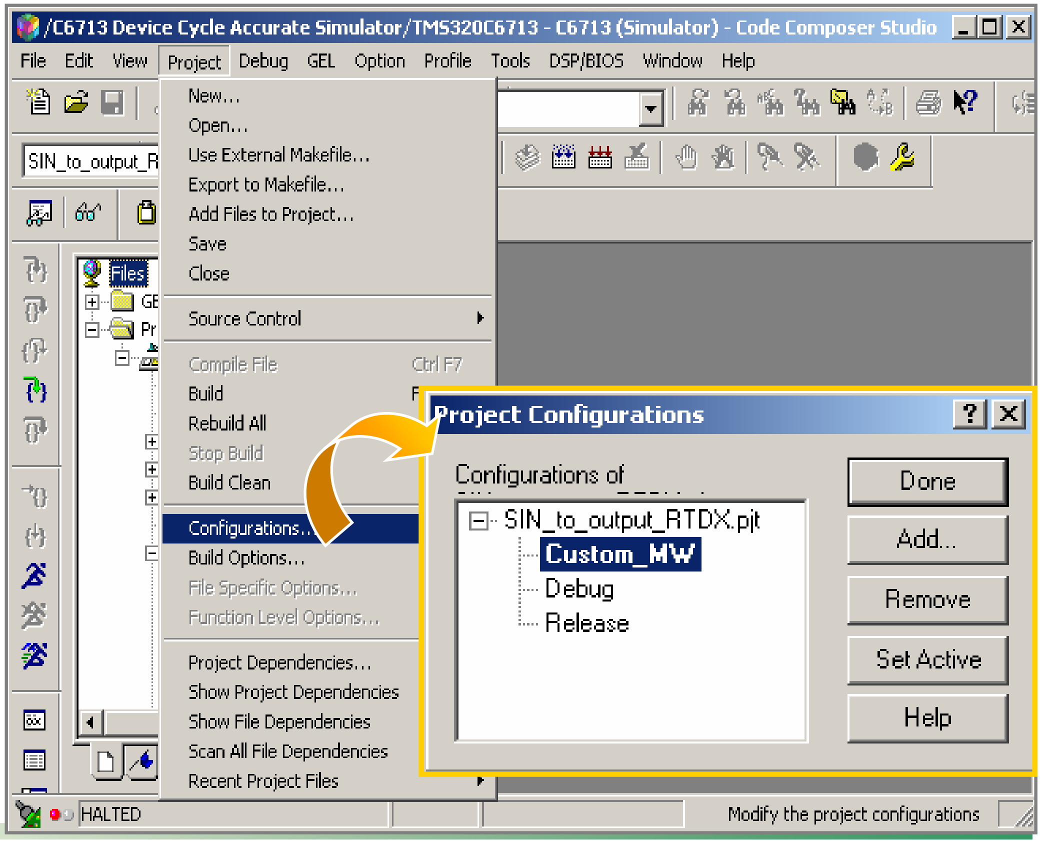
RT design flow: analysis & optimisation



8.1 Introduction

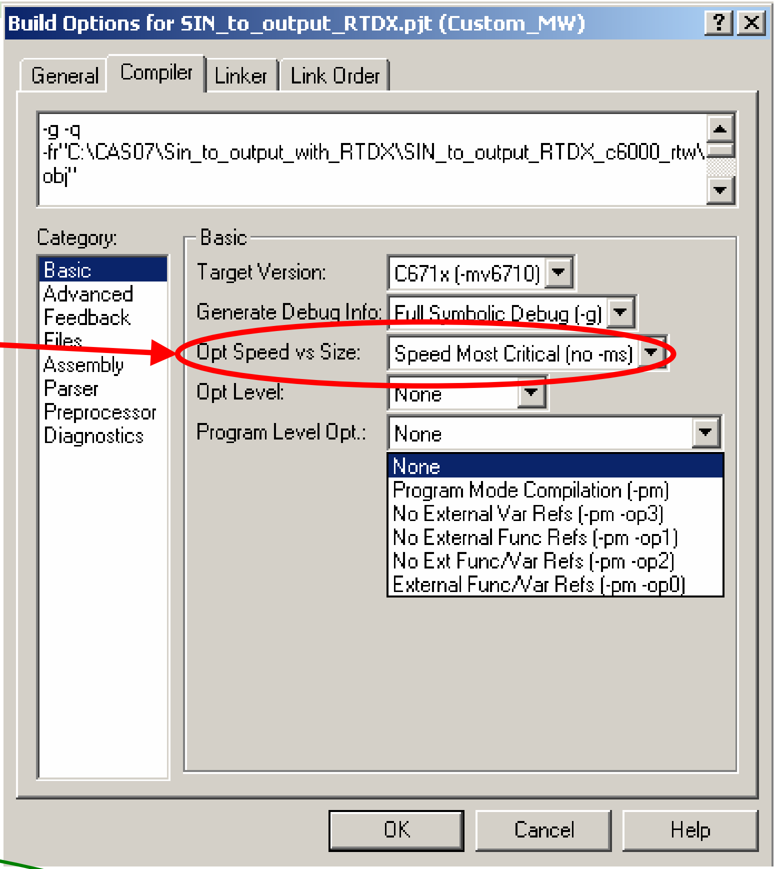
- Optimisation: speed, memory usage, I/O BW, power consumption.
- Steps: Debug → set optimiser ON → analyse & optimise (*if needed*).
- Debug & optimise: different & conflicting phases!

- Tuneable configurations.
  - **Debug**: debug features enabled.
  - **Release**: optimised (size /speed) version.
  - **Custom**



8.2 Optimiser ON

- Compilers very good @optimising: efficient code!
- Many optimisation phases (levels) : size vs. speed.
- Power consumption often critical factor, too!
- Careful: optimiser rearranges code!
  - Assembly looks different
  - Desired action may be modified:



```
-g -q
-fr"C:\CAS07\Sin_to_output_with_RTDX\SIN_to_output_RTDX_c6000_rtw\obj"
```

Basic

Target Version: C671x (-mv6710)

Generate Debug Info: Full Symbolic Debug (-g)

Opt Speed vs Size: Speed Most Critical (no -ms)

Opt Level: None

Program Level Opt.: None

- None
- Program Mode Compilation (-pm)
- No External Var Refs (-pm -op3)
- No External Func Refs (-pm -op1)
- No Ext Func/Var Refs (-pm -op2)
- External Func/Var Refs (-pm -op0)

```
unsigned int *ctrl;
while (*ctrl !=0xFF);
```

BAD!

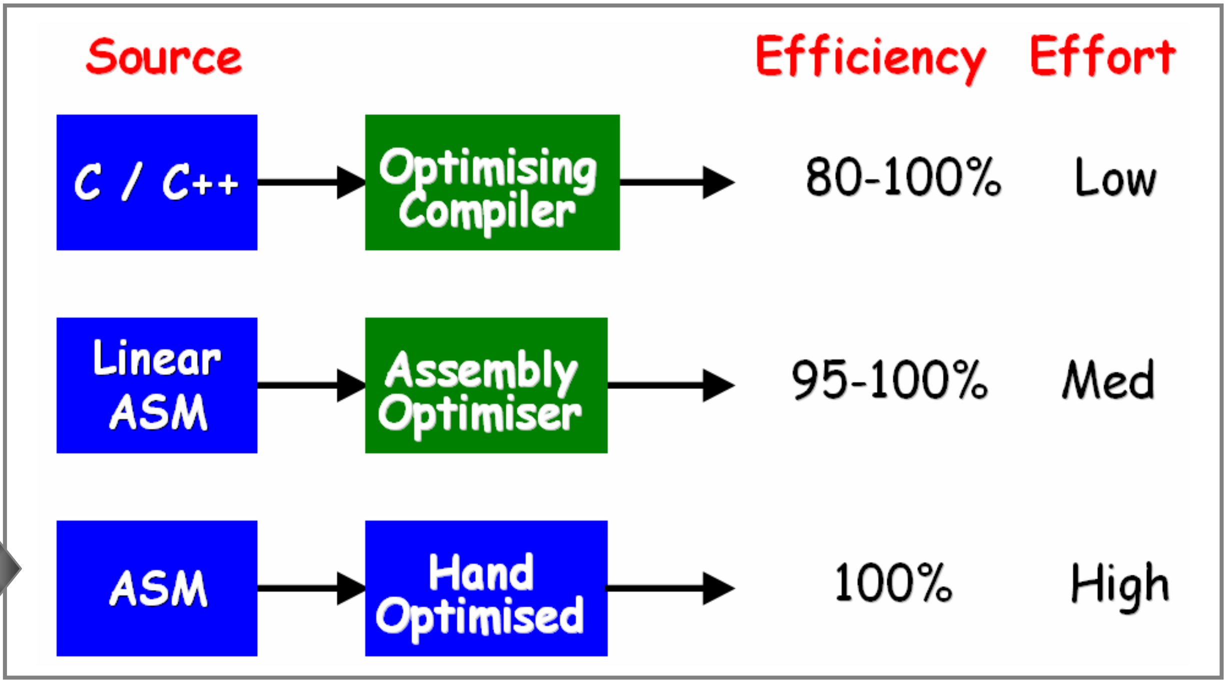
```
volatile unsigned int *ctrl;
while (*ctrl !=0xFF);
```

OK

Disables locally memory optimisation!

8.2 Optimiser ON [2]

- Recommended code development flow:
  - Phase 1: write C/C++ code.
  - Phase 2: optimize C/C++ code
  - Phase 3 (if needed): code time-critical areas in **linear assembly**.
  - Phase 4 (if needed): code time-critical areas by **hand in assembly**.

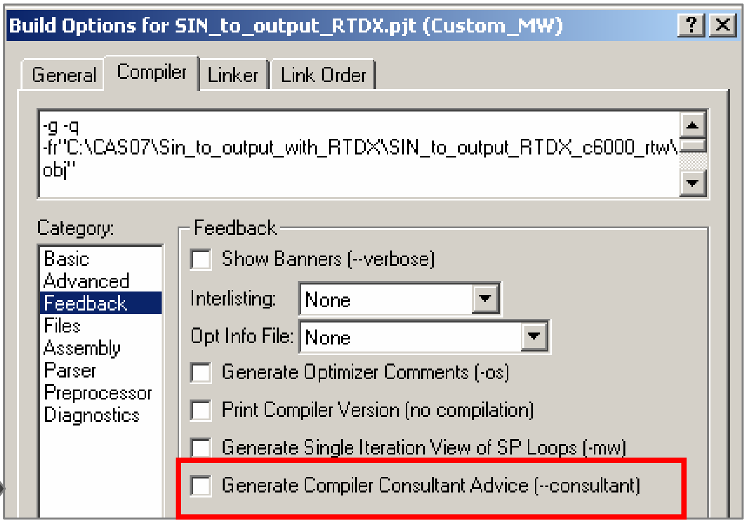


Comparison of programming techniques

8.3 Analysis tools

- Know what to optimise! 20% of the code does 80% of the work.
- Know when to stop! → diminishing returns.
- TI tools:
  - **Compiler consultant**: recommendations to optimize performance.
  - **Cache tune**: optimizes code size vs. cycle count.
  - **Code size tune**: graphical visualisation of memory reference patterns, to identify conflict areas.

Enabling Compiler Consultant for a project


Build Options for SIN_to_output_RTDX.pjt (Custom_MW)

```
-g -q
-fr"C:\CAS07\Sin_to_output_with_RTDX\SIN_to_output_RTDX_c6000_rtw\
obj"
```

Category: Feedback

- [ ] Show Banners (--verbose)
- Interlisting: None
- Opt Info File: None
- [ ] Generate Optimizer Comments (-os)
- [ ] Print Compiler Version (no compilation)
- [ ] Generate Single Iteration View of SP Loops (-mw)
- [ ] Generate Compiler Consultant Advice (--consultant)

NB: tools limitations with h/w. Use simulator!

8.4 Optimisation guidelines

… i.e. how to write more efficient code from the start

- Make the common case fast.
- Allocate memory wisely (→ linker!) & use DMA.
- Keep pipeline full.
  - Small code may fit in internal memory
  - Software pipelining: memory has edges!

- Native vs. emulated data types: faster execution on native data types (h/w vs. emulated arithmetic). → ***KNOW YOUR DSP !***

- Function calls: pass few parameters (if no more registers available, parameters passed via stack → slow!)

8.4 Optimisation guidelines [2]

- Data aliasing: multiple pointers *may* point to same data → compiler doesn't optimise → compilation switches to state aliasing YES/NO.
- Loops:
  - *Avoid function calls & control statement inside loops.*

```
for {
   if {…} else {…}
}
```

→

```
if {
   for {…}
} else {
   for {…}
}
```

No pipeline breaks, but bigger code.

```
k = k - 1;
if( k < -1)
   k = -1;
```

→

```
k = max (k-1, -1);
```

min/max/abs often single-cycle instructions

  - Move operations inner → outer loops (compilers focus on inner loops)
  - Keep loop code small (local repeat optimisation).
  - Loop counter: *int/unsigned int* instead of *long* .

8.4 Optimisation guidelines [3]

- Time-consuming operations:
  - **division**. Often no h/w support for single-cycle division. Use *shift* when possible.
  - **cos**, **sin**, **atan**: (+ high resolution) often needed by accelerator systems!

→ CERN LEIR LLRF: **polynomial** instead of Taylor-expansion. Resolution comparable to VisualDSP++ *emulated double floating point* **but** faster!

	Execution time [µs]		
Function	**CERN single precision implementation**	**VisualDSP++ single precision implementation**	**VisualDSP ++ double precision implementation**
cosine	0.25 (for a sine/cosine couple)	0.59	5.5
sine		0.59	5.3
atan	0.4125	1.4	5.6

CERN LEIR LLRF: optimised & high-resolution functions implementations.

8.4 Optimisation guidelines [4]

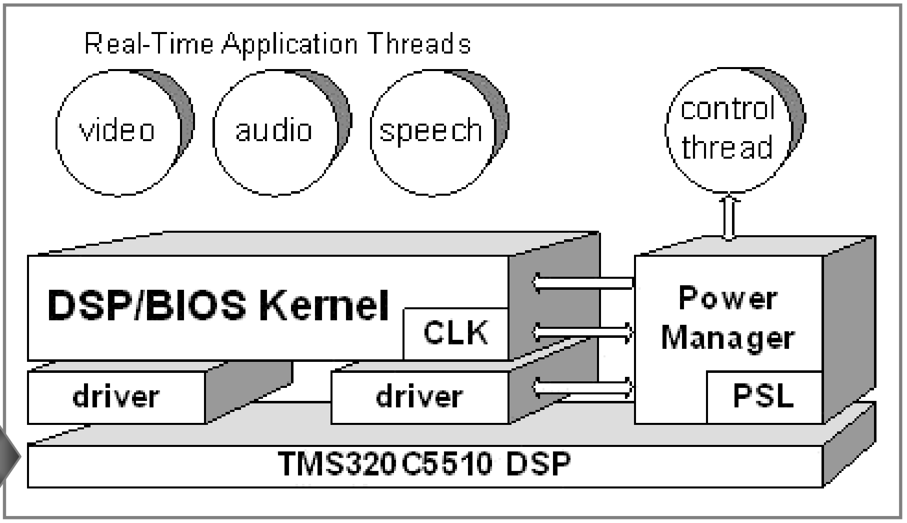
- Use libraries: optimisation done @*algorithmic* level (FFT, FIR, IIR…).
  - Sometimes data format not fully IEEE compatible for speed opt.

ADI Blackfin BF533 : IEEE-compliant vs. non IEEE-compliant library functions.

operation	fast-ft [cycles]	IEEE-ft [cycles]	ratio
multiply	93	241	0.4
add	127	264	0.5
subtract	161	329	0.5
divide	256	945	0.3
pow	8158	17037	0.5

- Power optimisation: s/w plays big role!
  - Minimise access to off-chip memory.
  - Use power-management API (not task!).
  - RTOS can help.

Power management (PWRM) added to DSP/BIOS for 'C5x DSPs.

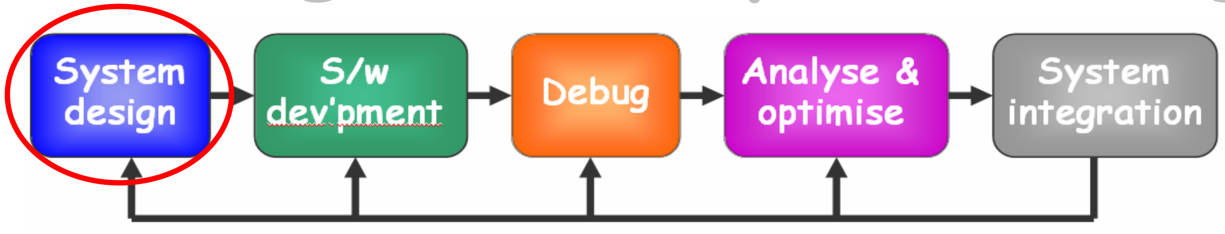


Chapter 8 summary

- Code optimisation: size, speed, power.
- Compiler optimisation rearranges code → turn optimisation ON after debugging!
- If compiler optimisation not enough → linear / hand-coded assembly.
- Development environment provides analysis tools: compiler consultant, cache/code size tune.
- Write efficient code from the start → optimisation guidelines.

Chapter 9 topics

RT design flow: system design



9.1 Introduction: DSP & architecture choice.

9.2 DSP : fixed vs. floating point

9.3 DSP: benchmarking

9.4 Architecture: multi-processing option

9.5 Architecture: radiation effects

9.6 Architecture: interfaces

9.7 Code design: interrupt-driven vs. RTOS

9.8 Code design: good practices

9.9 General recommendations

Summary

9.1 Intro: DSP & architecture

- DSP choice in industry: "4P" law (*Performance*, *Power consumption*, *Price*, *Peripherals*).
- DSP choice in accelerator sector: "*Power consumption*" factor negligible.
  - Standardisation in laboratory.
  - System evolution / migration to other machines.
  - Possible synergies.
  - Existing know-how / tools / hardware.

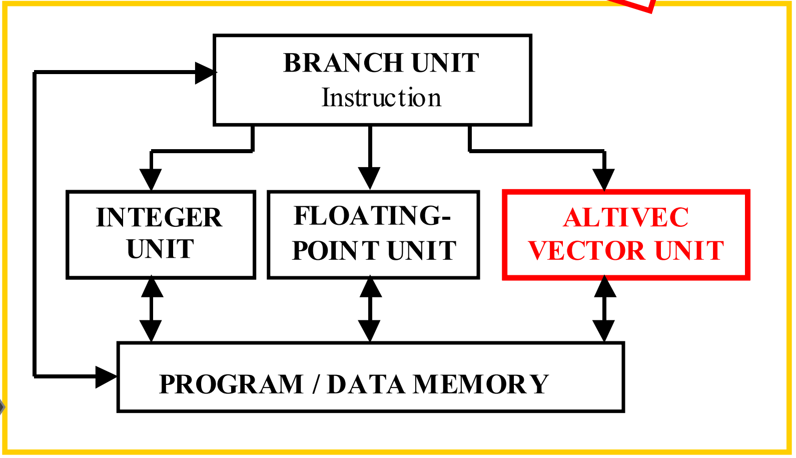
- **Global** decision needed for new systems

  3 main actors: **DSP**, **FPGA**, **f/end computer**.

  Know them to:
  - Decide which to use.
  - How to split tasks among them.

Not treated here

Motorola PowerPC + Altivec extension.
Altivec: SIMD expansion to PowerPC.



9.1 Intro: DSP & architecture [2]

Some points to be considered:

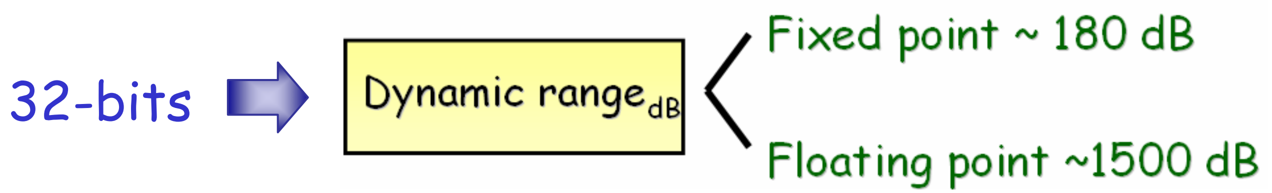
Which DSP:
- Fixed-point vs. floating point
- Benchmarking

System architecture
- Multi-DSP/multi-core
- Radiation effects
- Interfaces

DSP: how (code design)
- Interrupt-driven vs. RTOS
- Good practices

9.2 DSP: fixed vs. floating point

- Number format: influences DSP architecture



- **Fixed point: integer arithmetic**
  ☹ Scaling operations needed (*but* DSP features help, ex saturation)
  ☺ Fast (*but* scaling operations needed…)
  ☺ Algorithms (ex: MPEG-4 compression) bit-exact: made for fixed-point.

- **Floating point: integer/real arithmetic**
  ☹ High power consumption & slow speed (*but* scaling NOT needed)
  ☹ Expensive. DSP format often not fully IEEE-compliant (speed).
  ☺ High dynamic range helps many algorithms (ex.: FFT).

NB: Variable gap between numbers.
Large numbers → large gaps; small numbers → small gaps.

9.2 DSP: fixed vs. floating point [2]

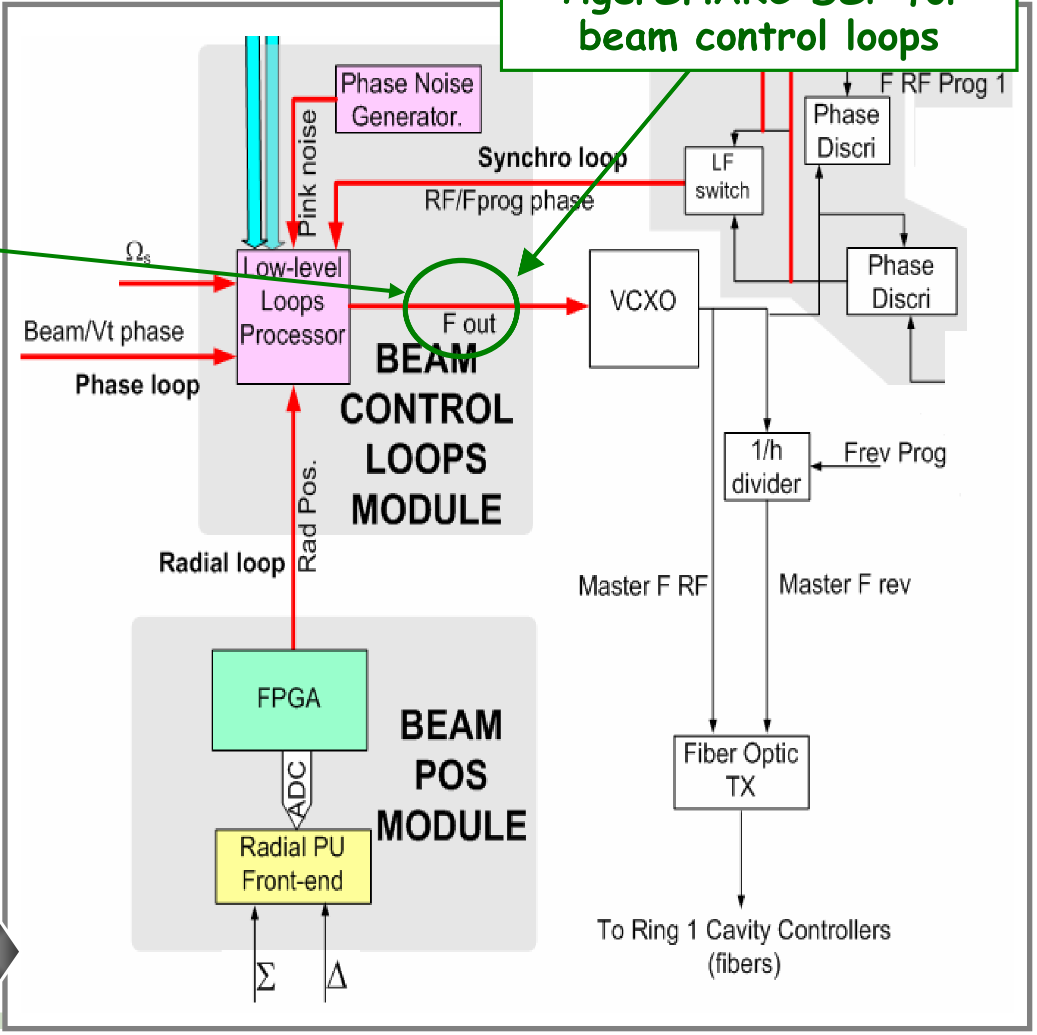
Floating point: often choice for accelerator but … CAREFUL!

LHC BC example

- Cavities @ ~400.78 MHz.
- F out:
  - ✓ format: unsigned int (16 bits)
  - ✓ resolution 0.15 Hz
  - ✓ range: 10 kHz from 400.7819 MHz
- Single floating: number spacing > 1 @400 MHz !
- TigerSHARC: h/w single-float, emulated double → loops calculations as offset from 400.7819 MHz.

TigerSHARC DSP for beam control loops

LHC beam control: zoom onto beam loops part.



9.3 DSP: benchmarking

- Performance commonly judged via metric set

METRIC	UNIT
Max clock frequency	[MHz]
Power consumption	[W or W/MIPS]
Execution speed	[MIPS, MOPS]
Memory bandwidth	[Mbytes/s]
Memory latency	[clock cycles]

Often misleading data!

Typical metric set & corresponding unit.

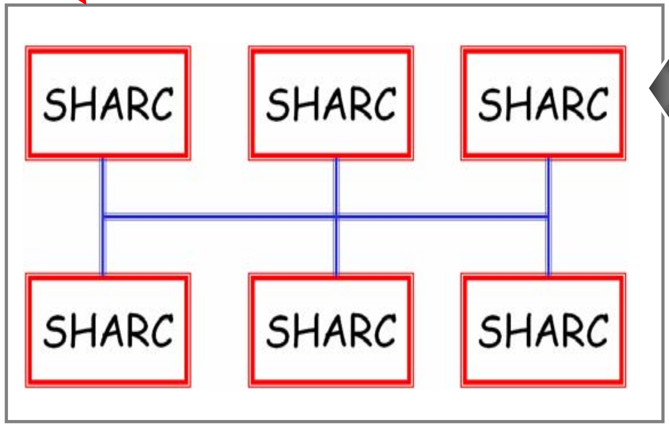
- Metrics often give peak/projected values. Difficult comparison!
  - **Clock frequency** can differ from instruction frequency.
  - ***MIPS***: VLIW DSPs have simple instruction set → one instruction does less work.
  - ***MOPS***: often based on MAC. Not included: control instructions & memory bottlenecks.
- Option: benchmark with kernel functions (ex: FFT, FIR, IIR…)

9.4 Architecture: multi-processor option

a) Multi-DSP

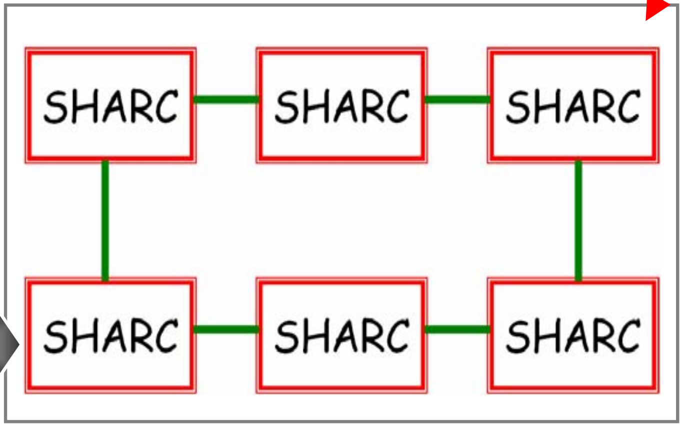
- Many DSPs collaborate to carry out processing.
- Essential: good application partition across DSPs.
- Inter-DSP communication channels: essential!
  - **Cluster bus**: resource sharing (ex: memory) & info broadcasting.
  - **Point-to-point bus**: direct communication among processing elements.

ADI SHARC DSP EXAMPLE



Cluster bus configuration

Point-to-point (ex: linkports) configuration

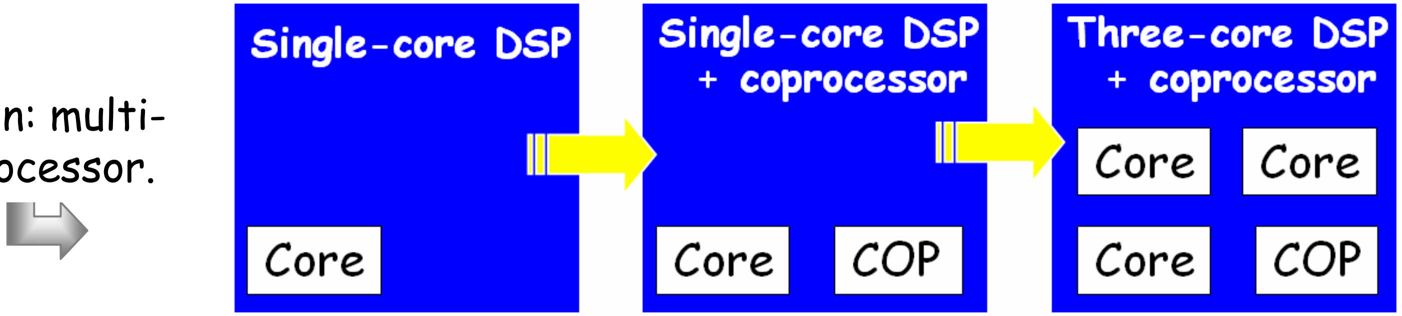


9.4 Architecture: multi-processor option [2]

b) Multi-core

- Multiple cores in same physical device: performance increase without architectural change.
  - Boosts effective performance: more gain for small core freq. increase.
  - Already-used philosophy: coprocessors (ex: Viterbi decoders).

DSP evolution: multi-core & coprocessor.



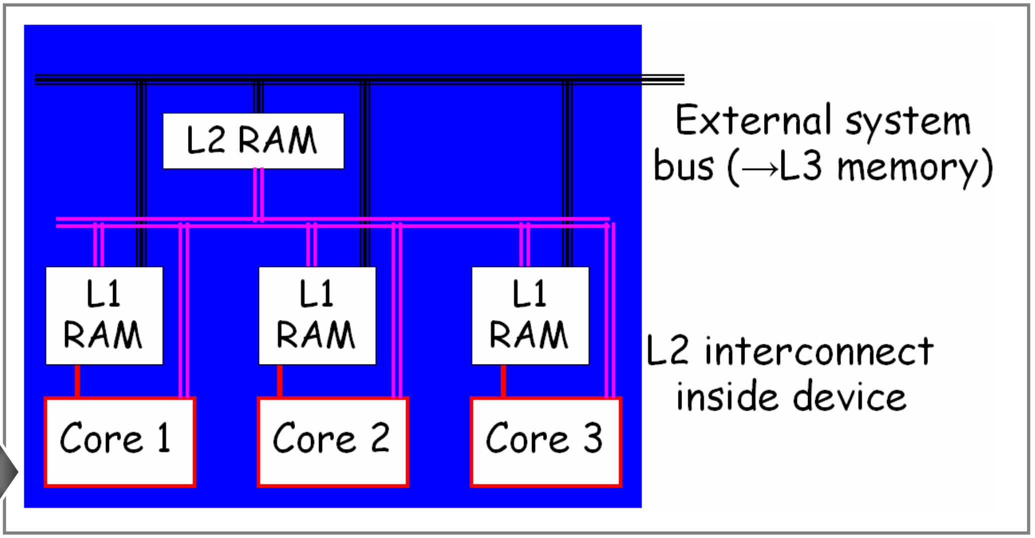
- Two main flavours:
  - Symmetric Multi-Processing (**SMP**): similar/identical DSPs.
  - Asymmetric Multi-Processing (**AMP**): DSP + MCU.
- Architecture options:
  - Cores operate independently (DSP farm).
  - Core interaction for task completion.

9.4 Architecture: multi-processor option [3]

b) Multi-core

- Resource partitioning:
  - @board level (like single-core case)
  - @ device level (added complexity).

Example of multi-core bus & memory hierarchy.


L2 RAM
L1 RAM
L1 RAM
L1 RAM
Core 1
Core 2
Core 3
External system bus (→L3 memory)
L2 interconnect inside device

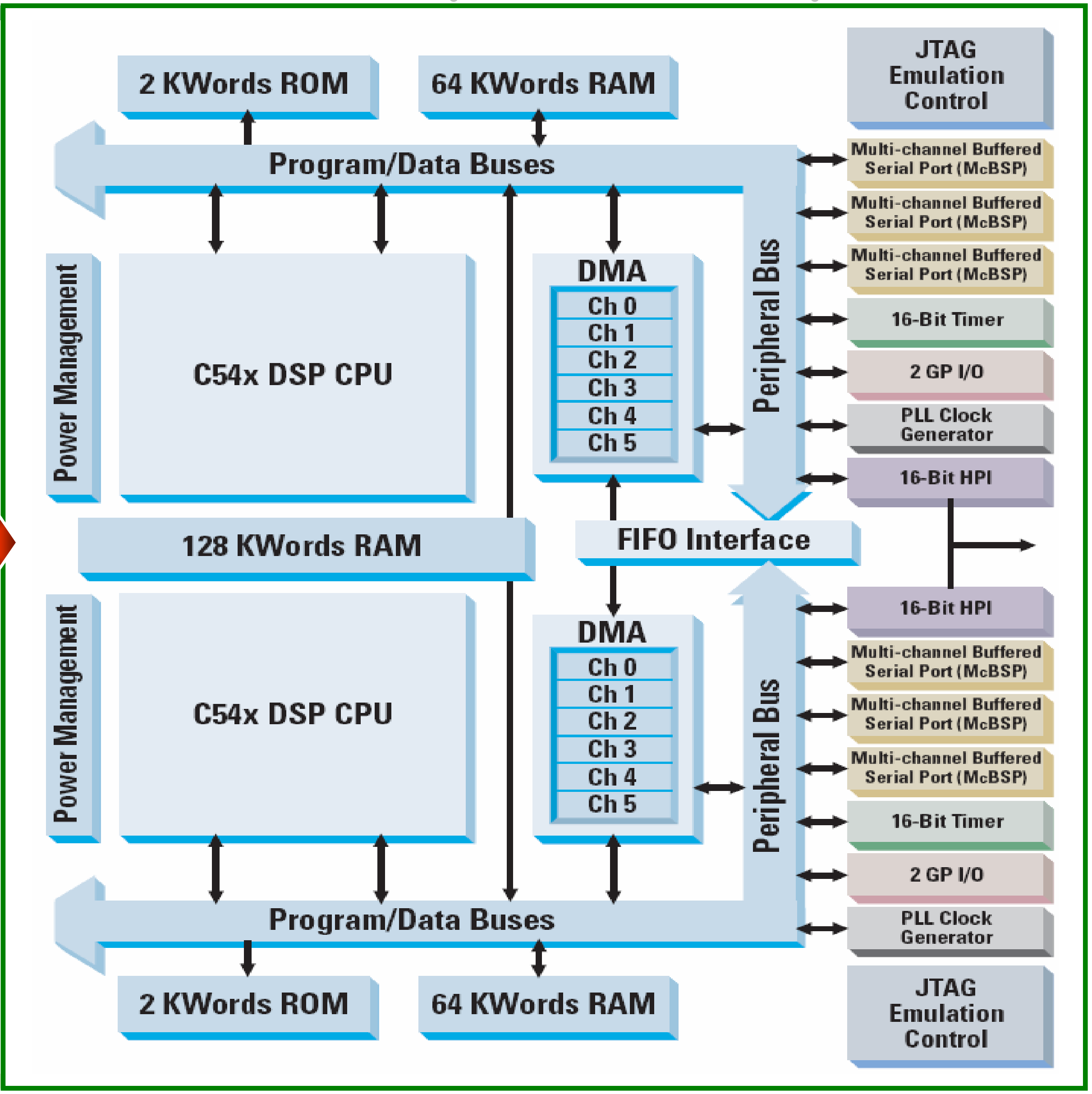
- Inter-core communication must be available.
- Programming complex : re-entrancy rules.
  - Needed to keep one's core processing from corrupting data of another core's processing.
  - Single-core follows re-entrancy rules for multitasking, too.

9.4 Architecture: multi-processor option [4]

b) Multi-core

SMP example:

TMS320C5421 multi-core DSP



9.5 Architecture: radiation effects

- Single Event Upset (SEU): radiations-induced circuit alterations.
- General mitigation techniques:
  - **Device level**: extra doping layers to limit substrate charge collection.
  - **Circuit level**: decoupling resistors/diodes/transistors… for SRAM.
  - **System level**:
    - ✓ Error Detection & Correction (EDAC) code…
    - ✓ Algorithm-based fault tolerance (ex: Weighted Checksum Code). Rounding errors + weights overflow → difficult with floating point!
- ADI/TI: no rad-hard DSP offered (third-party companies offer ADI/TI rad-hard versions).
- Application example: CERN LHC power supply controllers.
  - TI DSP 'C32 + MCU (non rad-hard).
  - EDAC for SRAM protection.
  - Watchdog to restart system if it crashes.

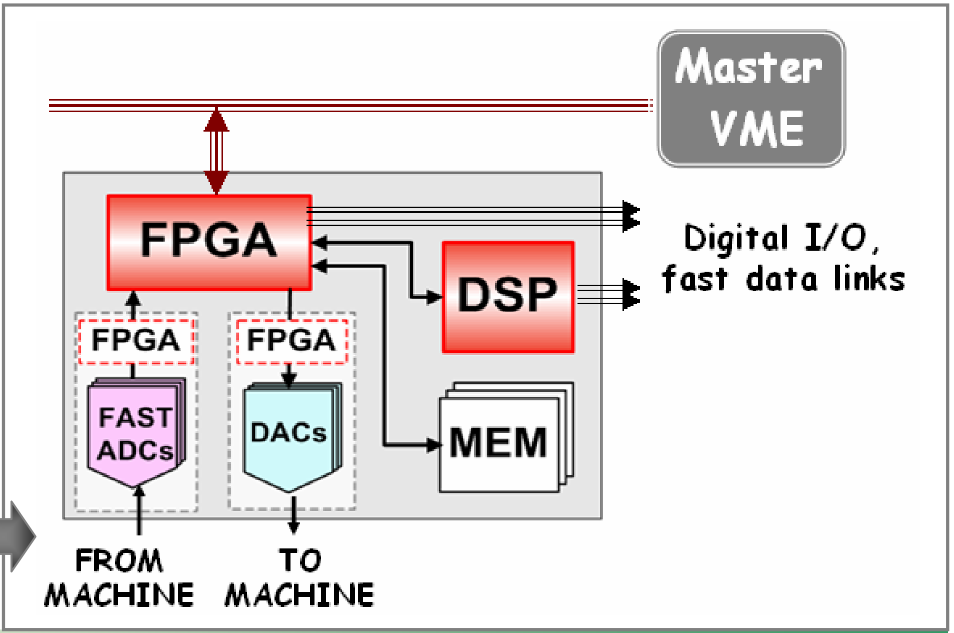
9.5 Architecture: interfaces

- DSP interface to define:
  - DSP-DSP
  - DSP-FPGA
  - Timing
  - DSP-Master VME (control + diagnostics)
  - DSP-daughtercards
- Don't hard-code addresses in DSP code – use linker!
- Create data access libraries → modular approach (upgradeable!).

Remember:

good fences make good neighbours!

Digital system: typical building blocks



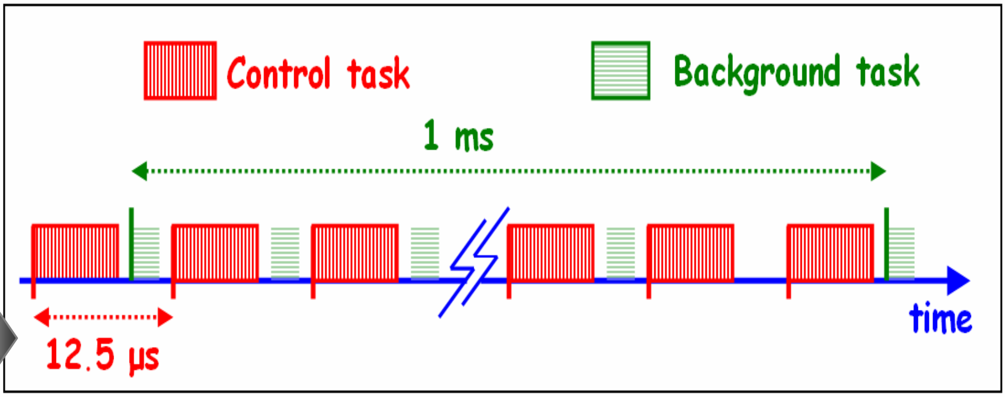
9.6 Code design: interrupt-driven vs. RTOS

- Fundamental choice. Depends on: { System complexity / Available resources

- **Interrupt-driven** : threads defined / triggered by interrupts.
  - Optimum resource use
  - OK for limited interrupt number.

- **RTOS-based** : RTOS manages threads + priority + trigger.
  - Some resources used by RTOS
  - Clean design + built-in checks

Interrupt-driven control & background tasks.



9.7 Code design: good practices

- Digital system *NOT* black box. Add diagnostics buffer: user-selectable / post-mortem / circular.
- Add version number to identify significant code release.
- Add **check on execution duration**. Essential for interrupt-driven systems.

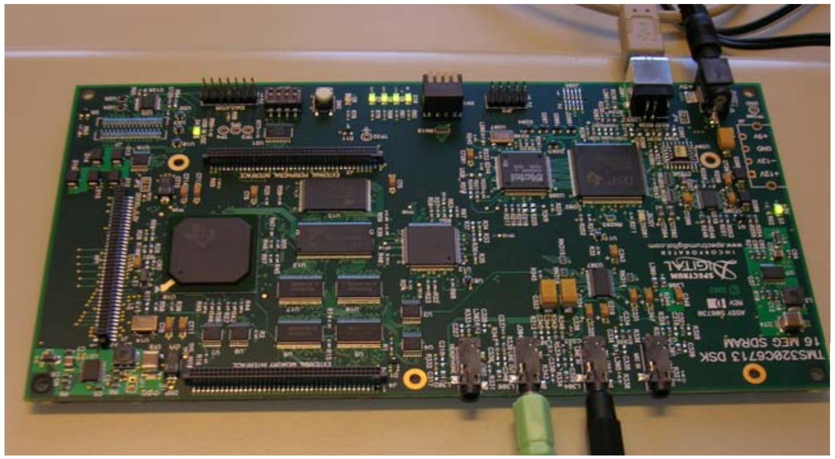
64-bit counter incremented unconditionally @every instruction cycle.

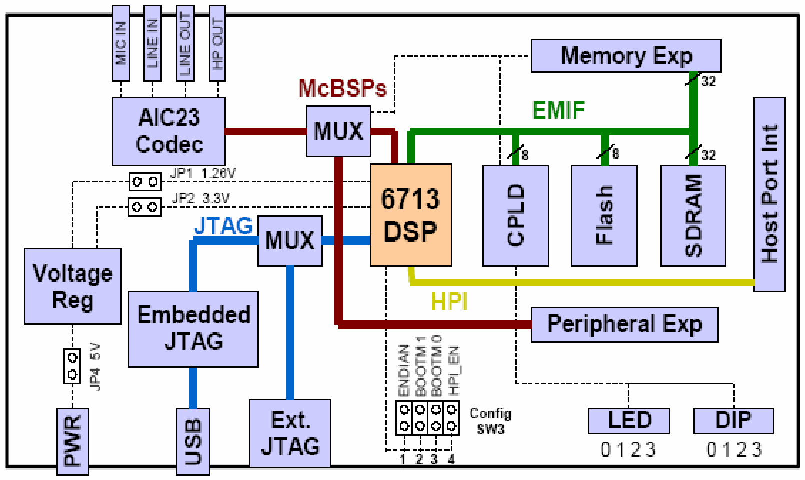
```
ustat3 = emuclk;   // read time @execution start

   CRITICAL
    ACTION

r0 = emuclk;       // read time @execution end
r1 = ustat3;
r1 = r0 - r1;      //calculate execution time
```

ADI SHARC: *emuclk* registers and their use.

9.8 General recommendations

- Careful with new DSPs – could be beta-versions !
- Look @ DSP anomalies list.
- Gain s/w experience with development environment & simulator.
  - ADI & TI give 90-days fully-functional free evaluation of their tools.
- Gain s/w + h/w experience with eval. boards: easy prototyping.
  - Helps solving technical uncertainties!





TI C6713 DSK: picture & block diagram.

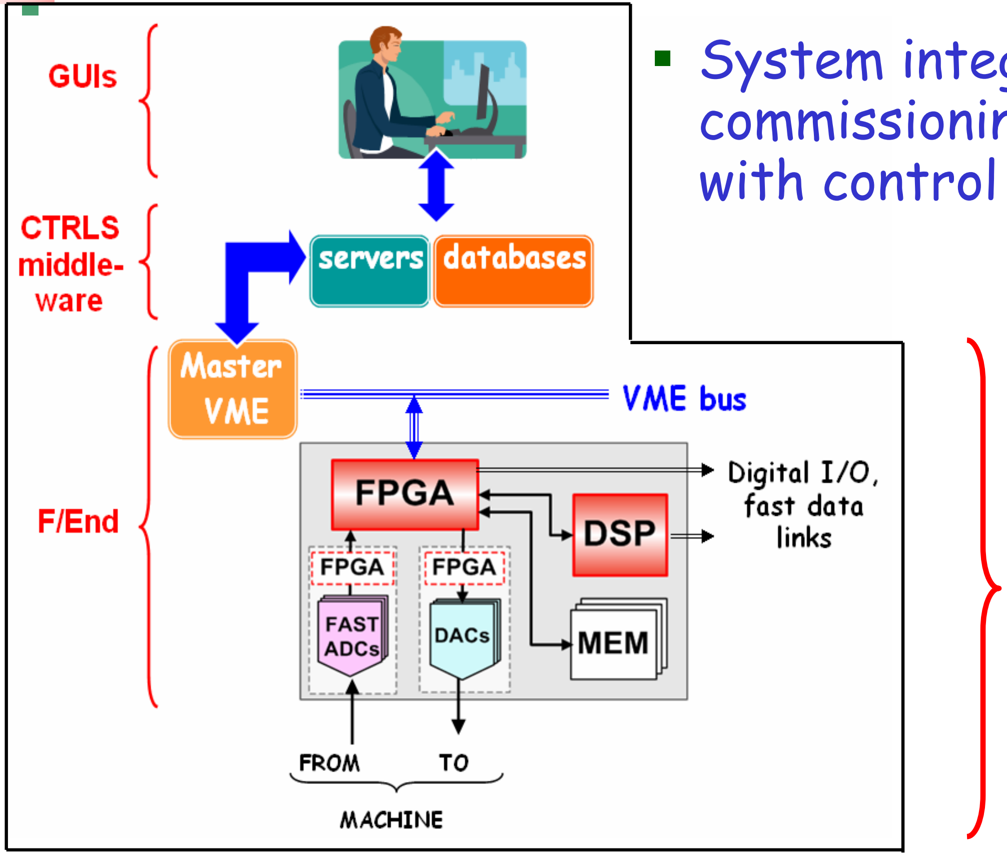
Chapter 9 summary

- DSP & architecture choice: influenced by many factors.
- Which DSP:
  - Fixed-point vs. floating point : LHC BC example
  - Benchmarking: careful, often misleading!
- System architecture:
  - Multi-DSP / multi-core.
  - Radiation effects.
- DSP: code design
  - Interrupt-driven vs. RTOS
  - Good practices
- General recommendations:
  - β-beware, anomalies
  - Fully functional s/w evaluations
  - Use evaluation boards!

Chapter 10 topics

RT design flow: system integration

10.1 Introduction



- System integration = system commissioning, limited to data exchange with control infrastructure & applic. prog.

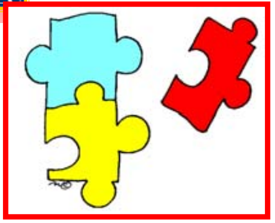
Typically digital developer works here

- Different developers (groups) involved: Instrumentation + Controls + Operation → coordination & specification work needed.
- Possibly slow: developers (groups) have different priorities.

10.2 Good practices

- **Work in parallel**
  - Start planning all layers **asap** → do not wait for low-level completion!
- **Interfaces**
  - Clear, documented & agreed upon.
  - Useful: recipes on how to setup/interact etc.
  - Keep documents updated & on server !
- **Input checks**
  - Check input validity → warnings/alarms
- **Spare parameters (in/out)**
  - Mapped DSP ⇄ application prg.
  - Small upgrades / debug added without new iterations.
- **Code releases**
  - Save current release + description. Going back easier if troubles.
- **Code validation**
  - Define data set + procedure for sub-system validation.

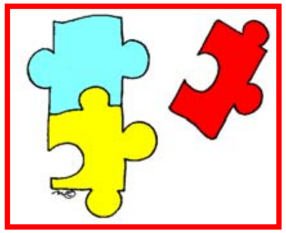
Chapter 11



Putting it all together…

A digital system example:

CERN LEIR LLRF

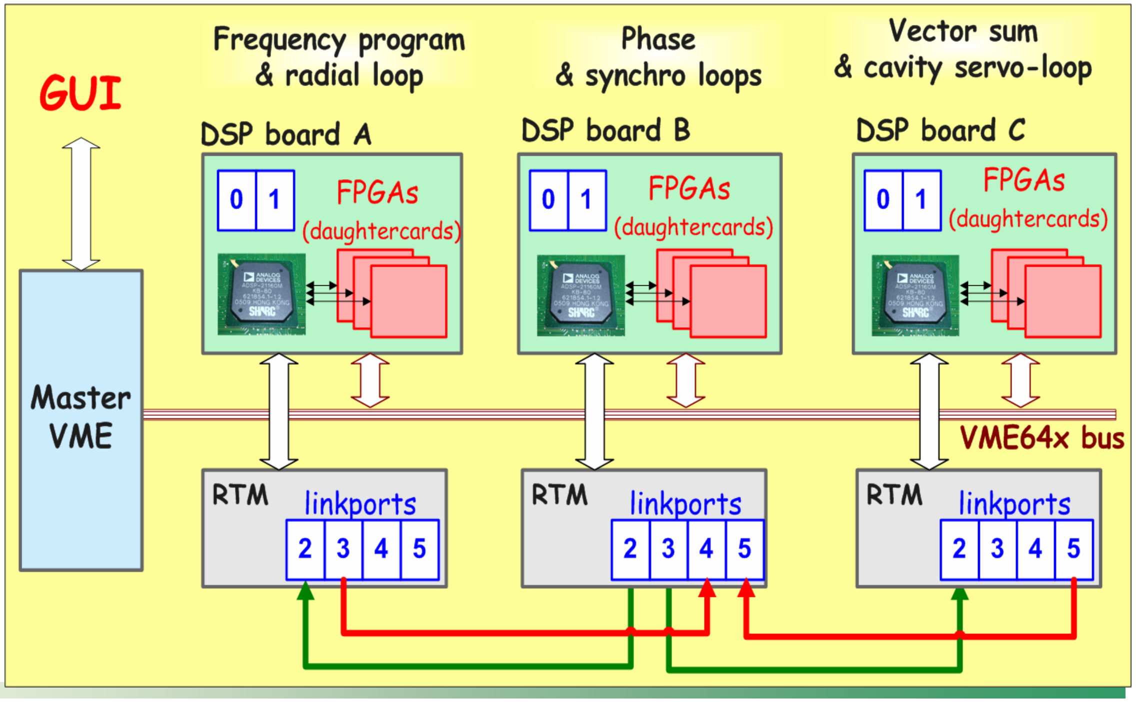


i.e. how now you know more on DSP fundamentals & system design than two days ago!

11. Example: CERN LEIR LLRF

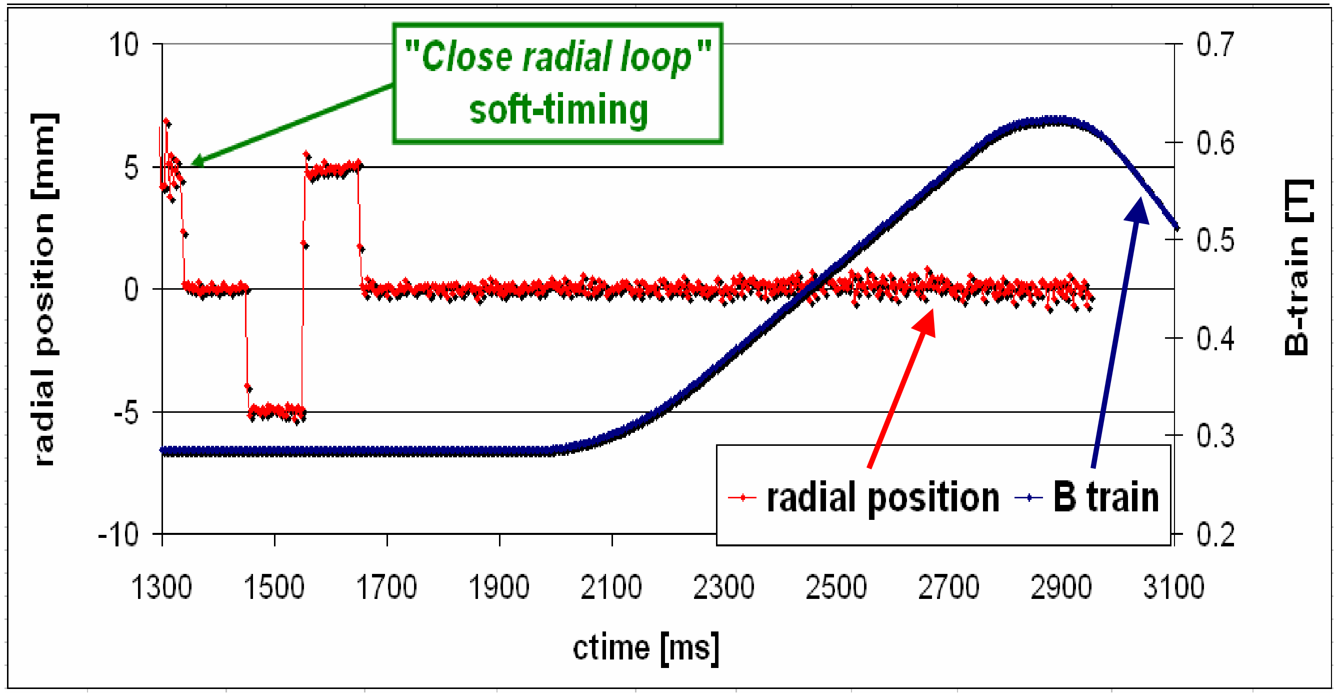
- **Components**: [→ chapter 9]
  - **DSP**: beam loops implementation
  - **FPGA**: fast processing + glue-logic.
  - **PowerPC**: LLRF management & controls interface.
- **Architecture**: interrupt-driven + multi-DSPs [→ chapter 9]
- **DSP-DSP comms.**: linkports + chained DMA. [→ chapters 4, 3, 9]
- **SRAM** shared DSP-Master VME (FPGA access arbitration). [→ chapter 4]

CERN LEIR LLRF system.



11. Example: CERN LEIR LLRF [2]

- **DSP boots** from on-board FLASH memory. [→ chapter 4]
- **Languages**: C + assembly (ISR + shadow registers). [→ chapter 6]
- **Diagnostics buffers**: four, 1024-word buffers / DSP board. User-selectable decimation & signal (~50 / DSP board) [→ chapter 9]



CERN LEIR LLRF system: radial position (red line) & B field (blue line) during a cycle.

DSP fundamentals & system design: summary

- DSPs born early '80s: evolution in h/w + s/w tools.
- **DSP core architecture** shaped by DSPing.
- **DSP peripherals** integrated & varied.
- RT design flow: **s/w development**.
  - Languages: assembly, C, C++, graphical. RTOS
  - Code building process: compiler, assembler. linker
- RT design flow: **debugging**
  - Simulation/Emulation
- RT design flow: **analysis & optimisation**
- RT design flow: **system design & integrations**