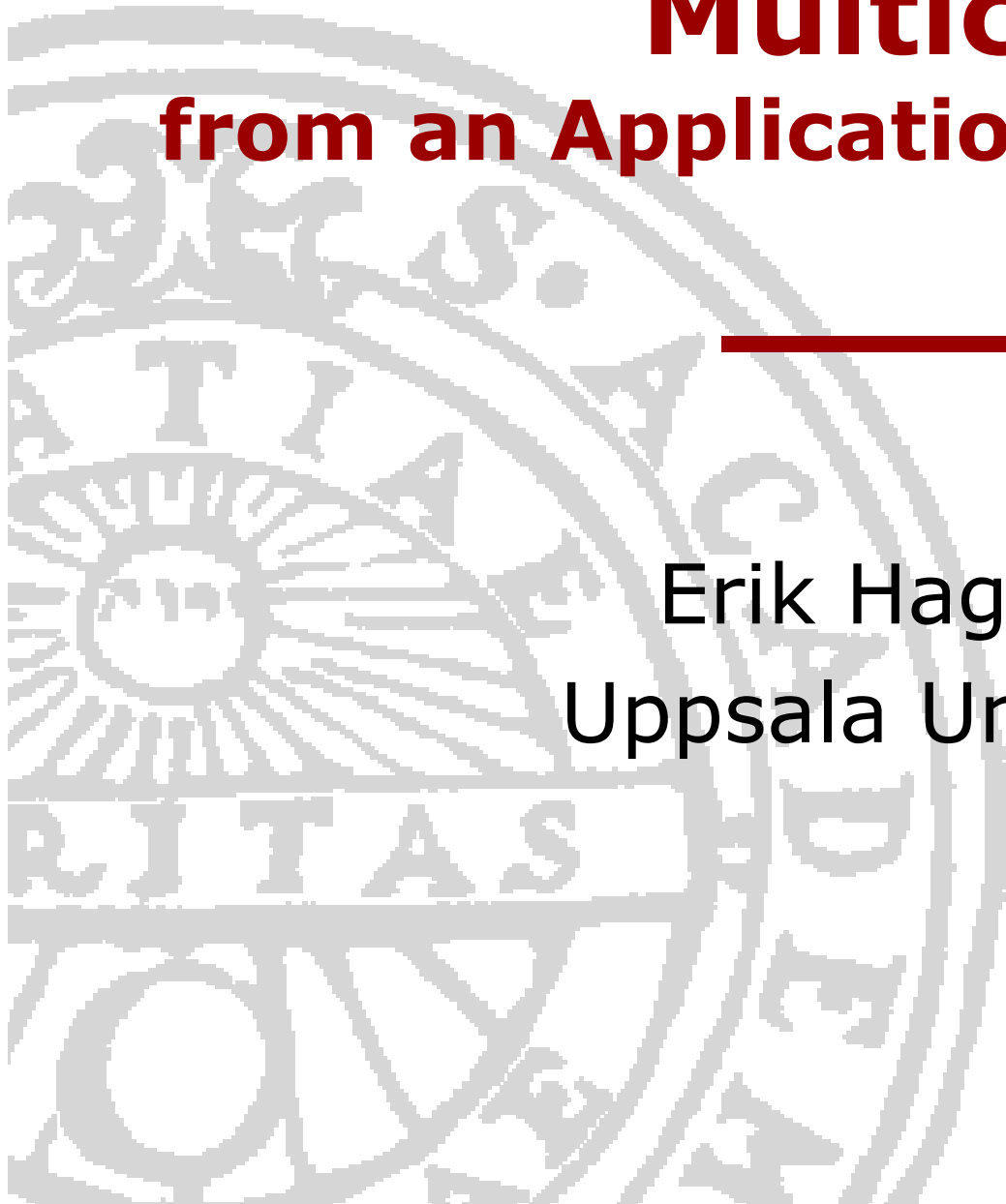


Multicore

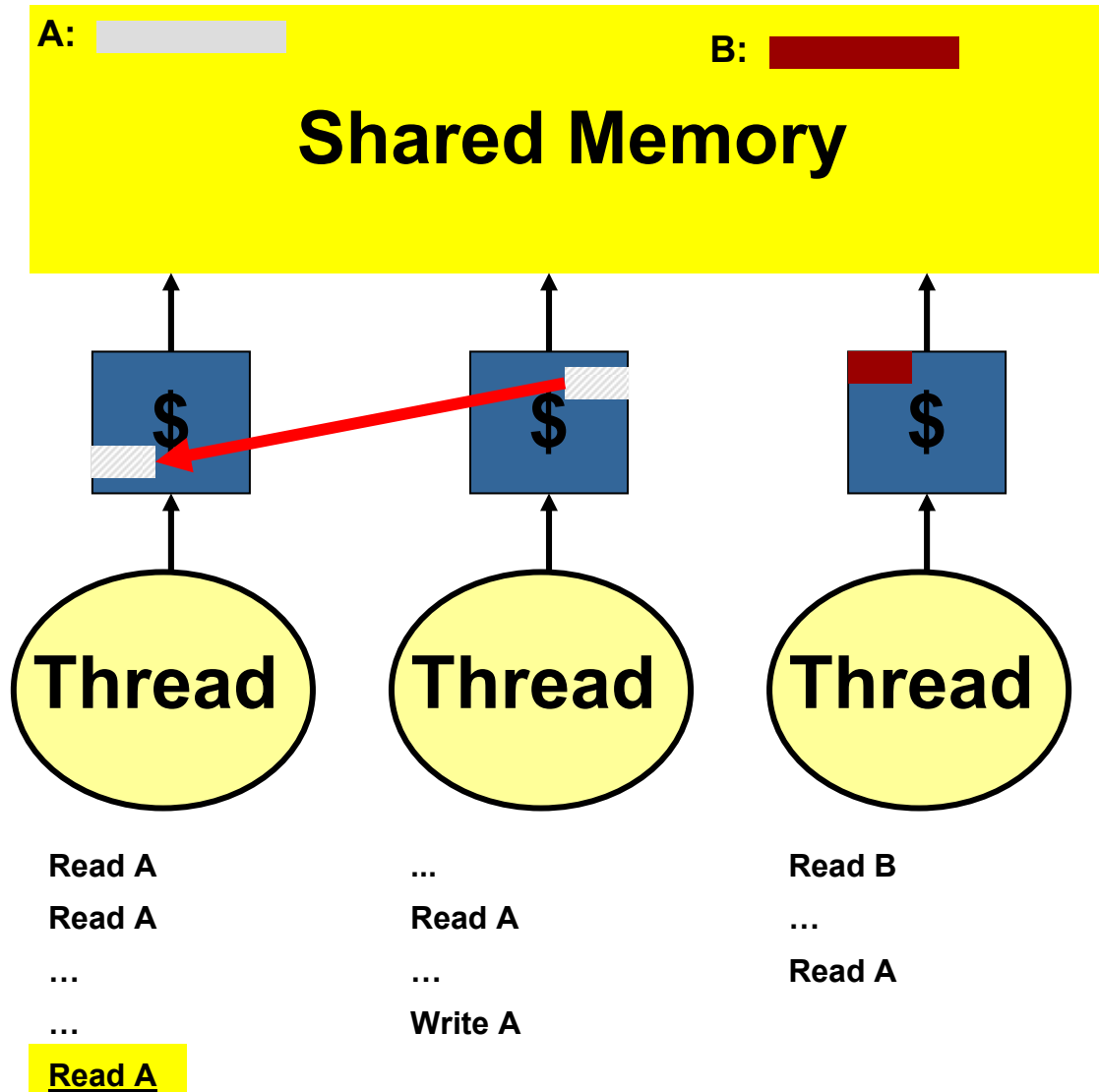
from an Application's Perspective

Erik Hagersten
Uppsala Universitet



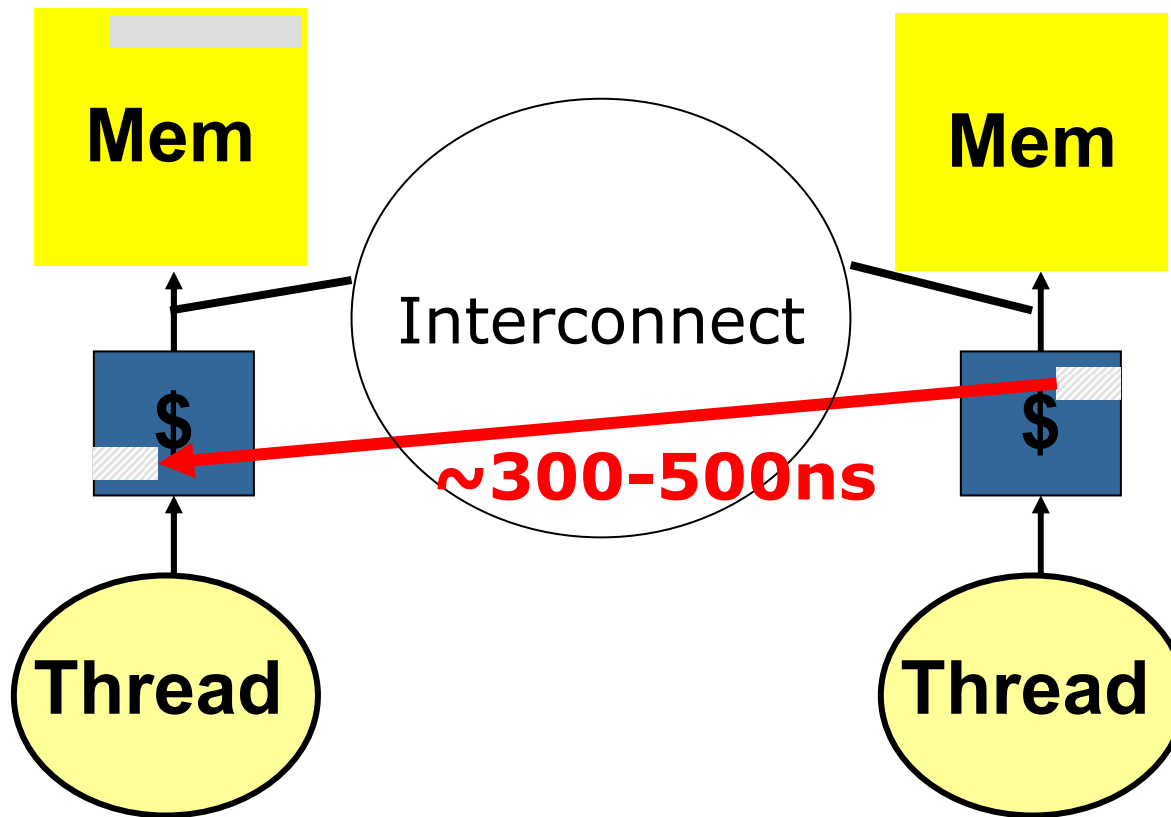


Communication in an SMP





Communication in a NUMA → Worse



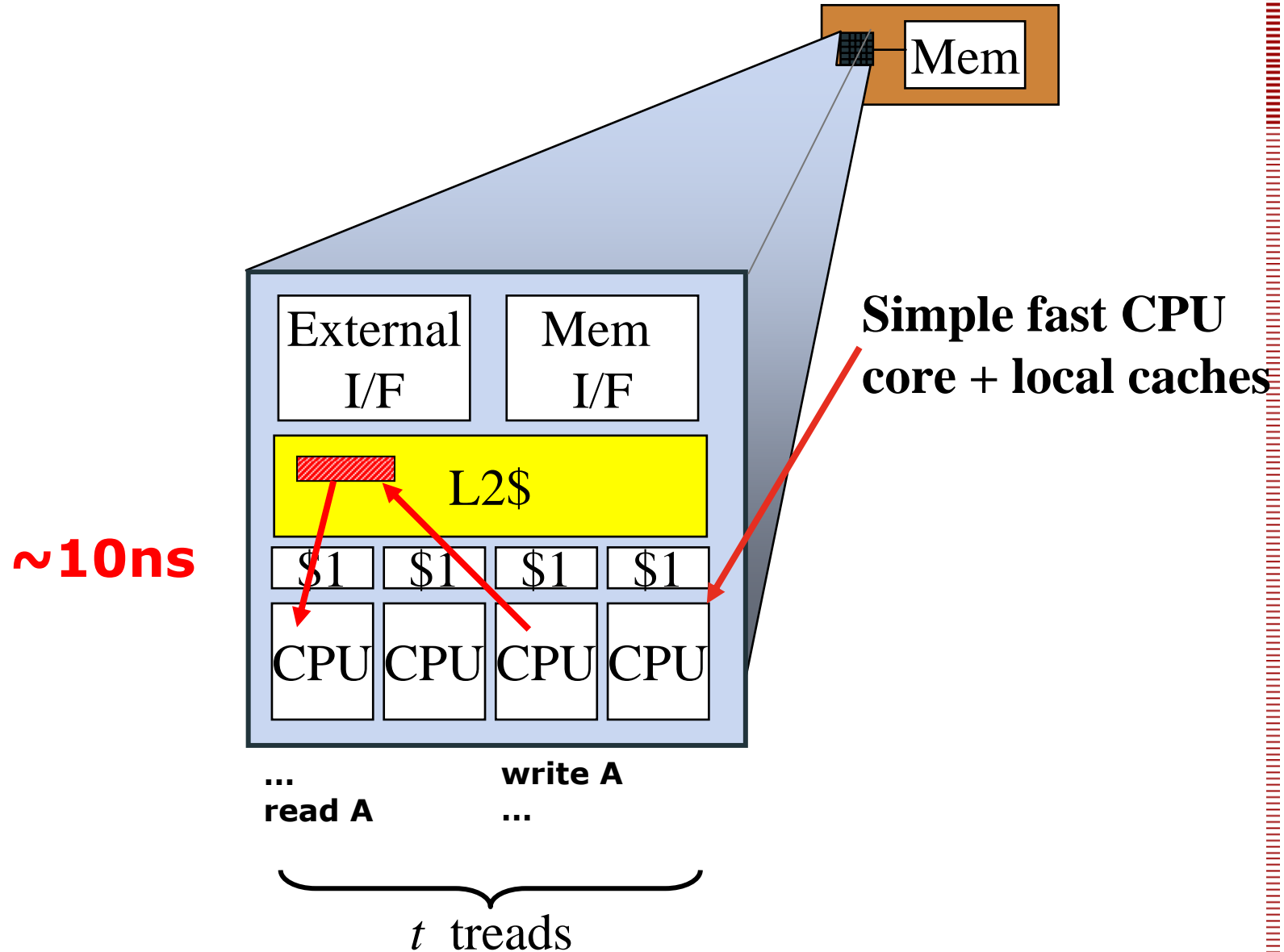
Read A
Read A
...

Read A

...
Read A
...
Write A

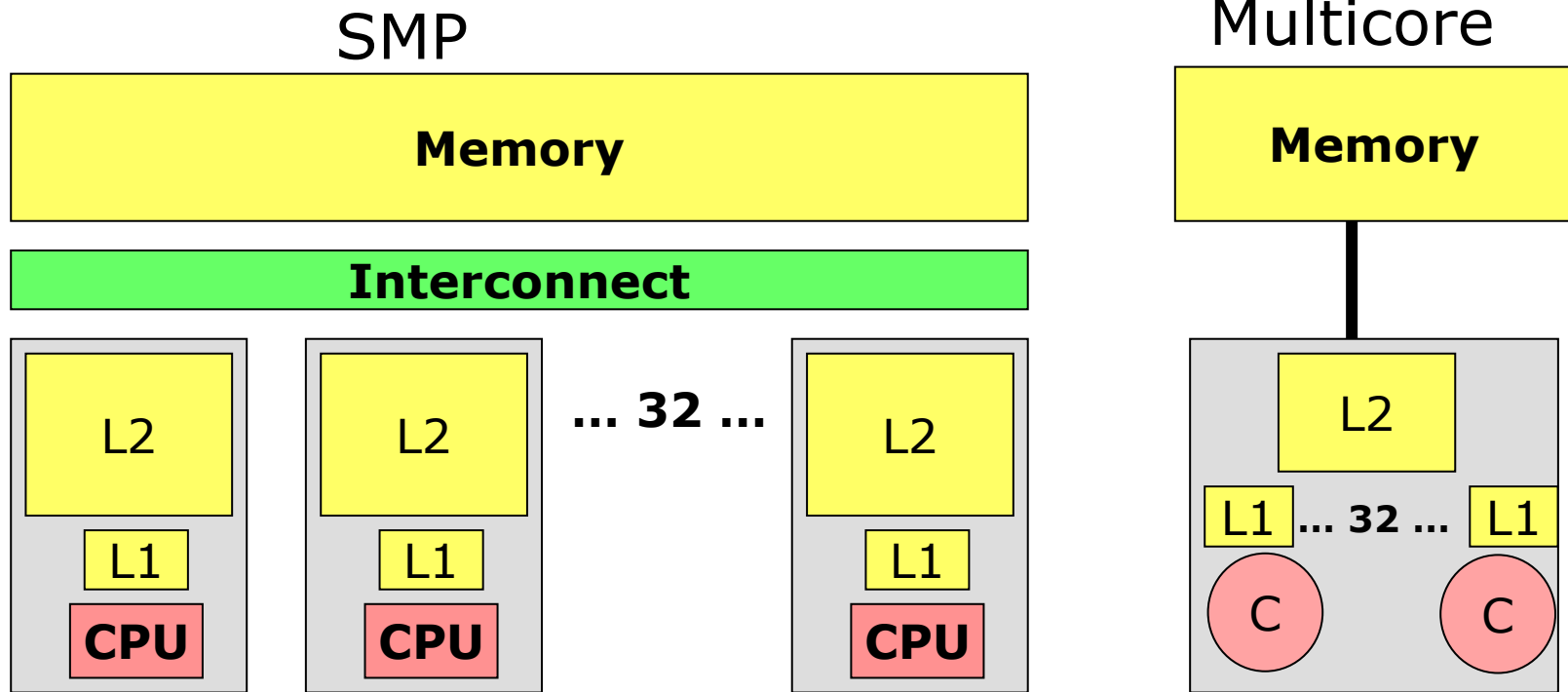


Communication in [some] Multicores





Looks and Smells Like an SMP?



Well, how about:

- Cost of thread communication?
- Cache capacity per thread?
- Memory bandwidth per thread?

→Gotta' Optimize For Locality!



Criteria for HPC Algorithms

■ Past:

- ✱ Minimize **communication**
- ✱ Maximize scalability (1000s of CPUs)

■ Multicores today:

- ✱ Communication is “for free”
[on some multicores]
- ✱ Scalability is limited to 32 threads
- ✱ The caches are tiny
- ✱ Memory bandwidth is scarce

➔ **Data locality is key!**

(Both for Capacity and Capability Computing!)

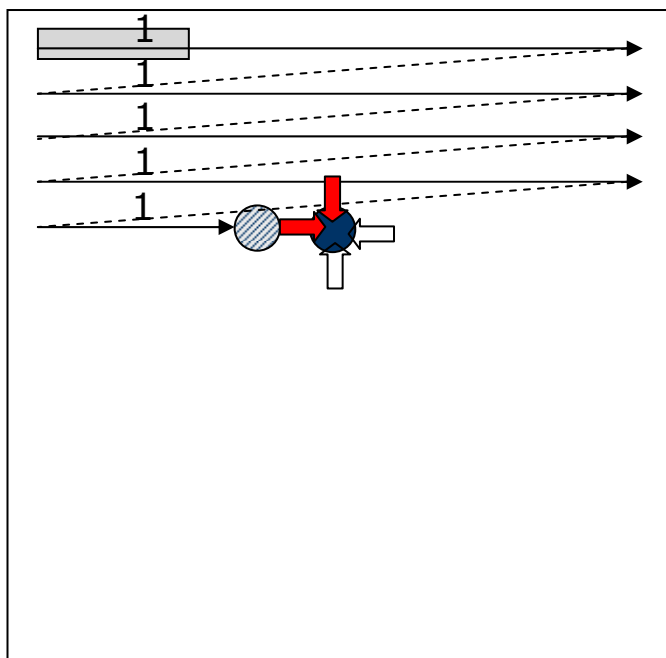


Case Study: Gauss-Seidel on Multicores

Erik Hagersten
Uppsala University
Sweden

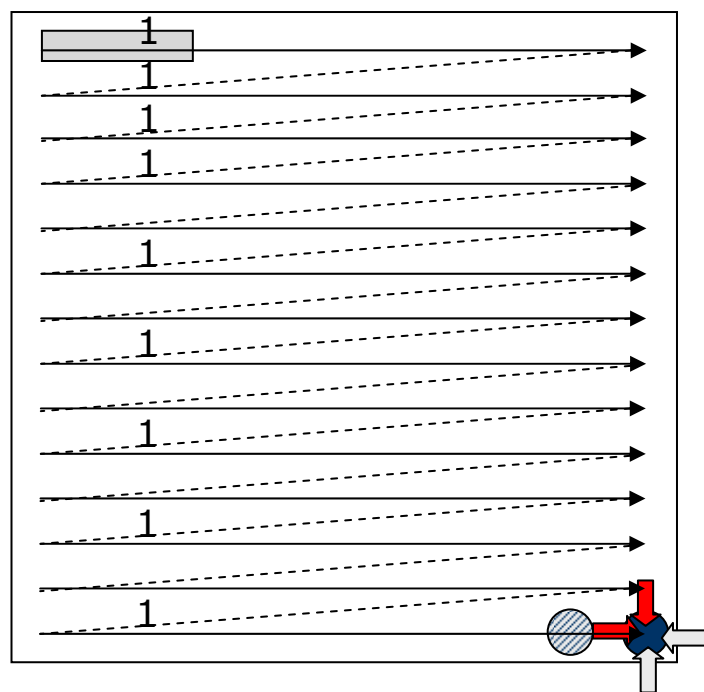
**Thanks: Dan Wallin(arch), Henrik Löf (sci comp) and
Sverker Holmgren (sci comp)
From Wallin et al, ICS 2006**

Natural Order Gauss-Seidel



- = sweep path
- ⊘ = previous
- = current
- ➔ = data dependence
- 1,2,3,4 = iteration number
- ▭ = cacheline layout

Natural Order Gauss-Seidel

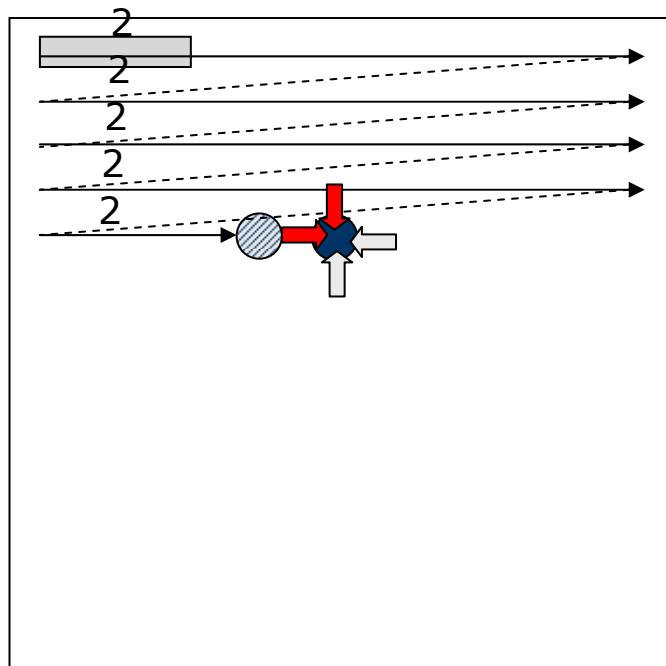


- = sweep path
- ⊙ = previous
- = current
- ➔ = data dependence
- 1,2,3,4 = iteration number
- ▭ = cacheline layout

```

IF (convergence_test)
  <done>
else
  <iterate again>
  
```

Natural Order Gauss-Seidel



- = sweep path
- ⊘ = previous
- = current
- ➔ = data dependence
- 1,2,3,4 = iteration number
- ▭ = cacheline layout

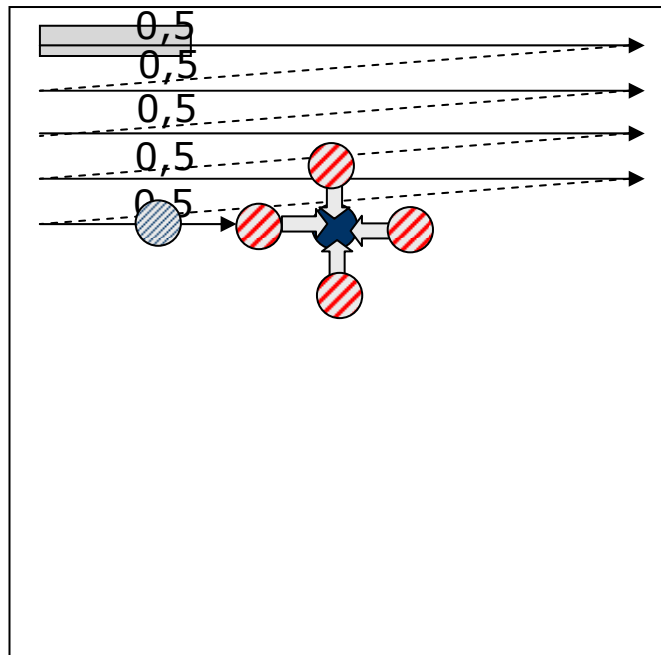
Data dependence → Poor Parallelism ☹️



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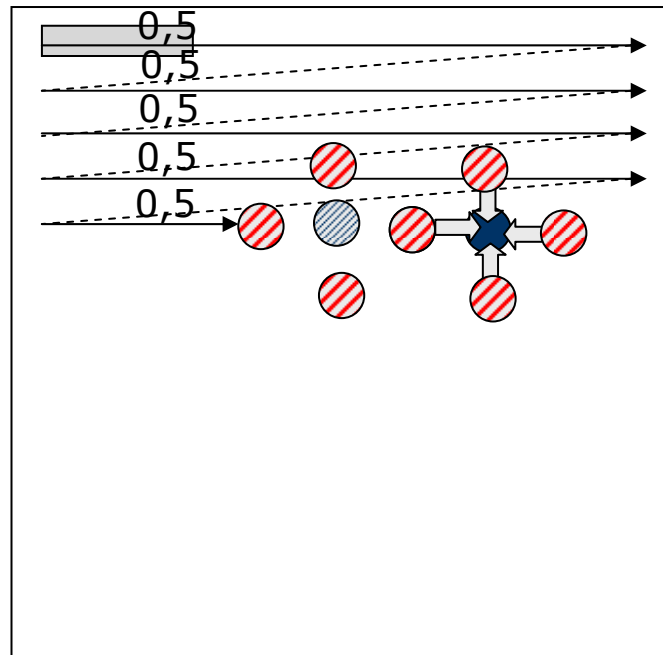
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Red-Black Gauss-Seidel



- = sweep path
- (hatched) = previous
- (blue) = current
- ➔ (red) = data dependence
- 1,2,3,4 = iteration number
- ▭ (gray) = cacheline layout

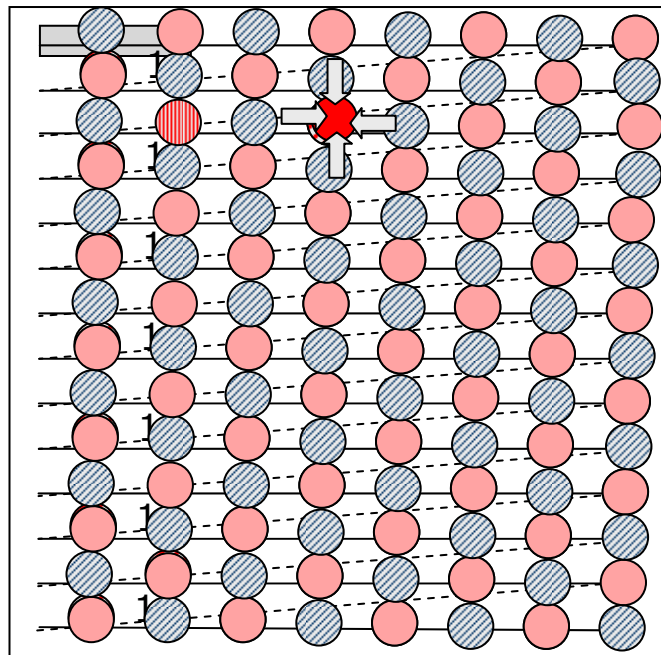
Red-Black Gauss-Seidel step 0,5: update the blacks



- = sweep path
- ⊘ = previous
- = current
- = data dependence
- 1,2,3,4 = iteration number
- ▭ = cacheline layout



Red-Black Gauss-Seidel step 1,0 update all reds



- = sweep path
- = previous
- = current
- = data dependence
- 1,2,3,4 = iteration number
- = cacheline layout

Update all blacks

<barrier>

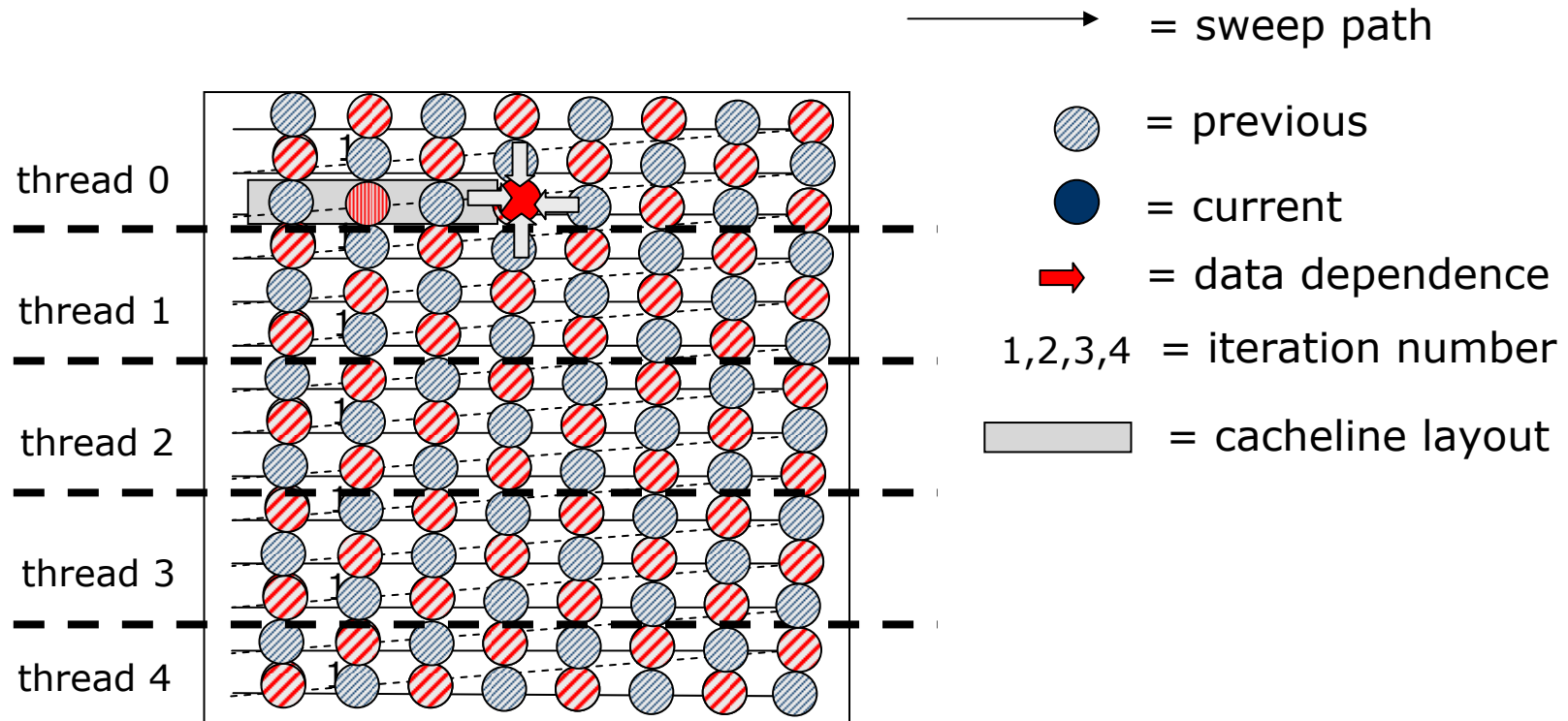
Update all reds

<barrier>

→ great parallelism!!!



Red-Black Gauss-Seidel Parallel version



IN PARALLELL {
Update all blacks
<barrier>
Update all reds
<barrier>
}

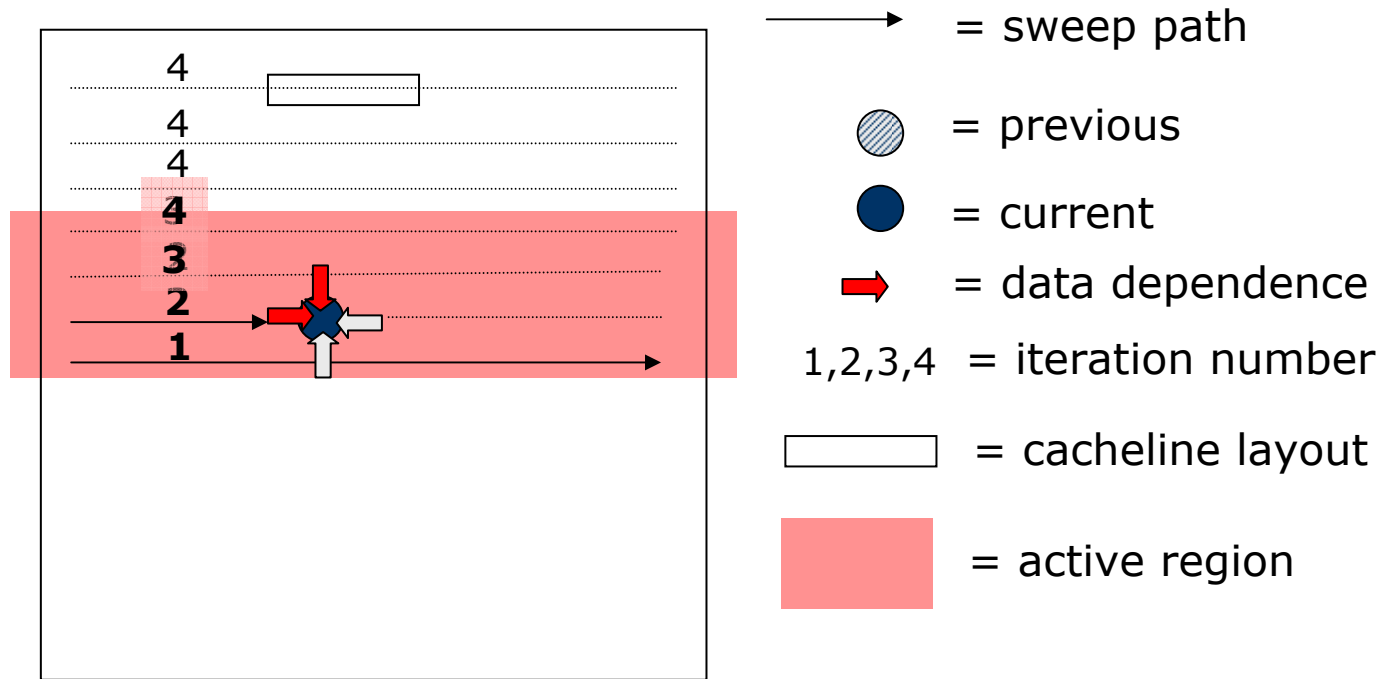


Any Drawbacks of the Red-Black?

- Poor Cache Locality of Red-Black:
 - ✱ Each element will be brought into the cache **twice** per iteration ☹️
- Natural Order:
 - ✱ Each element will be brought into the cache **once** per iteration ☺️
- You can do even better...
 - ➔ Natural Order with **Temporal Blocking** ☺️

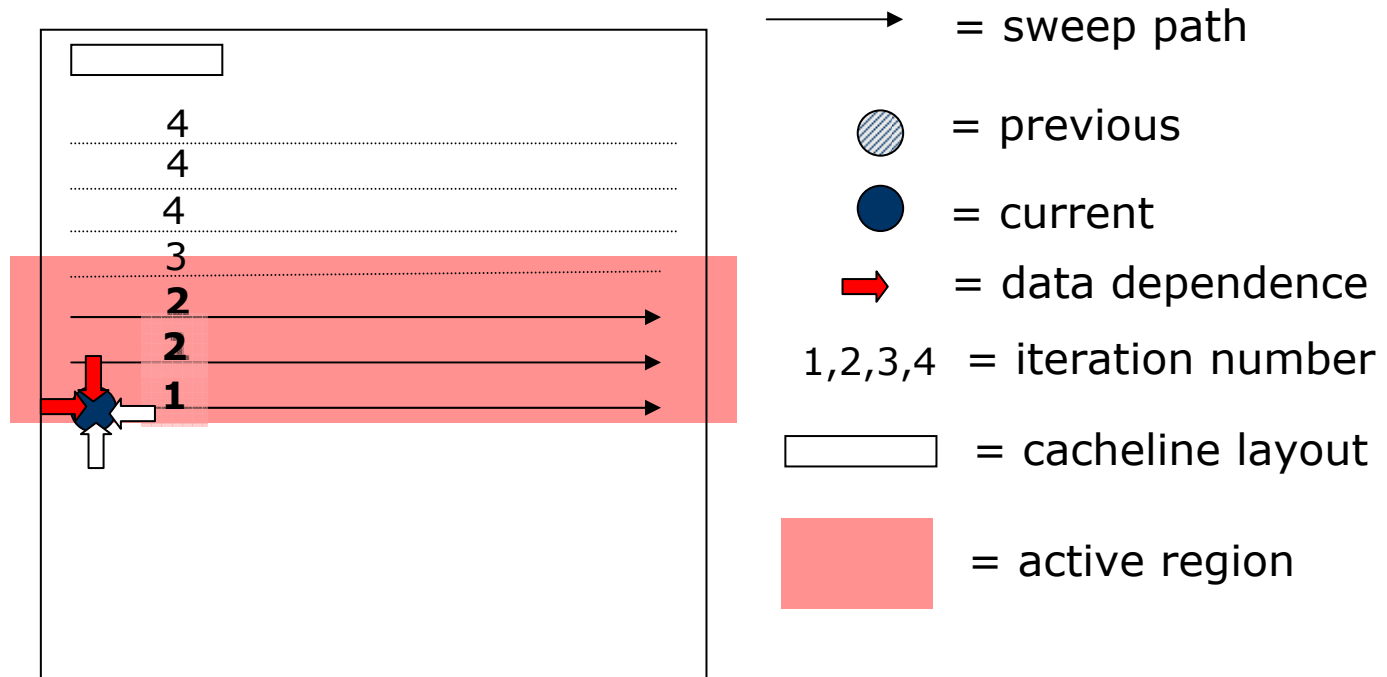


G-S, temporal blocking: several iterations per sweep





G-S, temporal blocking: several iterations per sweep



In this case: 4 iterations per "sweep". ($\sigma = 4$)

$\sigma = 1,0$ for natural order G-S

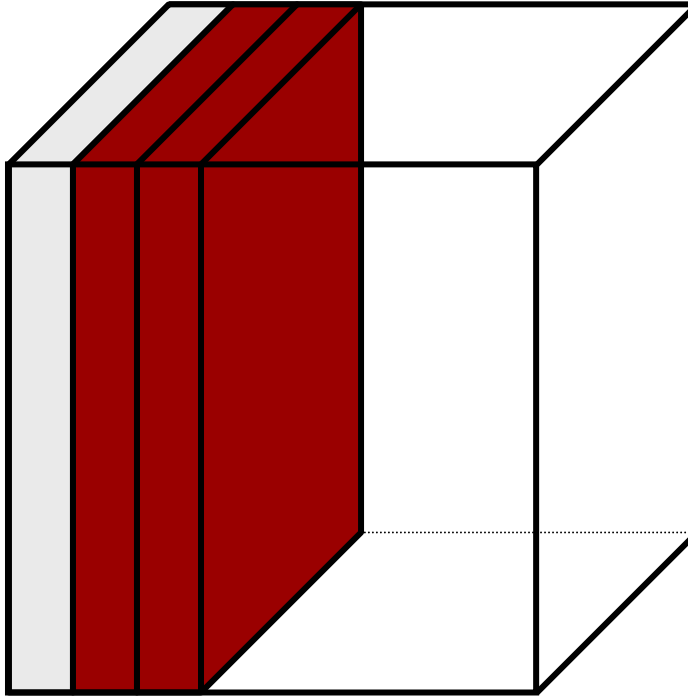
$\sigma = 0,5$ for red-black G-S



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G-S 3D, $\sigma=2$





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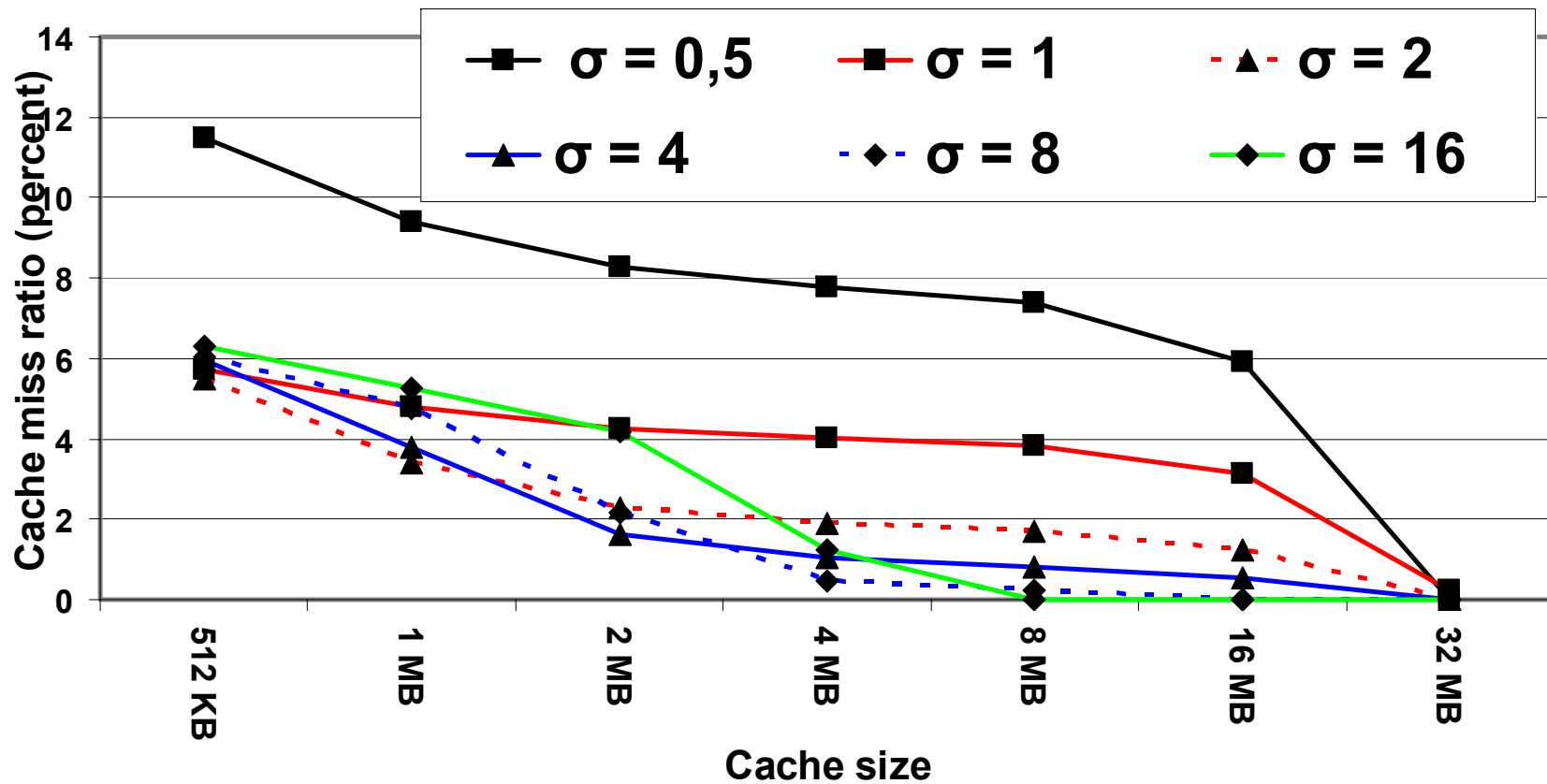
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G-S 3D, $\sigma=2$





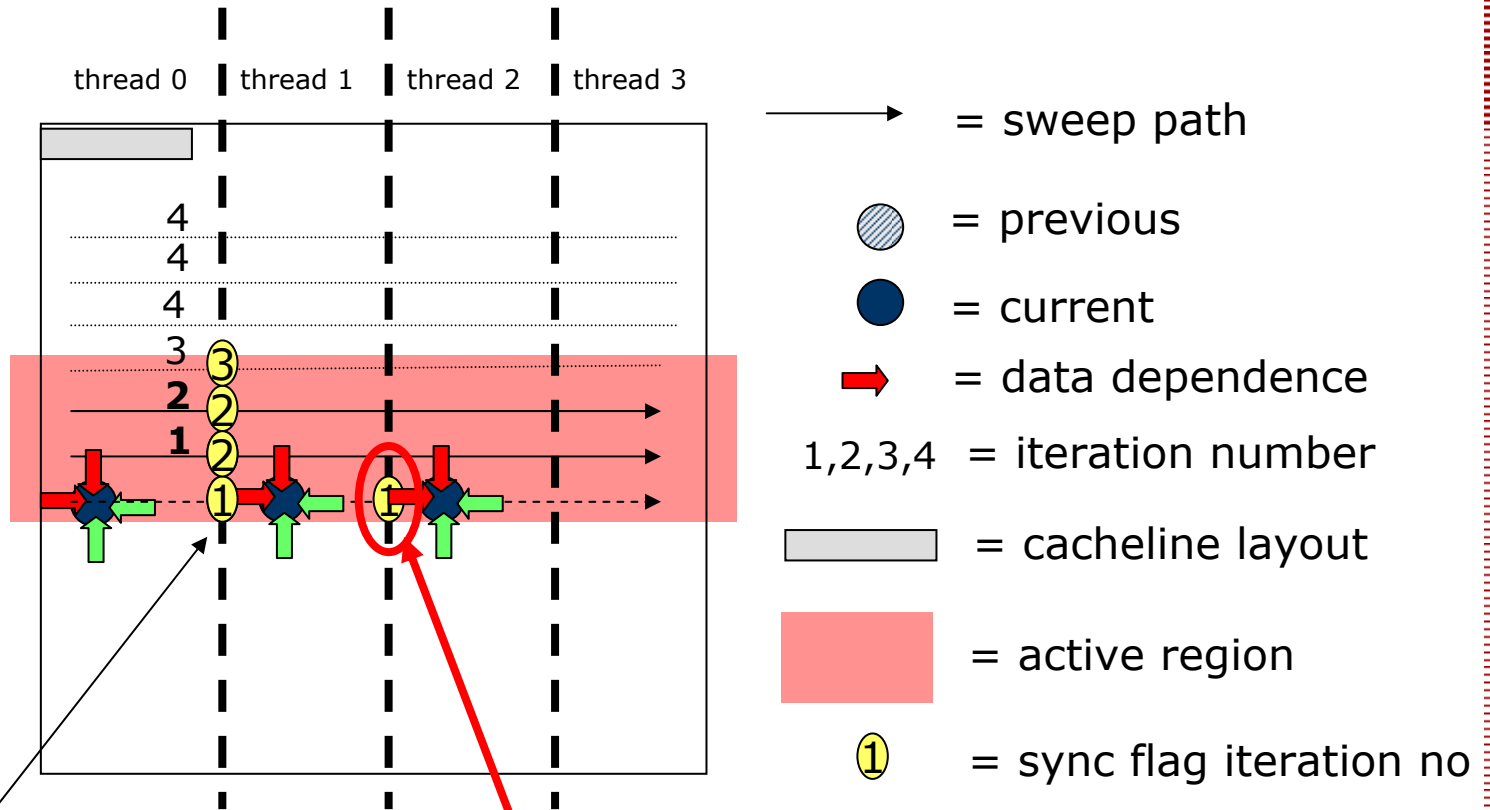
Acumem Graph, 3D N=129



Miss ratio \sim Memory bandwidth



Parallel G-S, temporal blocked



Synchronization flags

Wait until "lefty" is done:
Lots of communication

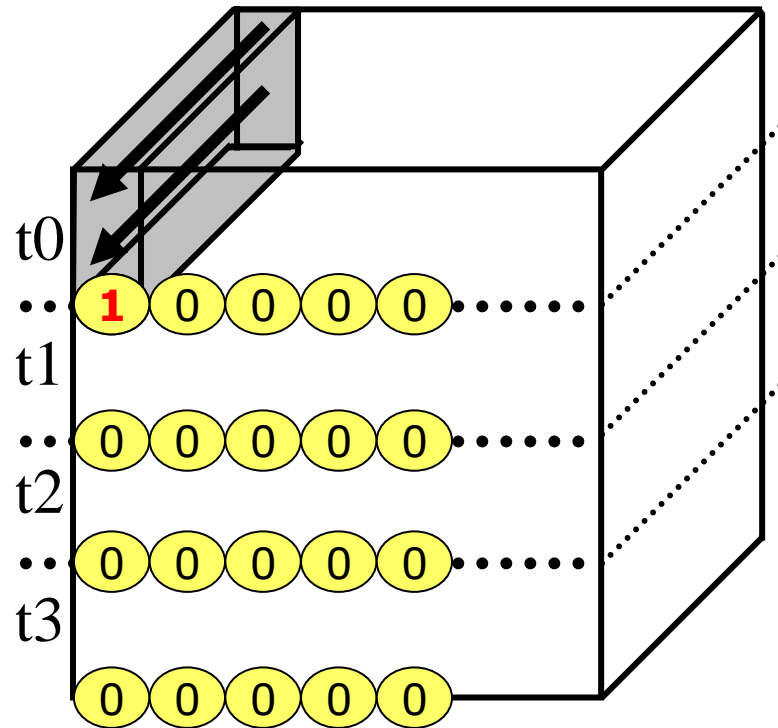
- Producer/Consumer flag
- Sharing of data values



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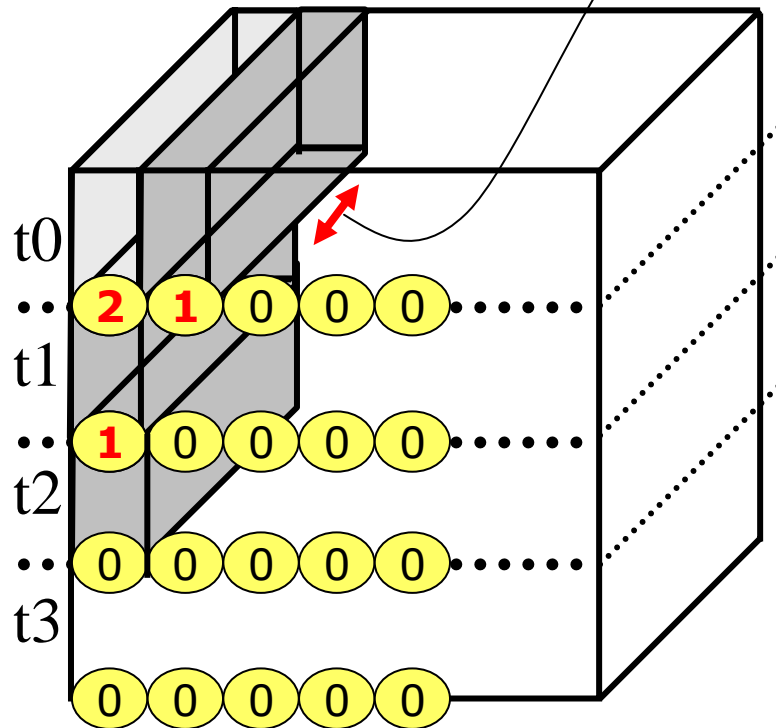
Parallel G-S 3D





Parallel G-S 3D

cacheline layout
(size B bytes)



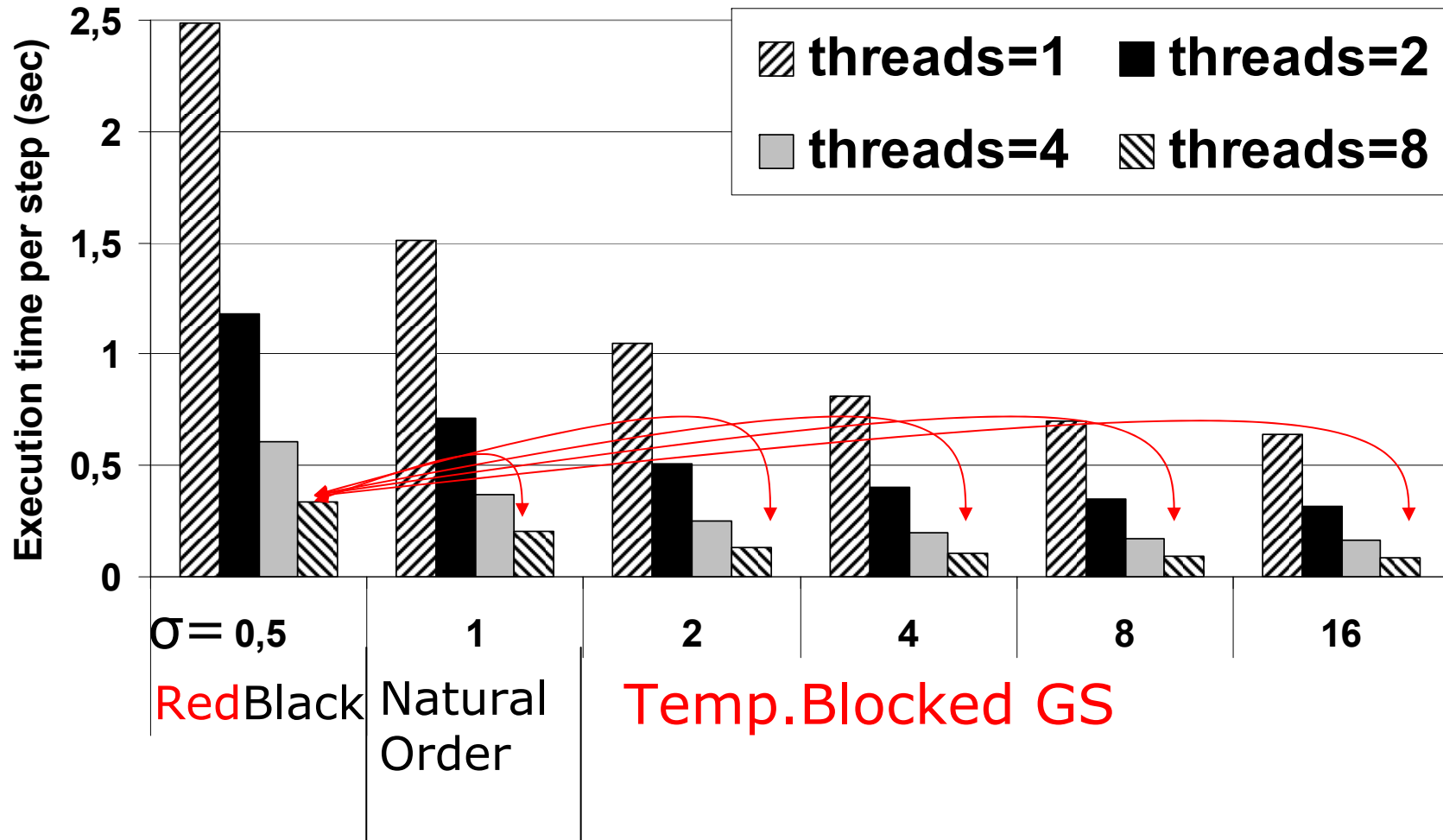
Stratup cost = $(\#threads-1)/(N\sigma)$

Communication:

- one flag synchronization per $N^2/\#threads$ ops
- one communication miss per $B*N/\#threads$ bytes



Parallel Executiontime

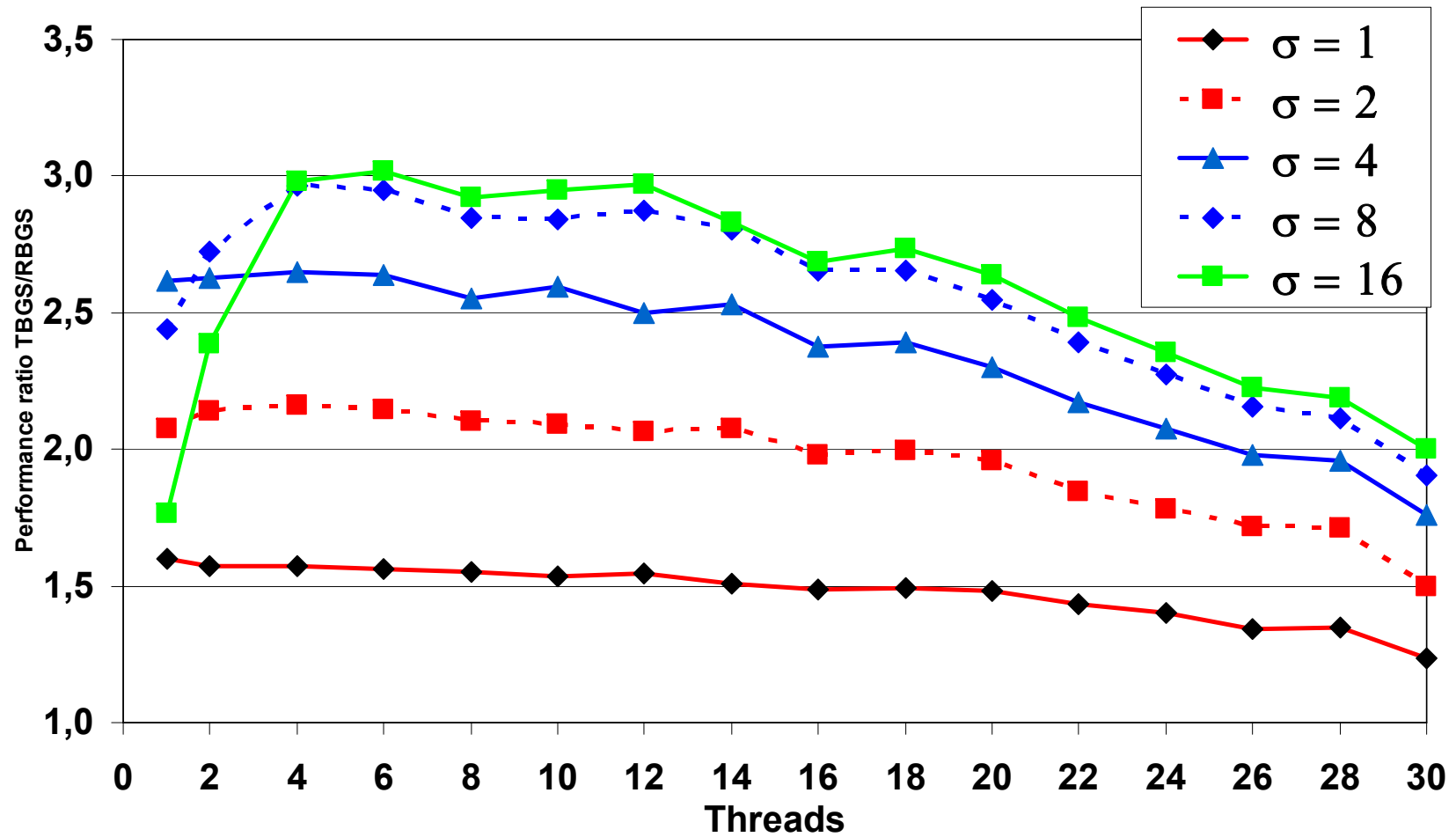




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Performance comparison with Red-Black $\sigma = 0,5$ $N = 257$, 32 threads (Sun E15 K, US IIIcu = SMP!!)



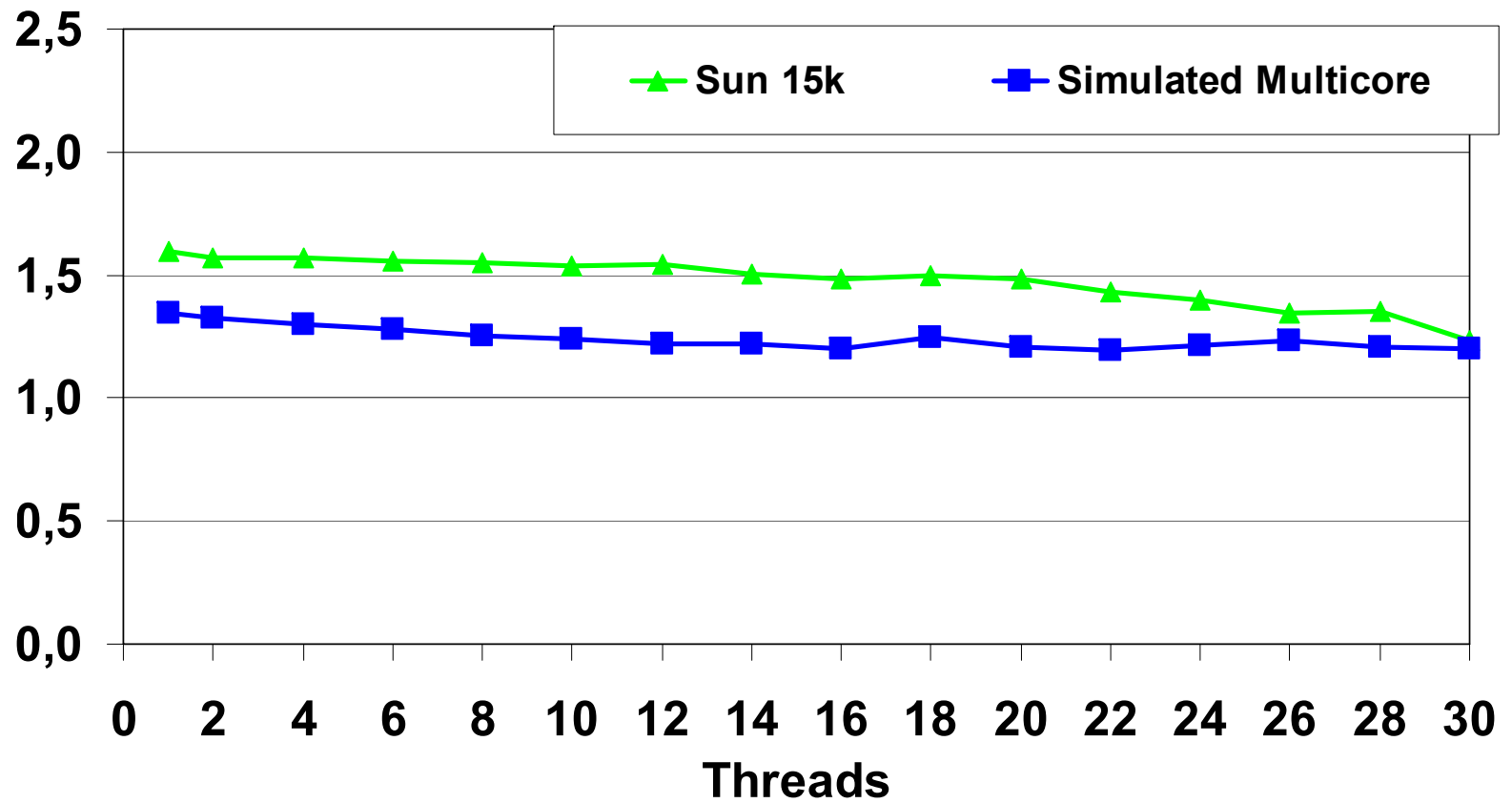


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Multicore Simulation

$\sigma = 1$





Using Gauss-Seidel Smoother in a Multigrid

- G-S Important part of many real apps!
- EX: G-S as a Smoother in “Multigrid”
 - ✱ Iterative algorithm
 - ✱ More efficient smoother cuts #iterations

threads	N=129	N=257	N=513
1	1.46	1.57	1.55
2	0.96	1.59	1.58
4	0.86	1.60	1.66
8	0.90	1.62	1.63

Table 4. Relative speedup of the multigrid solver with TBGS smoothing compared to the RBGS-multigrid solver.



One slide summary

- Today's algorithms assume expensive communication
- The communication cost of [some] multicores is close to zero
- Locality is becoming key to performance [again]
- ➔ Redesign HPC algorithms to face this fact!
(For both Capacity and Capability computing)

We show: * 3x performance gain

* ~30x less bandwidth

Is it time to revisit more algorithms?