# Full-System Timing-First Simulation
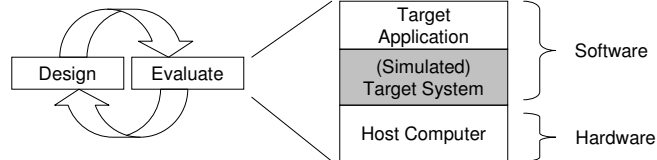
## Carl J. Mauer
## Mark D. Hill and David A. Wood

Computer Sciences Department
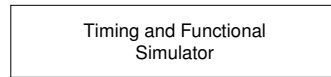University of Wisconsin—Madison

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## The Problem

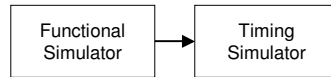- Design of future computer systems uses simulation



- Increasing functionality and timing demands from:
  - Micro-architecture complexity
  - Multiprocessing
  - Complex workloads

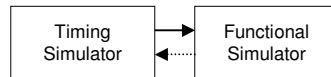- How can simulators be structured to manage complexity?

## Solutions

| Timing and Functional Simulator | Integrated (SimOS) |
| --- | --- |

**-** Complex

| Functional Simulator | → | Timing Simulator | Functional-First (Trace-driven) |
| --- | --- | --- | --- |

**-** Timing feedback

| Timing Simulator | → | Functional Simulator | Timing-First (This paper) |
| --- | --- | --- | --- |

- ▪Complete Timing   ▪No Timing
- ▪Partial Function   ▪Complete Function

**+** Models multiprocessor timing
**+** Decouples complexity
**+** Leverages existing simulators

- Separates the complexity of functional correctness from timing accuracy

**\*** Timing-directed discussed in paper

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## Outline

- Overview
- Introduction
- Timing-First Simulation
- Evaluation
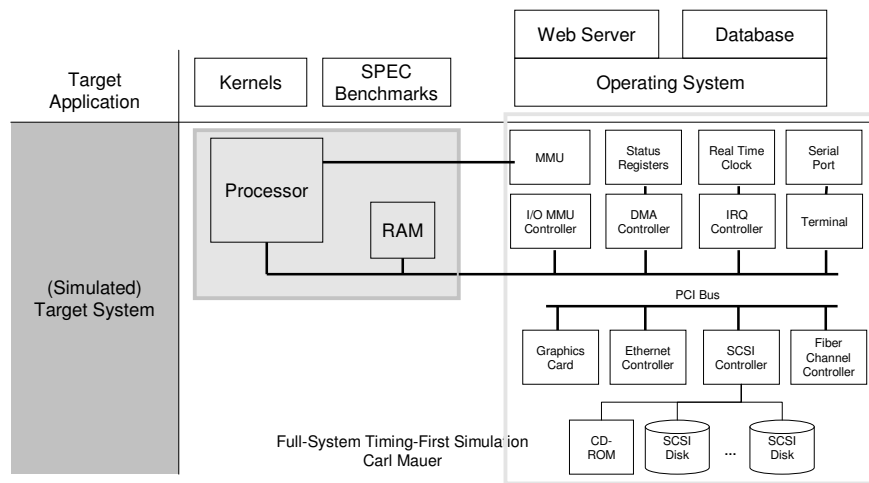- Conclusion

## Challenges to Timing Simulation

- Execution driven simulation is getting harder

- Increasing micro-architecture complexity
  - Multiple "in-flight" instructions
  - Speculative execution
  - Out-of-order execution

- Increasing use of multiprocessing
  - Chip multiprocessors
  - Hardware multi-threading

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## Challenges to Functional Simulation

- Commercial workloads have high functional fidelity demands

| | | | Web Server | Database |
|---|---|---|---|---|
| Target Application | Kernels | SPEC Benchmarks | Operating System | |

| | | | | |
|---|---|---|---|---|
| | Processor | MMU | Status Registers | Real Time Clock | Serial Port |
| (Simulated) Target System | RAM | I/O MMU Controller | DMA Controller | IRQ Controller | Terminal |

PCI Bus

| Graphics Card | Ethernet Controller | SCSI Controller | Fiber Channel Controller |
|---|---|---|---|

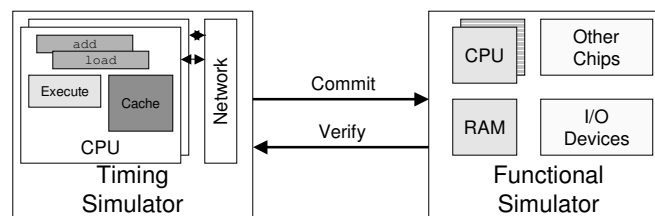CD-ROM    SCSI Disk    ...    SCSI Disk

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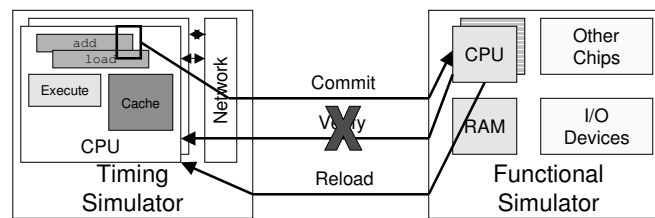- Conclusion

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# Timing-First Simulation

- Timing Simulator
  - does functional execution of user and privileged operations
  - does detailed multiprocessor timing simulation
  - does NOT implement full instruction set or any devices
- Functional Simulator
  - does full-system multiprocessor simulation
  - does NOT model detailed micro-architectural timing

# Timing-First Operation

- As instruction retires, step CPU in functional simulator
- Verify instruction's execution
- Reload state if timing simulator *deviates* from functional
  - Very uncommon case
  - Example: Instructions with unidentified side-effects



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# Benefits of Timing-First

- Support detailed multi-processor timing models
- Avoid re-implementing full-system simulator (hard!)
- Faster development, same performance
  - 99% correct is (much!) easier than 100%
  - Functional simulation is (much!) faster than timing simulation
  - Independent correctness checker helps development

- Questions:
  - How much error is introduced with this approach?
  - Are there simulation performance penalties?

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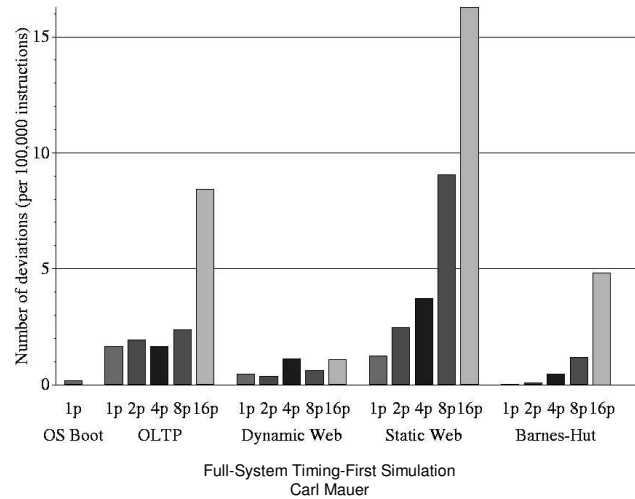- Evaluation
- Conclusion

## Evaluation

- Our implementation, TFsim uses:
  - Functional Simulator: Virtutech Simics
  - Timing simulator: Implemented in less than one-person year

- Evaluated using OS intensive commercial workloads
  - OS Boot: > 1 billion instructions of Solaris 8 startup
  - OLTP: Database workload with 1 GB of data
  - Dynamic Web: Apache serving message board, using code and data similar to `slashdot.org`
  - Static Web: Apache web server serving static web pages
  - Barnes-Hut: Scientific SPLASH-2 benchmark

## Measured Deviations

- Less than 2 deviations per 10,000 instructions     (0.02%)



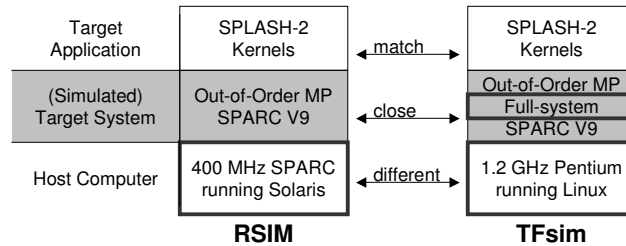Full-System Timing-First Simulation
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## Analysis of Results

- Runs full-system workloads!

- Timing performance impact of deviations
  – Worst case: less than 3% performance error
  – Average case: less than 0.3% performance error

- 'Overhead' of redundant execution
  – 18% on average for uniprocessors
  – 18% (2 processors) up to 36% (16 processors)

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## Performance Comparison

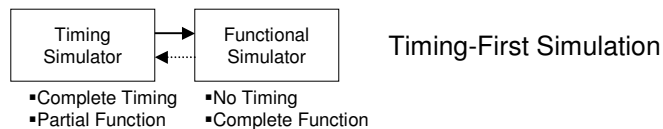| Target Application | SPLASH-2 Kernels | ←match→ | SPLASH-2 Kernels |
|---|---|---|---|
| (Simulated) Target System | Out-of-Order MP SPARC V9 | ←close→ | Out-of-Order MP / Full-system / SPARC V9 |
| Host Computer | 400 MHz SPARC running Solaris | ←different→ | 1.2 GHz Pentium running Linux |
| | **RSIM** | | **TFsim** |

- Absolute simulation performance comparison
  - In kilo-instructions committed per second (KIPS)
  - RSIM Scaled: 107 KIPS
  - Uniprocessor TFsim: 119 KIPS

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## Conclusions

- Execution-driven simulators are increasingly complex
- How to manage complexity?
- Our answer:

| Timing Simulator | → ⋯→ | Functional Simulator |
|---|---|---|
| ▪Complete Timing | | ▪No Timing |
| ▪Partial Function | | ▪Complete Function |

Timing-First Simulation

  - Introduces relatively little performance error (worst case: 3%)
  - Has low-overhead (18% uniprocessor average)
  - Rapid development time

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# Questions?

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# Related Work

| Name | Dynamic Full System | Out-of-Order | Multi-processor | Decoupled |
|---|---|---|---|---|
| Multiscalar Simulator [6] | | Yes | | Yes |
| FastSim [24] | | Yes | | Yes |
| SimpleScalar 3.0 [2] | | Yes | | Yes |
| MASE [18] | | Yes | | Yes |
| RSIM [15] | | Yes | Yes | |
| SimpleMP [22] | | Yes | Yes | Yes |
| ASIM [14] | | Yes | Yes | Yes |
| g88 [4] | Yes | | | |
| gsim [19] | Yes | | Yes | |
| Talisman [5] | Yes | | Yes | |
| Simics [20] | Yes | | Yes | |
| PharmSim [7] | Yes | Yes | Yes | |
| SimOS [23] | Yes | Yes | Yes | |
| TFsim [This paper] | Yes | Yes | Yes | Yes |

# Bundled Retires



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