

# Cache Aware Optimization of Stream Programs

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## Abstract

Effective use of the memory hierarchy is critical for achieving high performance on embedded systems. We focus on the class of streaming applications, which is increasingly prevalent in the embedded domain. We exploit the widespread parallelism and regular communication patterns in stream programs to formulate a set of cache aware optimizations that automatically improve instruction and data locality. Our work is in the context of the Synchronous Dataflow model, in which a program is described as a graph of independent actors that communicate over channels. The communication rates between actors are known at compile time, allowing the compiler to statically model the caching behavior.

We present three cache aware optimizations: 1) execution scaling, which judiciously repeats actor executions to improve instruction locality, 2) cache aware fusion, which combines adjacent actors while respecting instruction cache constraints, and 3) scalar replacement, which converts certain data buffers into a sequence of scalar variables that can be register allocated. The optimizations are founded upon a simple and intuitive model that quantifies the temporal locality for a sequence of actor executions. Our implementation of cache aware optimizations in the StreamIt compiler yields a 249% average speedup (over unoptimized code) for our streaming benchmark suite on a StrongARM 1110 processor. The optimizations also yield a 154% speedup on a Pentium 3 and a 152% speedup on an Itanium 2.

**Categories and Subject Descriptors** D.3.4 [Programming Languages]: Processors—Optimization; code generation; compilers; D.3.2 [Programming Languages]: Language Classifications—Concurrent, distributed, and parallel languages; Data-flow languages

**General Terms** Languages, Design, Performance

**Keywords** Stream Programming, StreamIt, Synchronous Dataflow, Cache, Cache Optimizations, Fusion, Embedded

## 1. Introduction

Efficiency and high performance are of central importance within the embedded domain. As processor speeds continue to increase, the memory bottleneck remains a primary impediment to attaining performance. Current practices for hiding memory latency are

invariably expensive and complex. For example, superscalar processors resort to out-of-order execution to hide the latency of cache misses. This results in large power expenditures (unfit for embedded systems) and also increases the cost of the system. Compilers have also employed computation and data reordering to improve locality, but this requires a heroic analysis due to the obscured parallelism and communication patterns in traditional languages such as C.

For performance-critical programs, the complexity inevitably propagates all the way to the application developer. Programs are written to explicitly manage parallelism and to reorder the computation so that the instruction and data working sets fit within the cache. For example, the inputs and outputs of a procedure might be arrays that are specifically designed to fit within the data cache on a given architecture; loop bodies are written at a level of granularity that matches the instruction cache. While manual tuning can be effective, the end solutions are not portable. They are also exceedingly difficult to understand, modify, and debug.

The recent emergence of streaming applications represents an opportunity to mitigate these problems using simple transformations in the compiler. Stream programs are rich with parallelism and regular communication patterns that can be exploited by the compiler to automatically tune memory performance. Streaming codes encompass a broad spectrum of applications, including embedded communications processing, multimedia encoding and playback, compression, and encryption. They also range to server applications, such as HDTV editing and hyper-spectral imaging. It is natural to express a stream program as a high-level graph of independent components, or *actors*. Actors communicate using explicit FIFO channels and can execute whenever a sufficient number of items are available on their input channels. In a stream graph, actors can be freely combined and reordered to improve caching behavior as long as there are sufficient inputs to complete each execution. Such transformations can serve to automate tedious approaches that are performed manually using today's languages; they are too complex to perform automatically in hardware or in the most aggressive of C compilers.

This paper presents three simple cache aware optimizations for stream programs: (i) execution scaling, (ii) cache aware fusion, and (iii) scalar replacement. These optimizations represent a *unified approach* that simultaneously considers the instruction and data working sets. We also develop a simple quantitative model of caching behavior for streaming workloads, providing a foundation to reason about the transformations. Our work is done in the context of the Synchronous Dataflow [13] model of computation, in which each actor in the stream graph has a known input and output rate. This is a popular model for a broad range of signal processing and embedded applications.

Execution scaling is a transformation that improves instruction locality by executing each actor in the stream graph multiple times before moving on to the next actor. As a given actor usually fits within the cache, the repeated executions serve to amortize the

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cost of loading the actor from off-chip memory. However, as our cache model will show, actors should not be scaled excessively, as their outputs will eventually overflow the data cache. We present a simple and effective algorithm for calculating a scaling factor that respects both instruction and data constraints.

Prior to execution scaling, cache aware fusion combines adjacent actors into a single function. This allows the compiler to optimize across actor boundaries. Our algorithm is cache aware in that it never fuses a pair of actors that will result in an overflow of the instruction cache.

As actors are fused together, new buffer management strategies become possible. The most aggressive of these, termed scalar replacement, serves to replace an array with a series of local scalar variables. Unlike array references, scalar variables can be register allocated, leading to large performance gains. We also develop a new buffer management strategy (called “copy-shift”) that extends scalar replacement to sliding-window computations, a domain where complex indexing expressions typically hinder compiler analysis.

Our cache aware optimizations are implemented as part of StreamIt, a language and compiler infrastructure for stream programming [21]. We evaluate the optimizations on three architectures. The StrongARM 1110 represents our primary target; it is an embedded processor without a secondary cache. Our other targets are the Pentium 3 (a superscalar) and the Itanium 2 (a VLIW processor). We find that execution scaling, cache aware fusion, and scalar replacement each offer significant performance gains, and the most consistent speedups result when all are applied together. Compared to unoptimized StreamIt code, our cache optimizations yield a 249% speedup on the StrongARM, a 154% speedup on the Pentium 3, and a 152% speedup on Itanium 2. These numbers represent averages over our streaming benchmark suite.

This paper is organized as follows. Section 2 gives background information on the StreamIt language. Section 3 lays the foundation for our approach by developing a quantitative model of caching behavior for any sequence of actor executions. Section 4 describes execution scaling and cache aware scheduling. Section 5 evaluates buffer management strategies, including scalar replacement. Section 6 contains our experimental evaluation of these techniques in the StreamIt compiler. Finally, Section 7 describes related work and Section 8 concludes the paper.

## 2. StreamIt

StreamIt is an architecture independent language that is designed for stream programming. In StreamIt, programs are represented as graphs where nodes represent computation and edges represent FIFO-ordered communication of data over tapes.

**Hierarchical Streams** In StreamIt, the basic programmable unit (i.e., an actor) is a *filter*. Each filter contains a work function that executes atomically, popping (i.e., reading) a fixed number of items from the filter’s input tape and pushing (i.e., writing) a fixed number of items to the filter’s output tape. A filter may also *peek* at a given index on its input tape without consuming the item; this makes it simple to represent computation over a sliding window. The *push*, *pop*, and *peek* rates are declared as part of the work function, thereby enabling the compiler to construct a static schedule of filter executions. An example implementation of a Finite Impulse Response (FIR) filter appears in Figure 1.

The work function is invoked (fired) whenever there is sufficient data on the input tape. For the FIR example in Figure 1, the filter requires at least  $N$  elements before it can execute. The value of  $N$  is known at compile time when the filter is constructed. A filter is akin to a class in object oriented programming with the work function serving as the main method. The parameters to a filter

```
float->float filter FIR_Filter (int N, float[] weights) {
  work push 1 pop 1 peek N {
    float sum = 0;
    for (int i = 0; i < N; i++) {
      sum += peek(i) * weights[i];
    }
    pop();
    push(sum);
  }
}
```

Figure 1. StreamIt code for an FIR filter

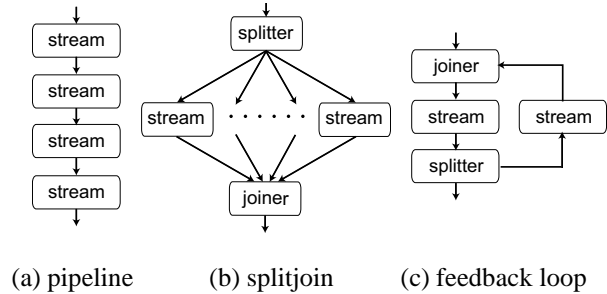


Figure 2. Hierarchical streams in StreamIt.

```
float -> float pipeline Main() {
  add Source(); // code for Source not shown
  add FIR();
  add Output(); // code for Output not shown
}
```

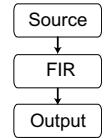


Figure 3. Example pipeline with FIR filter.

(e.g.,  $N$  and *weights*) are equivalent to parameters passed to a class constructor.

In StreamIt, the application developer focuses on the hierarchical assembly of the stream graph and its communication topology, rather than on the explicit management of the data buffers between filters. StreamIt provides three hierarchical structures for composing filters into larger stream graphs (see Figure 2). The *pipeline* construct composes streams in sequence, with the output of one connected to the input of the next. An example of a pipeline appears in Figure 3.

The *splitjoin* construct distributes data to a set of parallel streams, which are then joined together in a roundrobin fashion. In a splitjoin, the *splitter* performs the data scattering, and the *joiner* performs the gathering. A splitter is a specialized filter with a single input and multiple output channels. On every execution step, it can distribute its output to any one of its children in either a *duplicate* or a *roundrobin* manner. For the former, incoming data are replicated to every sibling connected to the splitter. For the latter, data are scattered in a roundrobin manner, with each item sent to exactly one child stream, in order. The splitter type and the weights for distributing data to child streams are declared as part of the syntax (e.g., `split duplicate` or `split roundrobin( $w_1, \dots, w_n$ )`). The splitter counterpart is the joiner. It is a specialized filter with multiple input channels but only one output channel. The joiner gathers data from its predecessors in a roundrobin manner (declared as part of the syntax) to produce a single output stream.

StreamIt also provides a *feedback loop* construct for introducing cycles in the graph.

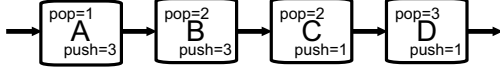


Figure 4. Example pipeline.

**Execution Model** As noted earlier, an actor (i.e., a filter, splitter, or joiner) executes whenever there are enough data items on its input tape. In StreamIt, actors have two epochs of execution: one for initialization, and one for the *steady state*. The initialization primes the input tapes to allow filters with peeking to execute the very first instance of their work functions. A steady state is an execution that does not change the buffering in the channels: the number of items on each channel after the execution is the same as it was before the execution. Every valid stream graph has a steady state [13], and within a steady state, there are often many possibilities for interleaving actor executions. An example of a steady state for the pipeline in Figure 4 requires filter A to fire 4 times, B 6 times, C 9 times, and D 3 times.

**Compilation Process** The StreamIt compiler derives the initialization and steady state schedules [10] and outputs a C program that includes the initialization and work functions, as well as a driver to execute each of the two schedules. Our compilation process allows the StreamIt compiler to focus on high level optimizations, and relies on existing compilers to perform machine-specific optimizations such as register allocation, instruction scheduling, and code generation—this two-step approach affords us a great deal of portability (e.g., code generated from the StreamIt compiler is compiled and run on three different machines as reported in Section 6).

### 3. Cache Model for Streaming

From a caching point of view, it is intuitively clear that once a actor’s instruction working set is fetched into the cache, we can maximize instruction locality by running the actor as many times as possible. This of course assumes that the total code size for all actors in the steady state exceeds the capacity of the instruction cache. For our benchmarks, the total code size for a steady state ranges from 2 Kb to over 135 Kb (and commonly exceeds 16 Kb). Thus, while individual actors may have a small instruction footprint, the total footprint of the actors in a steady state exceeds a typical instruction cache size. From these observations, it is evident that we must *scale* the execution of actors in the steady state in order to improve temporal locality. In other words, rather than running a actor  $n$  times per steady state, we scale it to run  $m \times n$  times. We term  $m$  the *scaling factor*.

The obvious question is: to what extent can we scale the execution of actors in the steady state? The answer is non-trivial because scaling, while beneficial to the instruction cache behavior, may overburden the data cache as the buffers between actors may grow to prohibitively large sizes that degrade the data cache behavior. Specifically, if a buffer overflows the cache, then producer-consumer locality is lost.

In this section we describe a simple and intuitive cache model to estimate the instruction and data cache miss rates for a steady state sequence of actor firings. The model serves as a foundation for reasoning about the cache aware optimizations introduced in this paper. We develop the model first for the instruction cache, and then generalize it to account for the data cache.

#### 3.1 Instruction Cache

A steady state execution is a sequence of actor firings  $S = (a_1, \dots, a_n)$ , and a *program execution* corresponds to one or more repetitions of the steady state. We use the notation  $S[i]$  to refer to

the actor  $a$  that is fired at logical time  $i$ , and  $|S|$  to denote the length of the sequence.

Our cache model is simple in that it considers each actor in the steady state sequence, and determines whether one or more misses are bound to occur. The miss determination is based on the *instruction reuse distance (IRD)*, which is equal to the number of unique instructions that are referenced between two executions of the actor under consideration (as they appear in the schedule). The steady state is a compact representation of the whole program execution, and thus, we simply account for the misses within a steady state, and generalize the result to the whole program. Within a steady state, an actor is charged a miss penalty if and only if the number of referenced instructions since the last execution (of the same actor) is greater than the instruction cache capacity.

Formally, let  $phase(S, i)$  for  $1 \leq i \leq |S|$  represent a subsequence of  $k$  elements of  $S$ :

$$phase(S, i) = (S[i], S[i+1], \dots, S[i+k-1])$$

where  $k \in [1, |S|]$  is the smallest integer such that  $S[i+k] = S[i]$ . In other words, a phase is a subsequence of  $S$  that starts with the specified actor ( $S[i]$ ) and ends before the next occurrence of the same actor (i.e., there are no intervening occurrences of  $S[i]$  in the phase). Note that because the steady state execution is cyclic, the construction of the subsequence is allowed to wrap around the steady state<sup>1</sup>. For example, the steady state  $S_1 = (AABB)$  has  $phase(S_1, 1) = (A)$ ,  $phase(S_1, 2) = (ABB)$ ,  $phase(S_1, 3) = (B)$ , and  $phase(S_1, 4) = (BAA)$ .

Let  $I(a)$  denote the code size of the work function for actor  $a$ . Then the instruction reuse distance is

$$IRD(S, i) = \sum_a I(a)$$

where the sum is over all distinct actors  $a$  occurring in  $phase(S, i)$ . We can then determine if a specific actor will result in an instruction cache miss (on its next firing) by evaluating the following step function:

$$IMISS(S, i) = \begin{cases} 0 & \text{if } IRD(S, i) \leq C_I; \text{ hit: no cache refill,} \\ 1 & \text{otherwise; miss: (some) cache refill.} \end{cases} \quad (1)$$

In the equation,  $C_I$  represents the instruction cache size.

Using Equation 1, we can estimate the instruction miss rate (*IMR*) of a steady state as:

$$IMR(S) = \frac{1}{|S|} \sum_{i=1}^{|S|} IMISS(S, i). \quad (2)$$

The cache model allows us to rank the quality of an execution ordering: schedules that boost temporal locality result in miss rates closer to zero, and schedules that do not exploit temporal locality result in miss rates closer to one.

For example, in the steady state  $S_1 = (AABB)$ , assume that the combined instruction working sets exceed the instruction cache, i.e.,  $I(A) + I(B) > C_I$ . Then, we expect to suffer a miss at the start of every steady state because the phase that precedes the execution of A (at  $S_1[1]$ ) is  $phase(S_1, 2) = (ABB)$  with an instruction reuse distance greater than the cache size ( $IRD(S_1, 2) > C_I$ ). Similarly, there is a miss predicted for the first occurrence of actor B since  $phase(S_1, 4) = (BAA)$  and  $IRD(S_1, 4) > C_I$ . Thus,  $IMR(S_1) = 2/4$  whereas for the following variant  $S_2 = (ABAB)$ ,  $IMR(S_2) = 1$ . In the case of  $S_2$ , we know that since the combined instruction working sets of the actors exceed the cache size, when actor B is fired following A, it evicts part of actor A’s instruction

<sup>1</sup> In other words, the subsequence is formed from a new sequence  $S' = S|S$  where  $|$  represents concatenation.

working set. Hence when we transition back to fire actor A, we have to refetch certain instructions, but in the process, we replace parts of actor B's working set. In terms of our model,  $IRD(S_2, i) > C_I$  for every actor in the sequence, i.e.,  $1 \leq i \leq |S_2|$ .

Note that the amount of refill is proportional to the number of cache lines that are replaced when swapping actors, and as such, we may wish to adjust our cache miss step function (*IMISS*). One simple variation is to allow for some partial replacement without unduly penalizing the overall value of the metric. Namely, we can allow the constant  $C_I$  to be some fraction greater than the actual cache size. Alternatively, we can use a more complicated miss function with a more uniform probability distribution.

**Temporal Locality** In our model, the concept of improving temporal instruction locality translates to deriving a steady state where, in the best case, every actor has only one phase that is longer than unit-length. For example, a permutation of the actors in  $S_2$  (where all phases are of length two) that improves temporal locality will result in  $S_1$ , which we have shown has a relatively lower miss rate.

**Execution Scaling** Another approach to improving temporal locality is to scale the execution of the actors in the steady state. Scaling increases the number of consecutive firings of the same actor. In our model, a scaled steady state has a greater number of unit-length phases (i.e., a phase of length one and the shortest possible reuse distance).

We represent a scaled execution of the steady state as  $S^m = (a_1^m, \dots, a_n^m)$ : the steady state  $S$  is scaled by  $m$ , which translates to  $m - 1$  additional firings of every actor. For example, scaling  $S_1 = (\text{AABB})$  by a factor of two results in  $S_1^2 = (\text{AAAABBBB})$  and scaling  $S_2 = (\text{ABAB})$  by the same amount results in  $S_2^2 = (\text{AABBAABB})$ ;

From Equation 1, we observe that unit-length phases do not increase the instruction miss rate as long as the size of the actor's instruction working set is smaller than the cache size; we assume this is always the case. Therefore, scaling has the effect of preserving the pattern of miss occurrences while also lengthening the steady state. Mathematically, we can substitute into Equation 2:

$$\begin{aligned} IMR(S^m) &= \frac{1}{|S^m|} \sum_{i=1}^{|S^m|} IMISS(S^m, i) \\ &= \frac{1}{m \times |S|} \sum_{i=1}^{|S^m|} IMISS(S^m, i) \\ &= \frac{1}{m \times |S|} \sum_{i=1}^{|S|} IMISS(S, i). \end{aligned} \quad (3)$$

The last step is possible because *IMISS* is zero for  $m - 1$  out of  $m$  executions of every scaled actor. The result is that the miss rate is inversely proportional to the scaling factor.

In Figure 5 we show a representative curve relating the scaling factor to overall performance. The data corresponds to a coarse-grained implementation of a Fast Fourier Transform (FFT) running on a Pentium 3 architecture. The x-axis represents the scaling factors (with increasing values from left to right). The y-axis represents the execution time and is an indirect indicator of the miss rate (the two measures are positively correlated). The execution time improves in accord with our model: the running time is shortened as the scaling factor grows larger. There is however an eventual degradation, and as the sequel will show, it is attributed to the data cache performance.

### 3.2 Data Cache

The results in Figure 5 show that scaling can reduce the running time of a program, but ultimately, it degrades performance. In this

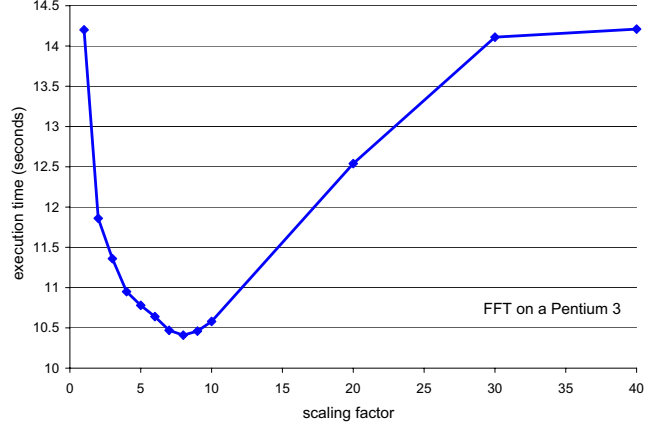


Figure 5. Impact of execution scaling on performance.

section, we provide a basic analytical model that helps in reasoning about the relationship between scaling and the data cache miss rate.

We distinguish between two types of data working sets. The static data working set of an actor represents state, e.g., weights in the FIR example (Figure 1). The dynamic data working set is the data generated by the work function and pushed onto the output channel. Both of these working sets impact the data cache behavior of an actor.

Intuitively, the presence of state suggests that it is prudent to maximize that working set's temporal locality. In this case, scaling positively improves the data cache performance. To see that this is true, we can define a data miss rate (*DMR*) based on a derivation similar to that for the instruction miss rate, replacing  $C_I$  with  $C_D$  in Equation 1, and  $I(a)$  with  $State(a)$  when calculating the reuse distance. Here,  $C_D$  represents the data cache size, and  $State(a)$  represents the total size of the static data in the specified actor.

Execution scaling however also increases the I/O requirements of a scaled actor. Let *pop* and *push* denote the declared pop and push rates of an actor, respectively. The scaling of an actor by a factor  $m$  therefore increases the pop rate to  $m \times pop$  and the push rate to  $m \times push$ . Combined, we represent the dynamic data working set of an actor  $a$  as  $IO(a, m) = m \times (pop + push)$ . Therefore, we measure the data reuse distance (*DRD*) of an execution  $S$  with scaling factor  $m$  as follows:

$$DRD(S^m, i) = \sum_a State(a) + IO(a, m)$$

where the sum is over all distinct actors  $a$  occurring in  $phase(S^m, i)$ . While this simple measure double-counts data that are both produced and consumed within a phase, such duplication could be roughly accounted for by setting  $IO'(a, m) = IO(a, m)/2$ .

We can determine if a specific work function will result in a data cache miss (on its next firing) by evaluating the following step function:

$$DMISS(S^m, i) = \begin{cases} 0 & \text{if } DRD(S^m, i) \leq C_D; \text{ hit: no cache refill,} \\ 1 & \text{otherwise; miss: (some) cache refill.} \end{cases} \quad (4)$$

Finally, to model the data miss rate (*DMR*):

$$DMR(S^m) = \frac{1}{|S^m|} \sum_{i=1}^{|S^m|} DMISS(S^m, i). \quad (5)$$

It is evident from Equation 5 that scaling can lead to lower data miss rates, as the coefficient  $1/|S^m| = 1/(m \times |S|)$  is

inversely proportional to  $m$ . However, as the scaling factor  $m$  grows larger, more of the *DMISS* values transition from 0 to 1 (they increase monotonically with the I/O rate, which is proportional to  $m$ ). For sufficiently large  $m$ ,  $DMR(S^m) = 1$ . Thus, scaling must be performed in moderation to avoid negatively impacting the data locality.

Note that in order to generalize the data miss rate equation so that it properly accounts for the dynamic working set, we must consider the amount of data reuse within a phase. This is because any actor that fires within  $phase(S, i)$  might consume some or all of the data generated by  $S[i]$ . The current model is simplistic, and leads to exaggerated I/O requirements for a phase. We also do not model the effects of cache conflicts, and take an “atomic” view of cache misses (i.e., either the entire working set hits or misses).

## 4. Cache Optimizations

In this section we describe two cache aware optimizations that are geared toward improving the cache behavior of streaming programs. First, we describe *execution scaling* which scales a steady state to improve instruction locality, subject to the data working set constraints of the actors in the stream graph. Second, we describe *cache aware fusion* which performs a series of granularity adjustments to the actors in the steady state. The fusion serves to (i) reduce the overhead of switching between actors, (ii) create coarser grained actors for execution scaling, and (iii) enable novel buffer management techniques between fused actors (see Section 5).

### 4.1 Execution Scaling

We have already alluded to execution scaling in previous sections. As the instruction cache model shows, increasing the number of consecutive firings of the same actor leads to lower instruction cache miss rates. However, scaling increases the data buffers that are maintained between actors. Thus it is prudent that we account for the data working set requirements as we scale a steady state.

Our approach is to scale the entire steady state by a single scaling factor, with the constraint that only a small percentage of the actors overflow the data cache. Our two-staged algorithm is outlined in Figure 6.

First, the algorithm calculates the largest possible scaling factor for every actor that appears in the steady state. To do this, it calculates the amount of data produced by each actor firing and divides the available data cache size by this data production rate. In addition, the algorithm can toggle the effective cache size to account for various eviction policies.

Second, it chooses the largest factor that allows a fraction  $p$  of the steady state actors to be scaled safely (i.e., the cache is adequate for their I/O requirements). For example, the algorithm might calculate  $m_A = 10$ ,  $m_B = 20$ ,  $m_C = 30$ , and  $m_D = 40$ , for four actors in some steady state. That is, scaling actor A beyond 10 consecutive iterations will cause its dynamic I/O requirements to exceed the data cache. Therefore, the largest  $m$  that allows  $p = 90\%$  of the actors to be scaled without violating the cache constraints is 10. Similarly, to allow for the safe scaling of  $p = 75\%$  of the actors, the largest factor we can choose is 20.

In our implementation, we use a 90-10 heuristic. In other words, we set  $p = 90\%$ . We empirically determined this value via a series of experiments using our benchmark suite; see [18] for detailed results.

Note that our algorithm adjusts the effective cache size that is reserved for an actor’s dynamic working set (i.e., data accessed via `pop` and `push`). This adjustment allows us to control the fraction of the cache that is used for reading and writing data—and affords some flexibility in targeting various cache organizations. For example, architectures with highly associative and multilevel caches may benefit from scaling up the effective cache size (i.e.,

```

// Returns a scaling factor for steady state S
// - c is the data cache size
// - alpha is the fraction of c dedicated for I/O
// - p is the desired percentile of all actors to be
//   satisfied by the chosen scaling factor (0 < p <= 1)
calculateScalingFactor(S, c, alpha, p) {
  create array M of size |S|
  for i = 1 to |S| {
    a = S[i]
    // calculate effective cache size
    c' = alpha * (c - State(a))
    // calculate scaling factor for a such
    // that I/O requirements are close to c'
    M[i] = round(c' / IO(a, 1))
  }
  sort M into ascending numerical order
  i = floor((1 - p) * |S|)
  return M[i]
}

```

Figure 6. Our heuristic for calculating the scaling factor.

$\alpha > 1$ ), whereas a direct mapped cache that is more prone to conflicts may benefit from scaling down the cache (i.e.,  $\alpha < 1$ ). In our implementation, we found  $\alpha = 2/3$  to work well. However, we note that the optimal choice for the effective cache size is a complex function of the underlying cache organization and possibly the application as well; this is an interesting issue that warrants further investigation.

### 4.2 Cache Aware Fusion

In StreamIt, the granularity of actors is determined by the application developer, according to the most natural representation of an algorithm. When compiling to a cache-based architecture, the presence of a large number of actors exacerbates the transition overhead between work functions. It is the role of the compiler to adjust the granularity of the stream graph to mitigate the execution overhead.

In this section we describe an actor coarsening technique we refer to as *cache aware fusion* (CAF). When two actors are fused, they form a new actor whose work function is equivalent to its constituents. For example, let an actor A fire  $n$  times, and an actor B fire  $2n$  times per steady state:  $S^n = (A^n B^n B^n)$ . Fusing A and B results in an actor F that is equivalent to one firing of A and two firings of B; F fires  $n$  times per steady state ( $S^n = (F^n)$ ). In other terms, the work function for actor F inlines the work functions of A and B.

When two actors are fused, their executions are scaled such that the output rate of one actor matches the input rate of the next. In the example, A and B represent a producer-consumer pair of filters within a pipeline, with filter A pushing two items per firing, and B popping one item per firing. The fusion implicitly scales the execution of B so that it runs twice for every firing of A.

Fusion also reduces the overhead of switching between work functions. In our infrastructure, the steady state is a loop that invokes the work functions via method calls. Thus, every pair of fused actors eliminates a method call (per invocation of the actors). The impact on performance can be significant, but not only because method calls are removed: the fusion of two actors also enables the compiler to optimize across function boundaries. In particular, for actors that exchange only a few data items, the compiler can allocate the data streams to registers. The data channel between fused actors is subject to special buffer management techniques as described in the next section.

```

void->void pipeline BufferTest {
    add Source();
    add FIR();
}

void->float filter Source {
    work push 1 {
        push( ... );
    }
}

float->void filter FIR {
    int PEEK = 4;
    work pop 1 peek PEEK {
        float result = 0;
        for (int i=1; i<PEEK; i++) {
            result += i*peek(i);
        }
        pop();
        print(result);
    }
}

```

**Figure 7.** Original StreamIt code for the buffer test.

There are, however, downsides to fusion. First, as more and more actors are fused, the instruction footprint can dramatically increase, possibly leading to poor use of the instruction cache. Second, fusion increases the data footprint when the fused actors maintain state (e.g., coefficient arrays and lookup tables). Our fusion algorithm is cache aware in that it is cognizant of the instruction and data sizes.

The CAF algorithm uses a greedy fusion heuristic to determine which filters should be fused. It continuously fuses actors until the addition of a new actor causes the fused actor to exceed *either* the instruction cache capacity, or a fraction of the data cache capacity. For the former, we estimate the instruction code size using a simple count of the number of operations in the intermediate representation of the work function. For the latter, we allow the state of the new fused actor to occupy up to 50% of the data cache capacity.

The algorithm leverages the hierarchical nature of the stream graph, starting at the leaf nodes and working upward. For pipeline streams, the algorithm identifies the connection in the pipeline with the highest steady-state I/O rate, i.e., the pair of filters that communicate the largest number of items per steady state. These two filters are fused, if doing so respects the instruction and data cache constraints. To prevent fragmentation of the pipeline, each fused filter is further fused with its upstream and downstream neighbors so long as the constraints are met. The algorithm then repeats this process with the next highest-bandwidth connection in the pipeline, continuing until no more filters can be fused. For splitjoin streams, the CAF algorithm fuses all parallel branches together if the combination satisfies the instruction and data constraints. Partial fusion of a splitjoin is not helpful, as the child streams do not communicate directly with each other; however, complete fusion can enable further fusion in parent pipelines.

## 5. Buffer Management

A salient characteristic of stream programs is the use of FIFO channels to communicate between parallel components. Such channels make explicit the communication between actors, allowing execution to proceed in parallel or out-of-order so long as items are produced before they are consumed. FIFO channels also provide a natural abstraction for the programmer, as complex modules can be assembled from a set of small, reusable components. For these reasons, it is important to optimize the performance of communi-

```

void->void filter BufferTest {
    int PEEK = 4;
    float[4] BUFFER;
    int push_index = 0;
    int pop_index = 0;

    prework {
        for (int i=0; i<PEEK-1; i++) {
            BUFFER[push_index++] = ... ;
        }
    }

    work {
        // run Source
        BUFFER[push_index] = ... ;
        push_index = (push_index+1) & 3;

        // run FIR
        float result = 0;
        for (int i=1; i<PEEK; i++) {
            result += i*BUFFER[(pop_index+i) & 3];
        }
        pop_index = (pop_index+1) & 3;
        print(result);
    }
}

```

**Figure 8.** Fused buffer test using modulation buffer management.

cation channels. An efficient implementation enables a high-level abstraction for composing actors without sacrificing performance.

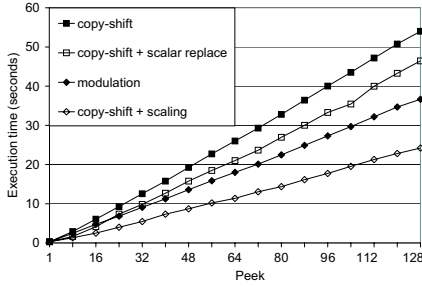
Buffer management in StreamIt is more involved than some other stream languages, due to the `peek` operation. The `peek` operation allows an actor to access an item on its input channel without removing the item from the channel (removal is done via the `pop` operation). The `peek` functionality is very important for components such as FIR (Finite Impulse Response) actors that access data over a sliding window. Because a given data item is accessed by multiple iterations of the actor, there must be a persistent buffer that stores items across executions. In the context of a uniprocessor, efficient buffer management translates to efficient maintenance and addressing of this buffer in memory. On a parallel system, buffers can also be implemented using network links.

In this section, we explore two basic strategies for buffer management in stream programs. The first strategy, termed *modulation*, implements a traditional circular buffer that is indexed by wraparound head and tail pointers. The second strategy, termed *copy-shift*, avoids modulo operations by shifting the buffer contents after each execution. We demonstrate that, while a naive implementation of copy-shift can be 2× to 3× slower than modulation, optimizations that utilize execution scaling can boost the performance of copy-shift to be significantly faster than modulation (51% speedup on StrongARM, 48% speedup on Pentium 3, and 5% speedup on Itanium 2).

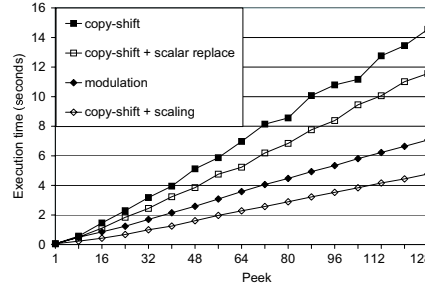
Our study is done in the context of a synthetic benchmark, shown in Figure 7. The benchmark is a pipeline consisting of a simple source and an FIR actor. On each iteration, the source pushes a single item. The FIR actor calculates a weighted sum over `PEEK` items of the input, then pops a single item from the channel. In our experiments, we vary the `PEEK` value from 1 to 128 items.

### 5.1 Modulation

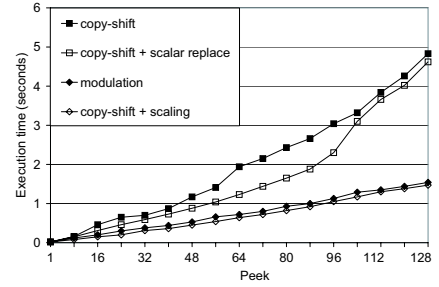
Figure 8 illustrates a fused version of the benchmark using modulation for buffer management. For simplicity, we illustrate each buffer management strategy as a source-to-source transformation in StreamIt. Each fused actor contains a `prework` function in which the source actor executes several times to prime the communication



**Figure 9.** Performance of buffer management strategies on a StrongARM.



**Figure 10.** Performance of buffer management strategies on a Pentium 3.



**Figure 11.** Performance of buffer management strategies on an Itanium 2.

```
void->void filter BufferTest {
  int PEEK = 4;
  float[3] BUFFER;

  prework {
    for (int i=0; i<PEEK-1; i++) {
      BUFFER[i] = ... ;
    }
  }

  work {
    float[4] TEMP_BUFFER;
    int push_index = 3;
    int pop_index = 0;

    // copy from BUFFER to TEMP_BUFFER
    for (int i=0; i<3; i++) {
      TEMP_BUFFER[i] = BUFFER[i];
    }

    // run Source
    TEMP_BUFFER[push_index++] = ... ;

    // run FIR
    float result = 0;
    for (int i=1; i<PEEK; i++) {
      result += i*TEMP_BUFFER[pop_index+i];
    }
    pop_index++;
    print(result);

    // copy from TEMP_BUFFER to BUFFER
    for (int i=0; i<3; i++) {
      BUFFER[i] = TEMP_BUFFER[i+1];
    }
  }
}
```

**Figure 12.** Copy-shift strategy.

```
void->void filter BufferTest {
  int PEEK = 4;
  float[3] BUFFER;

  prework {
    for (int i=0; i<PEEK-1; i++) {
      BUFFER[i] = ... ;
    }
  }

  work {
    float TEMP_BUFFER_0;
    float TEMP_BUFFER_1;
    float TEMP_BUFFER_2;
    float TEMP_BUFFER_3;

    // copy from BUFFER to TEMP_BUFFER
    TEMP_BUFFER_0 = BUFFER[0];
    TEMP_BUFFER_1 = BUFFER[1];
    TEMP_BUFFER_2 = BUFFER[2];

    // run Source
    TEMP_BUFFER_3 = ... ;

    // run FIR
    float result = 0;
    result += 1*TEMP_BUFFER_1;
    result += 2*TEMP_BUFFER_2;
    result += 3*TEMP_BUFFER_3;
    print(result);

    // copy from TEMP_BUFFER to BUFFER
    BUFFER[0] = TEMP_BUFFER_1;
    BUFFER[1] = TEMP_BUFFER_2;
    BUFFER[2] = TEMP_BUFFER_3;
  }
}
```

**Figure 13.** Copy-shift with scalar-replacement.

```
void->void filter BufferTest {
  int PEEK = 4;
  float[3] BUFFER;

  prework {
    for (int i=0; i<PEEK-1; i++) {
      BUFFER[i] = ... ;
    }
  }

  work {
    float[32] TEMP_BUFFER;
    int push_index = 3;
    int pop_index = 0;

    // copy from BUFFER to TEMP_BUFFER
    for (int i=0; i<3; i++) {
      TEMP_BUFFER[i] = BUFFER[i];
    }

    // run Source 16 times
    for (int k=0; k<16; k++) {
      TEMP_BUFFER[push_index++] = ... ;
    }

    // run FIR 16 times
    for (int k=0; k<16; k++) {
      float result = 0;
      for (int i=1; i<PEEK; i++) {
        result += i*TEMP_BUFFER[pop_index+i];
      }
      pop_index++;
      print(result);
    }

    // copy from TEMP_BUFFER to BUFFER
    for (int i=0; i<3; i++) {
      BUFFER[i] = TEMP_BUFFER[i+16];
    }
  }
}
```

**Figure 14.** Copy-shift with execution scaling.

channel with initial items, as well as a `work` function that represents the steady-state execution.

The modulation scheme uses a traditional circular-buffer approach. Three variables are introduced: a `BUFFER` to hold all items transferred between the actors, a `push_index` to indicate the buffer location that will be written next, and a `pop_index` to indicate the buffer location that will be read next (i.e., the location corresponding to `peek(0)`). The communication primitives are translated as follows:

```
push(val); ==> BUFFER[push_index] = val;
              push_index = (push_index + 1) % BUF_SIZE;

pop();      ==> pop_index = (pop_index + 1) % BUF_SIZE;

peek(i)    ==> BUFFER[(pop_index + i) % BUF_SIZE]
```

The StreamIt compiler converts the modulo operations to bitwise-and operations by scaling the buffer to a power of two. Note that if there are no `peek` operations, then the buffer will be empty following each execution of the downstream actor. In this case, the indices can be reset to zero at the start of each execution and the modulo operations can be eliminated. However, in our example the FIR actor performs peeking, so the modulo operations are needed.

**Experimental setup.** Figures 9, 10 and 11 illustrate the performance of various buffer management strategies on a 137 Mhz StrongARM 1110, a 600 Mhz Pentium 3 and a 1.3 Ghz Itanium 2, respectively. The figures illustrate the execution time per  $10^7$  outputs for the synthetic benchmark (Figure 7) across a range of `PEEK` values. To ensure a fair comparison with the scalar replacement optimization (Section 5.3), all loops in the original actor are fully unrolled.

**Evaluation.** The time required for the modulation strategy increases linearly with the peek rate. This is expected, as there is a constant overhead per peek operation. Relative to the other strategies, modulation performs noticeably better on the Itanium 2. We attribute this to the six integer units on the Itanium 2; since there is not much additional work in this benchmark, it can likely process the modulo operations in parallel with other operations using software pipelining.

## 5.2 Copy-Shift

The copy-shift strategy, illustrated in Figure 12, shifts the live items to the front of the buffer at the beginning of each execution. Because each execution starts writing to and reading from the buffer at the same location, there is no need for the indices to wraparound and the modulo operations can be eliminated. This benefit is compounded by additional optimizations enabled by the copy-shift approach, as described in the subsequent sections.

However, the cost of this strategy comes in the copying operations: at the start of each execution,  $(peek - pop)$  items are copied from the persistent BUFFER to the beginning of a local TEMP\_BUFFER. Subsequent operations reference TEMP\_BUFFER, and the live items are copied back to the BUFFER upon completion. While these two variables could also be combined into a single buffer, keeping them separate results in a smaller live data set when the actor is not executing.

The communication primitives are translated as follows:

```
push(val); ==> TEMP_BUFFER[push_index] = val;
              push_index = push_index + 1;

pop();      ==> pop_index = pop_index + 1;

peek(i)    ==> TEMP_BUFFER[pop_index + i]
```

Compared to the modulation scheme, the copy-shift strategy references the TEMP\_BUFFER and does not perform modulo operations.

**Evaluation.** As shown in Figures 9, 10 and 11, the unoptimized copy-shift strategy is the slowest strategy that we evaluate. Though the cost per peek operation is smaller than the modulation scheme, the copying overhead per iteration also grows with the peek rate and cancels out any savings; overall, copy-shift performs from  $2\times$  to  $3\times$  slower than modulation. The following sections describe optimizations that can justify taking the copy-shift approach.

## 5.3 Copy-Shift with Scalar Replacement

The first optimization enabled by the copy-shift scheme is dubbed *scalar replacement*. In contrast to the modulation scheme, the copy-shift approach can result in array operations that access the same location on every execution of the actor. The idea behind scalar replacement is to fully unroll the loops in the actor, thereby resolving each array index to an integer literal. Then, since each location is fully resolved at compile time, an  $n$ -length array can be replaced by a set of  $n$  scalar variables: one for each item in the buffer. This transformation is illustrated in Figure 13.

Scalar replacement offers several performance benefits. Scalar variables can be register allocated, and as local variables they are subject to a range of dataflow optimizations (constant propagation, copy propagation, dead code elimination, etc.). Replacing array operations with scalars also eliminates array index calculations. Despite these benefits, scalar replacement is nearly impossible to do in a general-purpose language such as C because array contents might be aliased with other pointers. StreamIt arrays represent values that are independent in memory, thereby facilitating this optimization.

Note that scalar replacement can only be applied when array indices can be resolved to compile-time constants. In the presence

of unpredictable control flow within an actor, or if the loops are too large to fully unroll, then scalar replacement does not apply.

**Evaluation.** Compared to an unoptimized copy-shift strategy, Figures 9, Figures 10 and 11 illustrate that scalar replacement offers modest gains on our synthetic benchmark. At the maximum peek rate of 128, the StrongARM and Pentium 3 offer speedups of 16% and 26%, respectively; these speedups are roughly uniform across all peek rates. On the Itanium 2, speedups range from 5% to 58% depending on the peek rate. We conjecture that scalar replacement is more critical for small actors that perform only a few operations. Due to the high communication-to-computation ratio in such actors, there could be large gains from register-allocating and copy-propagating the temporary variables.

## 5.4 Copy-Shift with Execution Scaling

A final optimization of the copy-shift strategy uses execution scaling to dramatically decrease the overhead associated with copying the buffer contents on each iteration. In any actor, the number of items inspected on one execution and saved for the next execution is  $(peek - pop)$ . This represents the number of items copied by the copy-shift scheme. However, this cost can be amortized by scaling the number of executions of the downstream actor in the fused code. By enclosing the body of the actor in a loop, the *peek* and *pop* rates can be made arbitrarily large, while  $(peek - pop)$  remains constant.

Thus, execution scaling reduces the fraction of time spent copying to an arbitrarily small level. In our study, we scale the executions of an actor until  $(peek - pop) \leq \frac{1}{4} pop$ . In the synthetic benchmark, this implies that each actor body executes 16 times before the buffer contents are shifted. The code resulting from this transformation is shown in Figure 14.

Note that due to the large loops introduced by execution scaling, it cannot be used in combination with scalar replacement. If the loops were unrolled to resolve the array indices, there could be a negative impact on the instruction cache.

**Evaluation.** As shown in Figures 9 and 10, the copy-shift approach with execution scaling performs significantly better than modulation on the StrongARM and Pentium 3. At the maximum peek rate of 128, the StrongARM exhibits a 51% speedup while the Pentium 3 shows a 48%. These speedups make sense, as each peek operation is cheaper due to the eliminated modulo operations (implemented as bitwise-and in the modulation scheme), while the overhead from copying is reduced to a fraction of the original copy-shift approach.

The gains are less substantial on Itanium 2, where the speedup at  $peek = 128$  is only 5% (Figure 11). We attribute this to the relatively high performance of the modulation approach on Itanium 2; due to the six parallel integer units, the bitwise-and operation may not increase the critical path. This balance might be different in programs with higher integer workloads within the actors. Still, copy-shift with execution scaling does no worse than modulation (on any architecture), and execution scaling always offers a large speedup over the original copy-shift approach.

## 5.5 Summary

We conclude that copy-shift with execution scaling is the best buffer management strategy for actors that utilize peeking. This is somewhat surprising because the unoptimized copy-shift strategy has large overheads that result in a slowdown relative to a circular buffer with modulation. However, by leveraging the flexibility of the parallel stream graph to perform execution scaling, the overheads are amortized. Compared to a plain circular buffer strategy, there are significant improvements on StrongARM (51% speedup) and Pentium 3 (48% speedup), and respectable performance (5% speedup) on Itanium 2.



Benchmark	Description	# of Actors
bitonic	bitonic sort of 64 integers	972
fir	finite impulse response (128 taps)	132
fft-fine	fine grained 64-way FFT	267
fft-coarse	coarse grained 64-way FFT	26
3gpp	3GPP Radio Access Protocol	105
beamformer	beamformer with 64 channels and 1 beam	197
matmult	matrix multiplication	48
fmradio	FM Radio with 10-way equalizer	49
filterbank	filterbank program (8 bands, 32 taps / filter)	53
filterbank2	independent filterbank (3 bands, 100 taps / filter)	37
ofdm	Orthogonal Frequency Division Multiplexor [20]	16

Table 1. Evaluation benchmark suite.

## 6. Experimental Evaluation

In this section we evaluate the merits of the proposed cache aware optimizations and buffer management strategies. We use three different architectures: a 137 MHz StrongARM 1110, a 600 MHz Pentium 3 and a 1.3 GHz Itanium 2. The StrongARM results reflect performance for an embedded target; it has a 16 Kb L1 instruction cache, an 8 Kb L1 data cache, and no L2 cache. The StrongARM also has a separate 512-byte minicache (not targeted by our optimizations). The Pentium 3 and Itanium 2 reflect desktop performance; they have a 16 Kb L1 instruction cache, 16 Kb L1 data cache, and 256 Kb shared L2 cache.

Our benchmark suite (see Table 6) consists of 11 StreamIt applications. They are compiled with the StreamIt compiler which applies the optimizations described in this paper, as well as aggressive loop unrolling (by a factor of 128 for all benchmarks) to facilitate scalar replacement (Section 5). The StreamIt compiler outputs a functionally equivalent C program that is compiled with `gcc` (v3.4, -O3) for the StrongARM and for the Pentium 3 and with `icc` (v7.0, -O3) for the Itanium 2. Each benchmark is then run five times, and the median user time is recorded.

As the StrongARM does not have a floating point unit, we converted all of our floating point applications (i.e., every application except for `bitonic`) to operate on integers rather than floats. In practice, a detailed precision analysis is needed in converting such applications to fixed-point. However, as the control flow within these applications is very static, we are able to preserve the computation pattern for the sake of benchmarking by simply replacing every floating point type with an integer type.

We also made an additional modification in compiling to the StrongARM: our execution scaling heuristic scales actors until their output fills 100% of the data cache, rather than 2/3 of the data cache as described in Section 4. This modification accounts for the 32-way set-associative L1 data cache in the StrongARM. Due to the high degree of associativity, there is a smaller chance that the actor outputs will repeatedly evict the state variables of the actor, thereby making it worthwhile to further fill the data cache. This observation yields up to 25% improvement on some benchmarks.

**Overall Speedup** The overall speedups offered by our techniques are illustrated in Figure 15 (StrongARM), Figure 16 (Pentium 3), and 16 (Itanium 2). These graphs have two bars: one for “full fusion”, in which all actors are fused into a single function (with scalar replacement), and one labeled `CAF+scaling+buffer`, representing all of our optimizations (cache aware fusion, execution scaling, and buffer optimizations) applied together. We include the comparison to full fusion because it represents a simple approach for eliminating function call overhead and optimizing across actor boundaries; while this fusion strategy utilizes our scalar replacement optimization, it remains oblivious to instruction and data locality. Performance is normalized to unoptimized

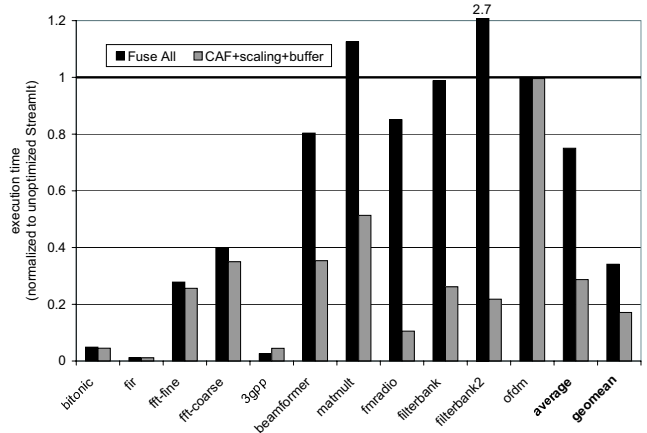


Figure 15. Summary of results on a StrongARM.

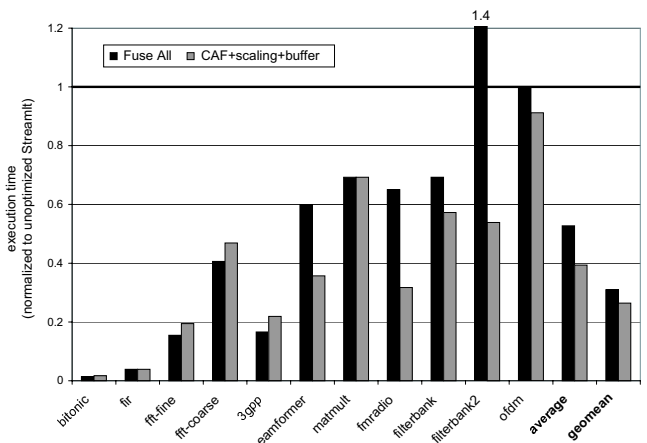


Figure 16. Summary of results on a Pentium 3

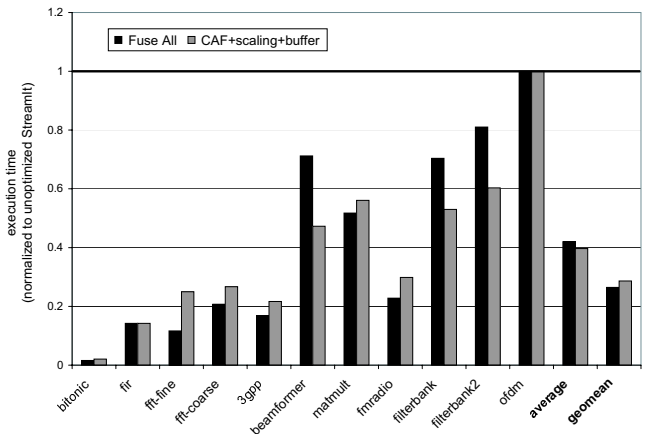


Figure 17. Summary of results on an Itanium 2

StreamIt, in which no actors are fused (but there is still unrolling by 128). On the right of each graph, both arithmetic and geometric means are shown for the benchmarks. We usually speak in terms of the arithmetic means as they are more intuitive (and also yield more conservative speedups), though we refer to the geometric mean for an unambiguous reference on close results.

On StrongARM (Figure 15), our cache optimizations offer a 249% average speedup over the baseline and a 162% average speedup over full fusion. Scalar replacement is responsible for much of the gains that both strategies offer over the baseline. Cache optimizations always perform better than the baseline, and they perform better than full fusion in all cases except for `3gpp`, where they yield a 45% slowdown. This slowdown is due to conservative code size estimation: the compiler predicts that the fused version of `3gpp` will not fit into the instruction cache, thereby preventing fusion. However, due to optimizations by `gcc`, the final code size is smaller than expected and does fit within the cache. While such inaccuracies could be improved by adding feedback between the output of `gcc` and our code estimation, each fusion possibility would need to be evaluated separately as the fusion boundary affects the impact of low-level optimizations (and thus the final code size).

The speedups offered by cache optimizations over a full fusion strategy are more modest for the desktop processors: 34% average speedup on Pentium 3 (Figure 16) and essentially zero speedup (6% by the arithmetic mean, -8% by the geometric mean) on Itanium 2 (Figure 17). Out of the 11 benchmarks, cache optimizations perform as well or better than full fusion for 7 benchmarks on the Pentium 3 and 5 benchmarks on the Itanium 2. Performance on any architecture is a tradeoff between two factors: 1) the benefit of data and instruction locality, and 2) the benefit of fusion, which reduces memory accesses due to improved register allocation across actor boundaries. Compared to the StrongARM, the Pentium 3 and Itanium 2 offer an L2 cache (as well as a larger L1 data cache), thereby lessening the impact of locality-enhancing cache optimizations. However, the fusion benefit remains a significant factor; for example, using Intel VTune on the Pentium 3, we measured that full fusion offers a 50% reduction in memory accesses over the cache-optimized version. This effect may be pronounced on the Itanium 2 due to the larger number of registers on that architecture (128 general, 128 floating point). While fusion benefits are also present on the StrongARM, cache optimizations are more important on that processor due to the large penalty for cache misses.

The cache aware fusion algorithm can be adjusted to account for the caching hierarchy on desktop machines. Specifically, if cache aware fusion is modified to allow fused actors to consume up to one half of the L2 cache (rather than L1 cache), then the performance of the cache optimizations is closer or equal to full fusion, for cases it was previously trailing on the Pentium 3 or the Itanium 2 (data not shown). The only benchmark that is negatively impacted by this change is `ofdm`, where two large actors are fused despite a very low communication to computation ratio, thereby lessening the impact of eliminated memory accesses while nonetheless worsening the instruction locality.

**Impact of Each Optimization** To better understand the overall speedups, we assess the individual performance impact of execution scaling, cache aware fusion, and buffer management optimizations. These results are illustrated in Figures 18, 19 and 20 for the StrongARM, Pentium 3, and Itanium 2, respectively. There are four bars per benchmark; as in the previous analysis, all performance is normalized to unoptimized StreamIt (with 128-way unrolling). The first bar, labeled `scaling`, applies only execution scaling. The second bar, labeled `CAF`, applies only cache aware fusion, including scalar replacement across the fused actors. The third bar, labeled `CAF+scaling`, first applies cache aware fusion with scalar replacement and then applies execution-scaling to the granularity-adjusted actors. The fourth bar, labeled `CAF+scaling+buffer`, additionally applies buffer management optimizations (detailed later); this bar is equivalent to the “best” cache-optimized performance illustrated in Figures 15, 16, and 17.

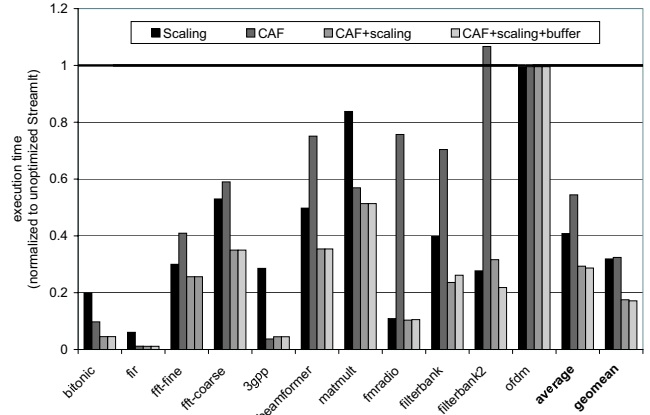


Figure 18. Impact of each optimization on a StrongARM.

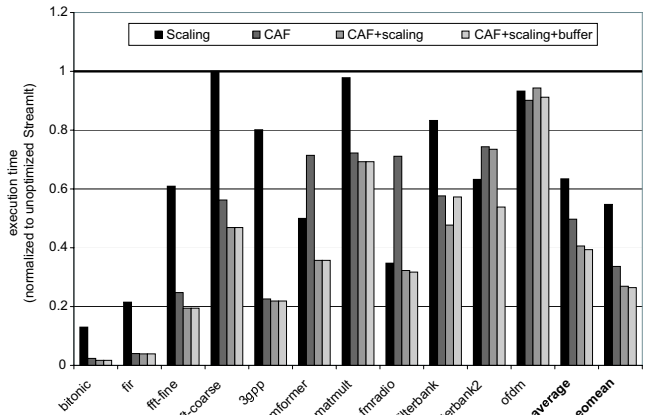


Figure 19. Impact of each optimization on a Pentium 3.

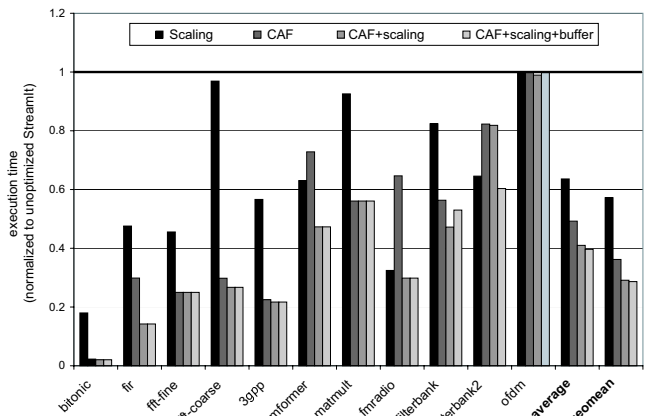


Figure 20. Impact of each optimization on an Itanium 2.

Execution scaling improves performance over unoptimized StreamIt, with average speedups of 145% for StrongARM, 58% for Pentium 3, and 57% for Itanium 2. The 90-10 heuristic works quite well (see [18] for full details) and there is only one instance where scaling results in a performance degradation. The granularity-adjusted `3gpp` on StrongARM has a 17% slowdown due to scaling (compare `CAF` to `CAF+scaling` in Figure 15).

This is possibly due to items in flight between the granularity-adjusted actors overwriting the state of an executing actor in the data cache. Since StrongARM has no L2 cache then such eviction can be quite expensive.

Independently, cache aware fusion also improves performance by 84% on StrongARM, 101% on Pentium 3 and a 103% on the Itanium 2. cache aware fusion degrades performance only for `filter-bank2` (by 6% on StrongARM). When we combine cache aware fusion with execution scaling, the performance consistently improves. The speedup of `CAF+scaling` over baseline is 241% on StrongARM, 146% on Pentium 3 and 144% on Itanium 2.

However, after coarsening the actors with cache aware fusion, scaling results in less additional speedup than it did relative to the baseline. The speedup of `CAF+scaling` over `CAF` is 86% for StrongARM, 22% for Pentium 3 and only 20% for Itanium 2. This is because some actors are implicitly scaled by fusion to match input/output rates of successive actors within a fused block.

Note that the `ofdm` benchmark does not benefit from fusion or scaling. This is because `ofdm` has few actors, some of which consume and produce a total of 16-66 Kb data; consequently, execution scaling does not apply. Also there is limited opportunity to fuse actors within `ofdm`, as there are actors that have an instruction size of 9 Kb and fusing them with other actors would exceed the instruction cache.

The last bar, `CAF+scaling+buffer`, illustrates the benefit of buffer management optimizations for filters that peek. As detailed in Section 5, such filters demand specialized buffer management, as they reuse items on the input tape across successive iterations. In our benchmark suite, peeking occurs only in the last four applications (i.e., `fmradio`, `filterbank`, `filterbank2` and `ofdm`). Thus, the `CAF+scaling` bar is equivalent to `CAF+scaling+buffer` for all benchmarks from `bitonic` through `matmult`.

The buffer optimization applied in Figures 15, 16, and 17 is termed `cutpeek`. In this optimization, the cache aware fusion algorithm is modified so that two adjacent filters are never fused if the downstream filter performs any peeking (i.e., it has `peek > pop`). Following execution scaling, the live items are copied to the start of the buffer once per scaled execution (using the copy-shift strategy, Section 5), thereby reducing the overhead of copying live items. Optimized buffer management offers the largest gains for `filterbank2`: 45% on StrongARM, 38% on Pentium 3, and 36% on Itanium 2. This is due to a large peek rate (100 items) in addition a large scaling factor of 300 that amortizes the cost of copying items.

While we found that `cutpeek` is, on average, the best buffer management strategy across the three platforms, we also evaluated several others. For `fmradio`, up to a 5% improvement is offered by a strategy called `peekscale`, in which (prior to other optimizations) filters with `peek > pop` are scaled to perform several executions at once. As scaling is performed, the `pop` and `peek` rates increase but `peek - pop` remains constant; scaling continues until the `pop` rate is at least  $4 * (peek - pop)$ . Like `cutpeek`, this serves to amortize the overhead of copy-shift, but it can also hamper the execution scaling optimization. Because certain other actors in the graph must fire more frequently to compensate for the scaled peeking filter, there is less room for global execution scaling. The only other case where `peekscale` is the best strategy is for `ofdm` on StrongARM, where there is a 7% improvement over `cutpeek`. Finally, on the `filterbank` benchmark, highest performance results from unoptimized copy-shift buffer management. We also evaluated buffer management using modulation for indexing, but this did not yield the best performance for any benchmark or platform.

## 7. Related Work

There is a large body of literature on scheduling synchronous dataflow (SDF) graphs to optimize various metrics [4, 5]. The work most closely related to ours is a recent study by Kohli [11] on cache aware scheduling of SDF graphs, implemented as part of the Ptolemy framework for simulating heterogeneous embedded systems [12]. Kohli develops a Cache Aware Scheduling (CAS) heuristic for an embedded target with a software-managed scratchpad instruction cache. His algorithm greedily decides how many times to execute a given actor based on estimates of the data cache and instruction cache penalties associated with switching to the next actor. In contrast, our algorithm considers the buffering requirements of all filters in a given container and increases the multiplicity so long as 90% of buffers are contained within the data cache. Kohli does not consider buffer management strategies, and the evaluation is limited to one 6-filter pipeline and an assortment of random SDF graphs. An empirical comparison of our heuristics on a common architectural target would be an interesting direction for future work.

It is recognized that there is a tradeoff between code size and buffer size when determining an SDF schedule. Most techniques to date have focused on “single appearance schedules” in which each filter appears at only one position in the loop nest denoting the schedule. Such schedules guarantee minimal code size and facilitate the inlining of filters. There are a number of approaches to minimizing the buffer requirements for single-appearance schedules (see [4] for a review). While it has been shown that obtaining the minimal memory requirements for general graphs is NP-complete [3], there are two complementary heuristics, APGAN (Pairwise Grouping of Adjacent Nodes) and RPMC (Recursive Partitioning by Minimum Cuts), that have been shown to be effective when applied together [3]. Buffer merging [15, 16] represents another technique for decreasing buffer sizes, which could be integrated with our approach in the future.

Govindarajan et al. develop a linear programming framework for determining the “rate-optimal schedule” with the minimal memory requirement [7]. A rate-optimal schedule is one that takes advantage of parallel resources to execute the graph with the maximal throughput. However, the technique is specific to rate-optimal schedules and can result in a code size explosion, as the same node is potentially executed in many different contexts.

The work described above is related to ours in that minimizing buffer requirements can also improve caching behavior. However, our goal is different in that we aim to improve spatial and temporal locality instead of simply decreasing the size of the live data set. In fact, our scaling transformation actually *increases* the size of the data buffers, leading to higher performance across our benchmark suite. Our transformations also take into account the size of the instruction and data caches to select an appropriate scaling and partitioning for the stream graph.

Proebsting and Watterson [17] give a fusion algorithm that interleaves the control flow graphs of adjacent filters. However, their algorithm only supports synchronous `get` and `put` operations; StreamIt’s `peek` operation necessitates buffer management between filters.

There are a large number of stream programming languages; see [19] for a review. The Brook language [6] extends C to include data-parallel kernels and multi-dimensional streams that can be manipulated via predefined operators. Synchronous languages such as Esterel [2] and LUSTRE [8] also target the embedded domain, but they are more control-oriented than StreamIt and are less amenable to compile-time optimizations. Benveniste et al. [1] also provides an overview of dataflow synchronous languages. Sisal (Stream and Iteration in a Single Assignment Language) is a high-performance,

implicitly parallel functional language [9]. We are not aware of any cache aware optimizations in these stream languages.

There is a large body of work covering cache miss equations, and an equally large body of work concerned with analytical models for reasoning about data reuse distances and cache behavior. The model introduced in this paper is loosely based on the notion of stack reuse distances [14]. Our model is especially tailored to streaming computations, and unique in leveraging the concept of a steady state execution.

## 8. Conclusions

In this paper, we present a simple yet highly effective methodology for running streaming programs on common cache-based architectures. The work shows that we can exploit the abundant parallelism in streaming codes to improve the behavior of the cache hierarchy and deliver significant performance improvements on existing machines. We evaluate our methodology on three architectures: the embedded StrongARM processor, the superscalar Pentium 3, and the VLIW Itanium 2.

Our optimizations are simple but yield surprisingly big savings in performance. First, we introduce *execution scaling*, which increases the execution frequency of every actor in the stream graph. Intuitively, scaling improves instruction locality because it increases the amount of reuse from the instruction cache. Concomitantly, it leads to performance gains of 145% on the StrongARM, 58% on the Pentium 3, and 57% on the Itanium 2. It is worthy to note that execution scaling is a departure from past optimization strategies for streaming programs, which try to minimize buffer requirements. Our scaling transformation actually *increases* the size of the data buffers between actors.

We also showed that scaling presents a tradeoff between instruction locality and data locality. Using a simple cache model, we show how scaling impacts the instruction and data caches. The model serves to motivate a heuristic for calculating the scaling factor. The heuristic, which accounts for the size of the instruction and data caches, works quite well in practice.

This paper also introduces *cache aware fusion*. The fusion optimization helps to reduce the data requirements of a program, and can reduce the total number of memory requests by as much as 50%. The fusion of actors in the stream graph is carried out judiciously, and our algorithms are sensitive to the instruction and data working sets of the coarsened execution units, as well as their impact on the cache hierarchy. Cache aware fusion leads to performance gains of 84% on the StrongARM, 101% on the Pentium 3, and 103% on the Itanium 2.

Cache aware fusion also enables a set of novel buffer management strategies for handling the streams of data between actors. Due to the static nature of stream programs, we can often apply *scalar replacement* to remove array references, and thus communication between fused actors is done through registers, rather than through memory. To allow scalar replacement to apply to sliding window computations, we introduce a *copy-shift* buffer management policy that out-performs a traditional rotating buffer.

In summary, the application of execution scaling, cache aware fusion, and our new buffer management strategies, can improve performance of StreamIt programs by 249% on the StrongARM, 154% on the Pentium 3, and 152% on the Itanium 2.

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