
School of Electrical, Electronic & Computer Engineering



**Studying an SoC with Virtual Self-timed Blocks
using MATLAB Simulink**

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Studying SoC with Virtual Self-timed Block using MATLAB Simulink

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ABSTRACT

In order to increase the power efficiency of IP cores in an SoC, a Self-timed Event Processor (STEP) is modelled and designed in our previous research to provide power management and event handling for each IP core in a frame of Virtual Self-timed Block (VSB). This paper presents the construction of an example SoC with four VSBs in MATLAB Simulink where a test bench named as “ball game” was implemented. The benchmark achieved from MATLAB Simulation verified the correctness and efficiency of our STEP design.

1. INTRODUCTION

In order to increase the energy efficiency of IP cores in an SoC, a Self-timed Event Processor (STEP) is modelled and designed in our previous studies [1,2,3,4] to provide power management and event handling for each IP core in a frame of Virtual Self-timed Block (VSB). In [2], stochastic models have been used to analyze an IP core’s performance in power and latency when the mode switching transitions in the core are accurately represented. A stochastic DPM (Dynamic Power Management) policy named Accumulation & Fire (A&F) was verified to have great potential in trading power with latency for an IP core no matter how many inactive/active modes that are provided by the core. Fine grain stochastic models were used in later study [3] where executions in a Control Unit (the controller for both power management and task management) were integrated into stochastic state space. An IP core with A&F control was proved to have high power efficiency even when the cost in the Control Unit was calculated. Therefore based on these studies, A&F policy was chosen to be implemented in our STEP design to provide easy and efficiency power control.

A Model Based Design (MBD) method was used in [4] when hierarchical CPN (Coloured Petri Nets) were used to specify, analyze, verify and simulate the executions in a VSB. All parallel processing in a VSB which was caused by on chip nondeterminism and concurrency were modelled as simultaneous enabling of transitions in CPN models. CPN simulation and state space checking verified these parallel processing can shorten system latency.

Although all executions in a STEP were described in detail in CPN models, the executions in the corresponding IP core are abstracted. For example, only two transitions (the $Load_i$ and $Execution_i$ ($i=1,2$) transitions in Section 3.5 of [4]) were used to represent the executions in an IP core. It is because our main concern is about the design of a STEP

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which can cooperate with different kinds of IP cores. Although the execution detail in an IP core can be abstracted because it has little influence about the VSB design, it has great impact on the VSB performance. The analysis of both power and latency performance in a VSB can only be carried out when the IP core is specified.

Furthermore, our modelling and analysis work in both stochastic and CPN models assume the incoming of events follows exponential distribution. This assumption can not be satisfied in all implementations. Therefore, we have to explore the performance of our VSB with A&F control when events incoming follows weak even non-exponential distribution.

Therefore, an example model of VSB should be built with a specified IP core and a real SoC environment. This example is used for the analysis of the average power/latency performance of the core in time dimension. MATLAB Simulink rather than CPN is used in this analysis because its powerful simulation as well as visualisation functions.

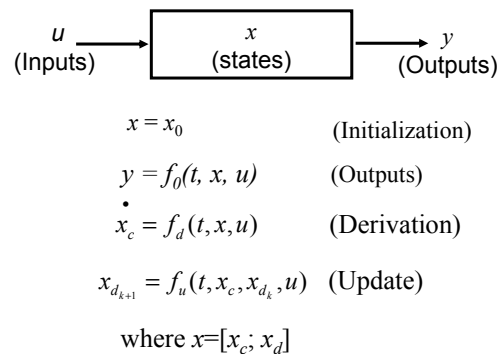


Figure 1: Mathematical Representation of Simulink Execution

Figure 1 gives the mathematical expression of a Simulink component. Vector u and y represent the inputs to a Simulink component respectively. Vector x represents the states of the component. x_c and x_d are used to represent the continuous and discrete states in x respectively. If x_0 represents the initial status of the component, it will be loaded to x during the initialization phase of Simulation model execution. When the initialization completes, Simulation executes all components in sequence according to the model's structure/connection. For the execution of one particular component, Simulink will calculate the new output of the component based on the current input u and state x . And it will calculate the component's new state by derivation (for continuous system) and/or update (for discrete system). This continues until the simulation is complete.

Therefore, although the model built in Simulink can not represent and simulate the truly asynchronous behaviours because MATLAB is a software operated in a synchronous platform, its simulation result can be very close to that generated in a real asynchronous system when the components used in the model are atomic and the sample intervals are short enough.

A library of fundamental components is provided by MATLAB Simulink. The STEP in a VSB is constructed by these components from the library so as to provide detail observation of executions in the STEP. When the components provided by the Simulink Library can not represent the design of users, they can use the *S-function* component to describe their design in program codes and integrate the codes with the other components

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in Simulink. An S-function (system-function) is a computer language description of a Simulink block. S-function can be written in MATLAB, C, C++, Ada, or Fortran. In our study, S-function is used to describe the executions in an IP core because the IP core design is not one part of our research, we only care about the function rather than the circuit detail of the IP core.

The rest of this paper is organized as follows: Section 2 is used to describe the SoC implementation of the VSB where a toy system named as “ball game” is designed. According to [4], a STEP can be divided into five main parts: *Event Handler (EH)*, *Power Manager (PM)*, *Task Manager (TM)*, *Output Control (OCtl)* and *Interface*. Section 3 is used to describe the construction of every part of the STEP in MATLAB Simulink and the corresponding simulation result. The design of an example IP core is introduced in Section 4 and the power/latency analysis of the example system was provided in Section 5. Finally is the conclusion and future work in Section 6.

2. IMPLEMENTATION SPECIFICATION

The example implementation used in this chapter is named as **Ball Game** (Figure 2). In the implementation, four balls of different size move in a playground with different speed but identical mode. The entire playground has been evenly divided into four parts, named as playground I, II, III, IV respectively. Four VSBs are employed and each VSB is used to control the ball movement in one playground. Four tasks contain in the IP core of every VSB whose codes provide the movement control of the corresponding balls. Different codes may be used in the four tasks to provide random or history based movement, but they all need to avoid ball collision (too balls are shown as overlap) in the movement.

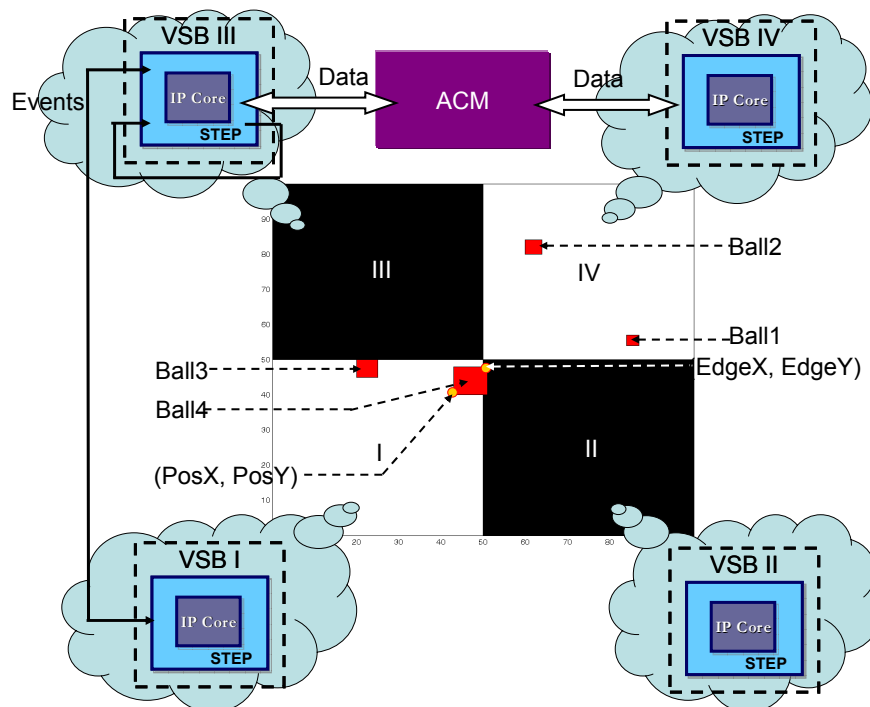


Figure 2: The Example Implementation of Ball Game

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When some ball moves across the boarder between two playgrounds, an event is generated to hand over the control of the ball to another VSB and parameters about the ball will be transferred to the VSB by the way of ACM.

If no balls contain in one playground (like playground III in Figure 2), the IP core in the corresponding VSB will be shut down to save power and the corresponding playground will be patched in black colour accordingly. When and how to activate the IP core for task processing depends on the DPM policy implemented in the STEP of each VSB.

The implementation detail is given as follows: A 100*100 pixels area is used as the entire playground of the ball game. Therefore each VSB controls a 50*50 pixels area. Four squares with different size represent the four balls in the game. And five parameters are used to describe one ball's movement. *PosX* and *PosY* are the positions of the bottom left edge of the ball in X and Y axis. *Width* represents the size of the ball and *Speed* indicates how fast the ball moves in each step. *History* remembers the direction of the ball's last movement. Four numbers (0,1,2,3) are used for the History information, which represent moving left, right, up, down respectively. Table 1: Initial Parameters of Four Balls gives the initial parameters of the balls in our example system.

Table 1: Initial Parameters of Four Balls

	PosX	PosY	Width	Speed	History
Ball1	84	54	4	4	1
Ball2	60	80	6	6	2
Ball3	20	45	8	8	3
Ball4	43	40	10	10	2

The position of the upper right edge of a ball is used to calculate if it is crossing the border of one playground. For example in Figure 2, Ball4 is just crossing from playground I to playground II, and VSB II will take the control of this ball accordingly.

In the current version of the ball game, the width and speed of each ball are constant, so they are kept in each task program in IP cores. However, the other three parameters, PosX, PosY and History, will be updated from time to time, and they will be saved in a public POOL typed ACM [5] for all VSBs rather than in the private memory of every VSB because the parameters of ALL balls are needed for the calculation of next position of one ball in case of collision even when some others are not contained in the same playground.

3. STEP DESIGN IN MATLAB SIMULINK

Since all VSBs in the implementation are identical, Figure 3 only gives the architecture of VSB I which controls the ball movement in playground I in MATLAB Simulink. The five subsystem blocks, PM, EH, TM, Interface and Output Control, are the five basic parts of the STEP. The IPCore block contains the four tasks, each of which controls the moving of one ball. The task programs are written as S-Function so as to integrate with the other block to give the unified simulation result. In order to reduce wires and connections in Simulink model, multiplex input/output ports are used and the number contained in the braces [] indicates the wire indexes integrated by the port. For example

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in Figure 3, the first input port Ch1[1:4] represents the four input signals from input Channel 1 and the fourth input port DataIn[1:24] represents 24 data input signals.

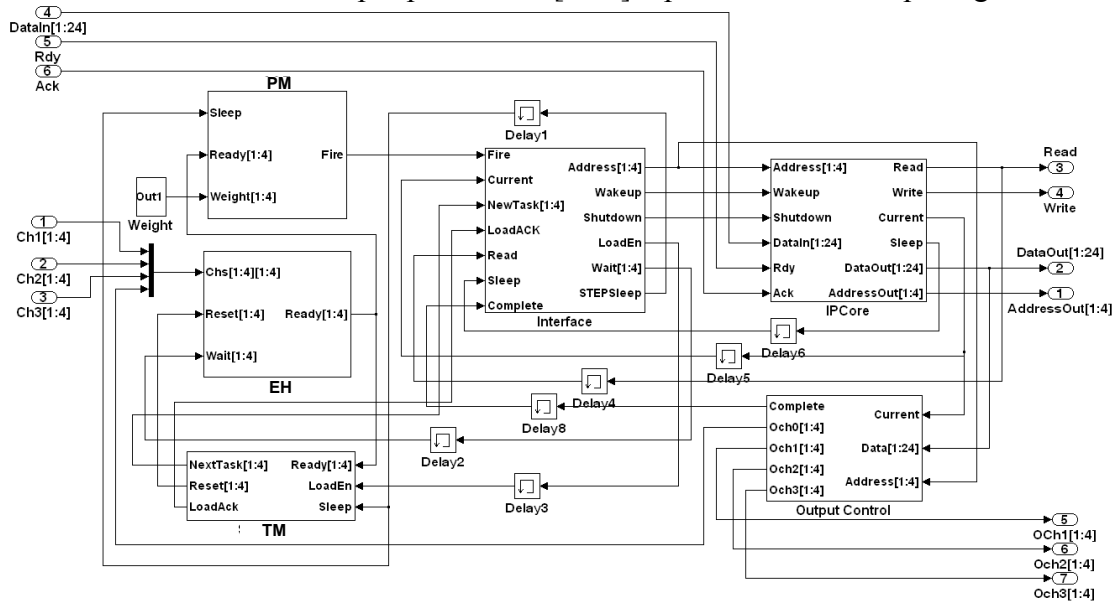


Figure 3: The Design of a Virtual Self-timed Block in Simulink

In the following sub-sections, the structure of the five parts of the STEP will be introduced in detail. The MATLAB model can be seen as the implementation of the CPN models in [4] and the simulation result in time/sample dimension of different signals in each part will be displayed accordingly.

3.1 The Design of Event Handler

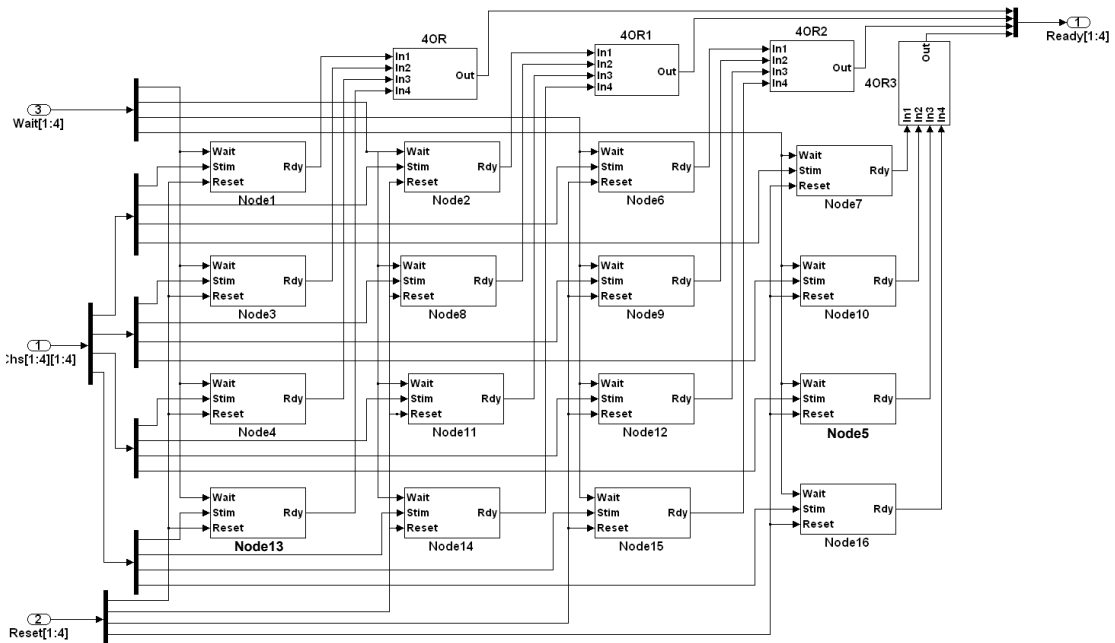


Figure 4: The Design of Event Handler Part in MATLAB

As four VSBs are used in the system and each VSB's IP core contains four tasks, the Event Handler Part of each VSB is built by 4*4 Wait&Stim nodes altogether (Figure 4).

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The first input port $\text{Chs}[1:4][1:4]$ is a multiplexed input port, which indicates there are four input Event Channels and each Channel use one-hot coding to indicate the ID number of the driven task. The first three Channels are used to connect with the other three VSBs and the last Channel is used as the feedback channel to receive events generated from the same VSB. Therefore, the event signals coming from the $\text{Chs}[1:4][1:4]$ port will be decomposed into 16 stim signals to set their corresponding stim bit in Nodes 1 to 16. Signals from the $\text{Wait}[1:4]$ port and $\text{Reset}[1:4]$ will set the wait bit or reset all Wait&Stim nodes in one column respectively. The operation in each node is the realization of the CPN model in Figure 8 in [4]. The subsystem block 4OR models the logic OR gate with four inputs. And signals from the output port $\text{Ready}[1:4]$ indicate which task is ready for processing.

According to the initial positions of four balls indicated by Table 1, both Ball3 and Ball4 are in playground I. Therefore the IP core in VSB I will be activated and task3 and task4 will be executed to control their corresponding balls to move one step further. Based on their initial history parameters, Ball3 will move one step up and Ball4 will move one step right, which means both of them will move out of playground I afterwards. The IP core in VSB I will be shut down accordingly. Although short, the period presents all executions that may be carried in one VSB. Therefore we use simulation provided by the MATLAB Simulink to observe signals' variation in different parts during this period. The simulation result for the EH part is given in Figure 5:

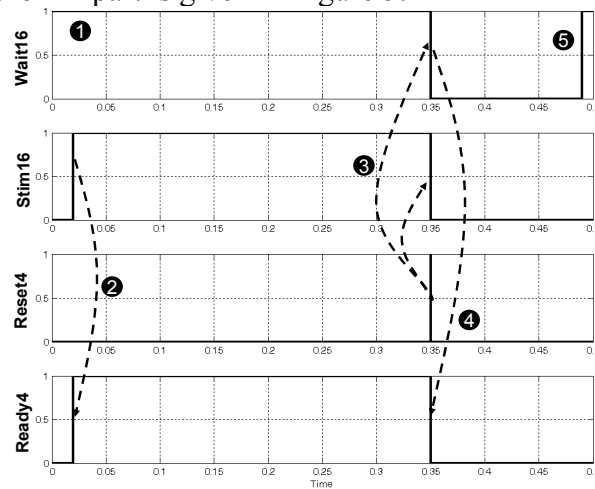


Figure 5: Simulation Result of the EH

In Figure 5, Wait16 indicates the status of the wait bit of Node 16. Since no task is processing in the IP core in the initialize stage, all wait signals keep high (1). And the initial setting will generate two events in the feedback Channel to activate task3 as well as task4. Therefore, Stim16 , as the stim bit for Node 16, becomes valid. When both stim and wait bits of Node 16 are set, Ready4 , as the 4th output signal in $\text{Ready}[1:4]$ becomes valid accordingly (2). After the IP core is fired (which is controlled by the Power Manager part that will be introduced in Section 3.2) and task4 is chosen to be loaded to the IP core (which is controlled by the Task Manager part that will be introduced in Section 3.3), Reset4 , as the 4th signal from input port $\text{Reset}[1:4]$ becomes valid. This signal will clear both stim and wait bits in Node 16 (3) so that Ready4 becomes invalid accordingly (4). After the execution of task4 in the IP core, Wait4 becomes valid again (5) indicating the corresponding task codes can be loaded to the IP core afterwards.

3.2 The Design of Power Manager

Figure 6 is about the design of PM Part in a VSB which is the realization of the CPN model of PM in Figure 9 in [4]. Each *access* subsystem block is the realization of the corresponding access transition in the CPN model of Figure 9 in [4]. Each *Polling* block is the realization of the corresponding select/pass transitions in Figure 9 in [4].

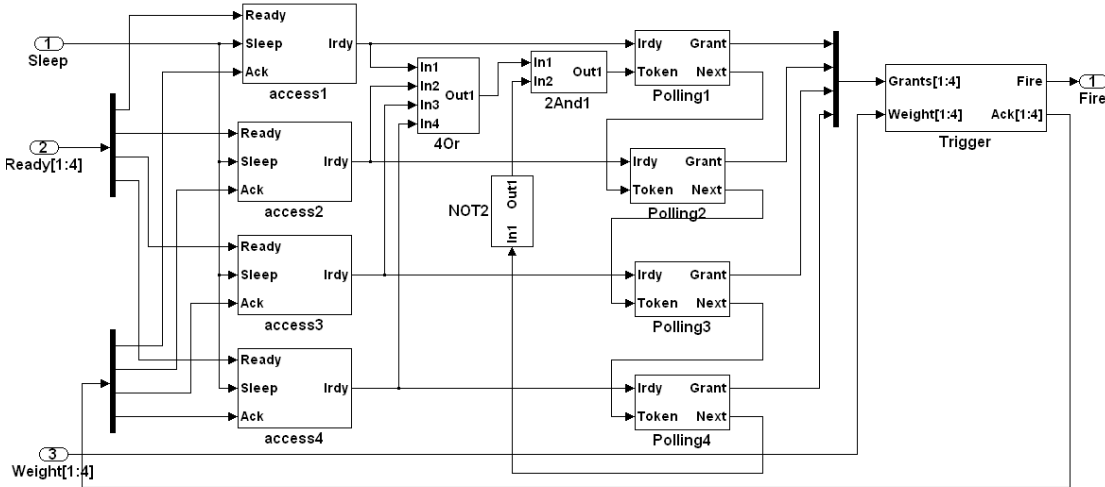


Figure 6: The Design of PM in MATLAB

The Trigger block in Figure 6 is based on the adder and Fire transitions in Figure 9 in [4]. Moreover, the weight of each task rather than the number of tasks is accumulated in this block. Currently, fixed weight is given to each task and the realization of the trigger block is given in Figure 7. If any grant signal from Grants[1:4] becomes valid, the corresponding weight number from Weight[1:4] will be added to the accumulation data which is kept in the Accumulation Memory block. Initially weight number 5 and 3 are given to task3 and task4 respectively. Given Threshold 6, the accumulation of these two tasks can active the IP core. A fire signal will be sent through the output port Fire accordingly.

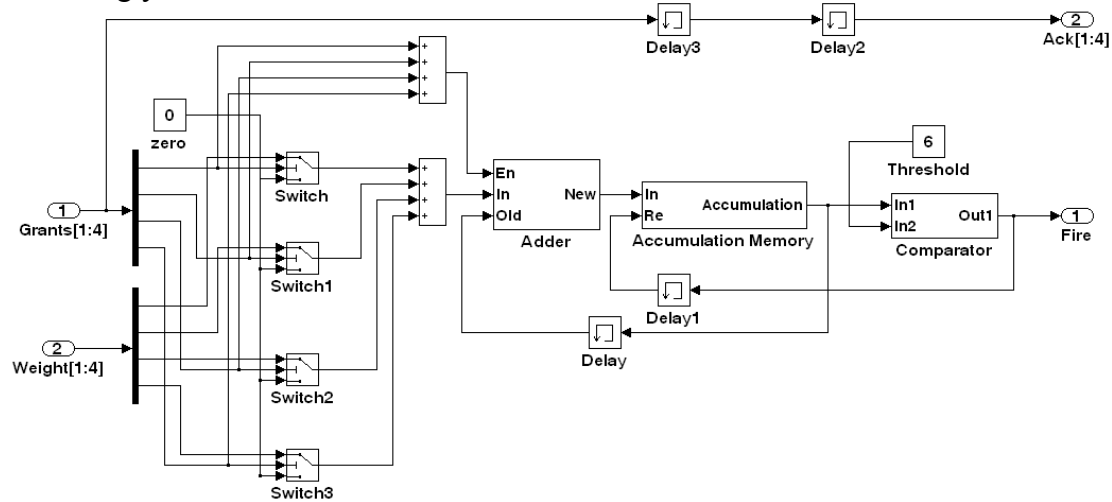


Figure 7: The Design of the Trigger Unit in Simulink

The simulation result of the PM part is given in Figure 8. The validation of Ready3 (as the 3rd signal of Ready[1:4]) will disable Enable3 (as the enable signal for Ready3) so

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transition in the corresponding CPN model, which focuses on loading the ID number of the new task to the IP core.

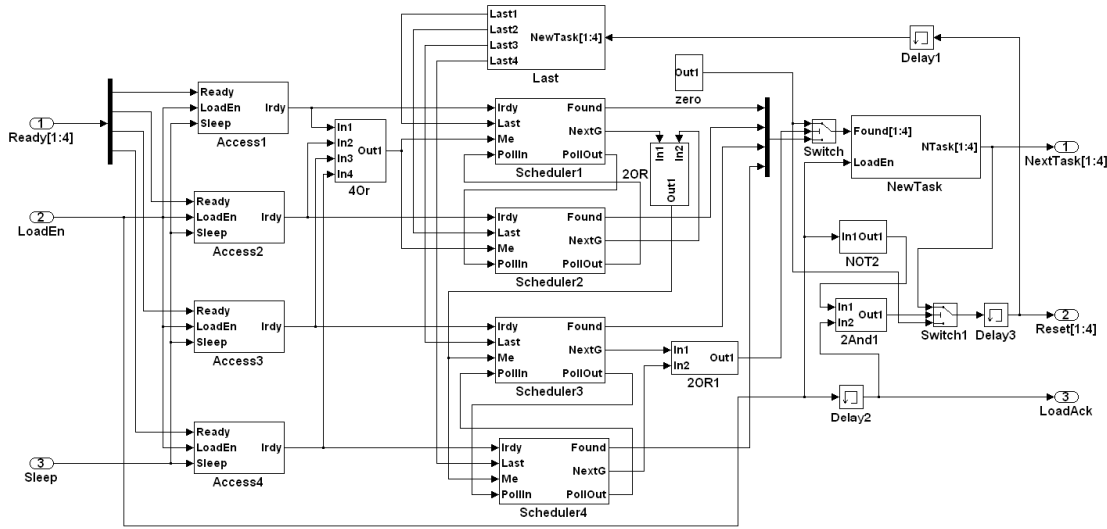


Figure 9: The Design of Power Manager in MATLAB

Because of the complexity of the scheduler part, the simulation result is given in Figure 10 and Figure 11 separately. In Figure 10, Ready3 and Ready4 represent the 3rd and 4th ready signals in Ready[1:4]. When Ready3 becomes valid, Found3 (the Found output signal of the 3rd Scheduler block) keeps invalid because no scheduling is forbidden when the IP core is sleeping (1).

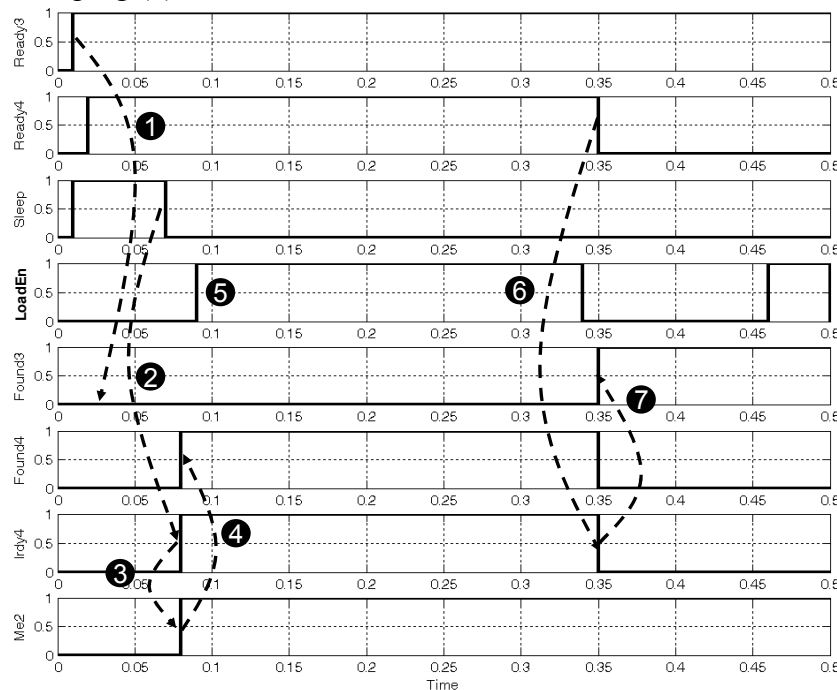


Figure 10: The Simulation Result of the TM Part

When the sleep signal becomes invalid, both Irddy3 and Irddy4 (as the output signals of the 3rd and 4th Access block respectively) signals are enabled by their corresponding ready signals (2). The Me2 signal is the input signal for both Scheduler3 and Scheduler4 blocks in their 3rd input port. The validation of this signal indicates neither task1 nor task2 is

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ready for execution. And this signal will enable Found4 (as Found output signal in the 4th Scheduler Block) since Task3 is initially set as the last task (4). The scheduling result will be loaded to the address bus and send to the IP core when the LoadEn signal becomes valid (5) and the detail of task loading will be introduced in Figure 11. The loading of the new task will also reset the corresponding ready signal in the EH part (which is introduced in Section 3.1). When Ready4 becomes invalid, the Irdy4 becomes invalid accordingly (6). Therefore Found3 becomes valid since Ready3 is the only valid ready signal at this time (7).

Figure 11 focuses on executions in the TM part during the task loading processing. After the scheduling result is achieved (1), NTask4, as the 4th signal of NewTask[1:4], becomes 1 when the LoadEn signal becomes valid (2). The LoadEn signal will be withdrawn when task4 has been carried out in the IP core. The withdrawal of this signal will update the record of last task in every priority group. In current case, Last4 becomes valid and Last3 becomes invalid at the same time because task4 is carried in the IP core (3). The withdrawal of LoadEn will also trigger the Reset signal to update the record in the Event Handler. In current case, a pulse of Reset4, as the 4th signal of Reset[1:4] is generated (4) to clean the Stim&Wait bits in Node 13 to Node 16 of the EH part in Figure 4. This reset operation will make Ready4 in Figure 10 invalid, and the change in ready signals triggers another scheduling which choose task3 as the new candidate for IP core's execution (5). And this task will be chosen as the new task to the IP core when the next valid LoadEn signal is issued (6).

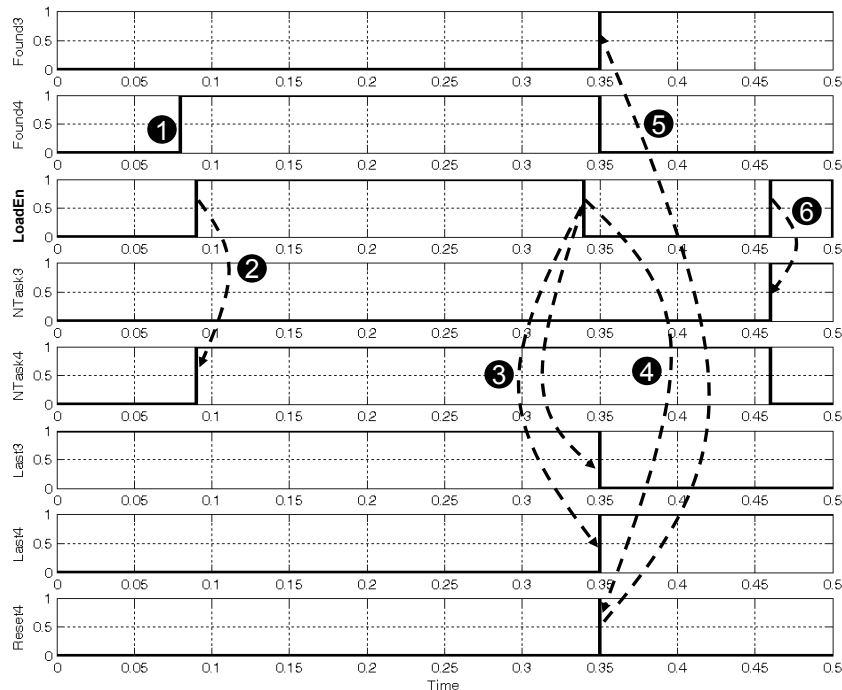


Figure 11: The Simulation Result of Task Management (2)

3.4 The Design of Interface

Figure 12 is about the design of Interface part in MATLAB. The explanation of the execution in this part can be found in the corresponding CPN model in Figure 12 in [4] for detail.

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The simulation result in this part is given in Figure 13. The validation of the Fire signal from the A&F part will enable the wakeup signal to the IP core, given the IP core is sleeping (1). Although the sleep signal from the IP core cannot be toggled because the wakeup processing in the IP core just begins, the STEPSleep signal becomes 0 without delay (2). This signal will disable the execution in the A&F part and enable scheduling in the scheduler part, therefore the scheduling can be completed before the IP core completes its wakeup processing. A LoadEn signal is issued afterwards (3). Tasks, as the 4th row in Figure 13, is the output of the 4OR block which is connected with NewTask[1:4]. Therefore, when signal Tasks is 1, it means a non-zero task ID number is loaded in the NewTask[1:4] (4).

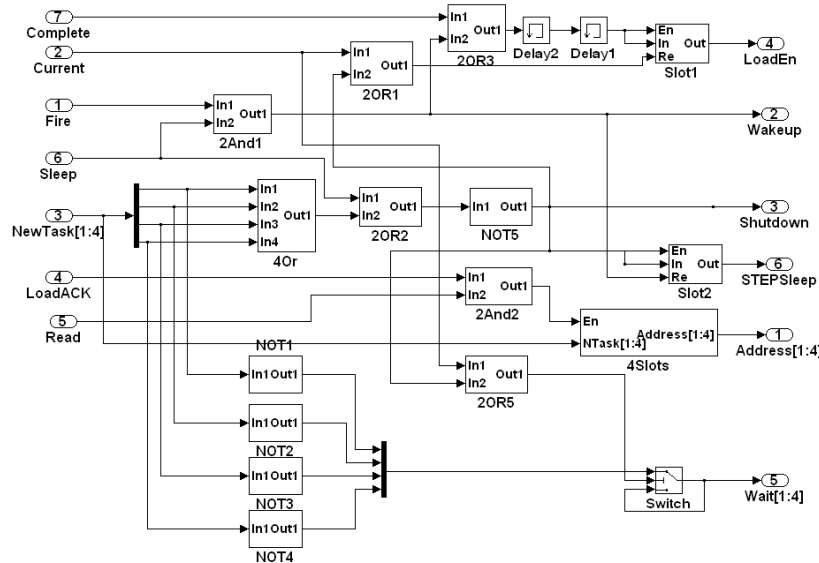


Figure 12: The Design of Interface Part in Simulink

When the wakeup processing in the IP core is completed, the sleep signal becomes 0, and a Read signal is generated accordingly (5) which will read the ID number of the new task chosen from the STEP to the IP core. If the IP core starts execution the corresponding task, the Current signal becomes valid (6), which will withdraw the LoadEn signal (7). The following pulses in the Read signal are generated during the execution of the current task in the IP core. When the current task is completed, the output control unit, which will be introduced later in Figure 14 will decide which VSB will control the ball movement corresponding to the current task. After the decision is made, a complete signal will be issued, and this signal will trigger the issuing of another LoadEn signal (8). According to Figure 2, both task3 and task4 can only be enabled once in VSB I because their corresponding balls will move outside of playground I after one step. Therefore, the 3rd valid LoadEn signal cannot find any valid task ID number from the scheduler (9). In this case, a Shutdown signal will be issued to IP core to start the shutdown processing (10). At the same time, the STEPSleep signal becomes 1 to start operations in the A&F part and disable operations in the scheduler part (11). However, the fire signal will only wakeup the IP core again when the shutdown processing in the IP core is completed (12).

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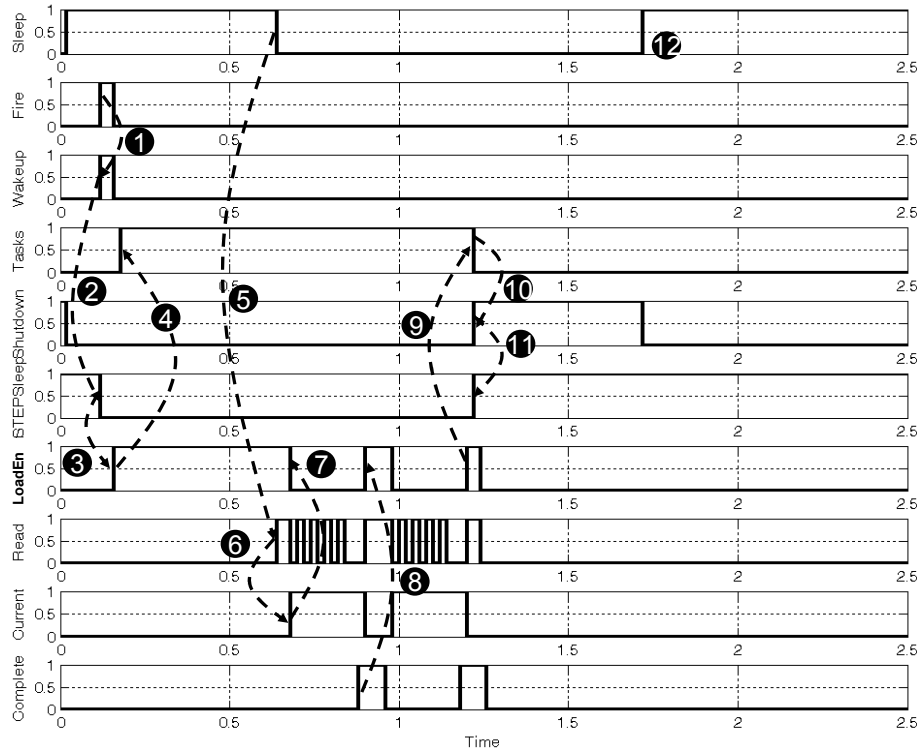


Figure 13: The Simulation Result of the Interface Part

3.5 The Design of Output Control

Figure 14 is the design of the Output Control part in MATLAB Simulink. When the current new position of one ball is calculated, its parameters will be loaded in the data bus to be transferred to the ACM (which will be introduced in Section 4 for detail). Therefore, the DeMux block is used to derive the PosX and PosY information from the data bus. Two comparators are used to calculate which VSB will take charge of the ball whose parameters are given in the data bus. When the decision is made, the ID number of the ball (also the ID number of the corresponding task) in the Address[1:4] port will be sent to the corresponding Output Channel (Ochi[1:4], $i=0,1,2,3$ and Och0[1:4] is the feedback channel). At the same time, a Complete signal will be issued to the Interface part to enable the next task loading.

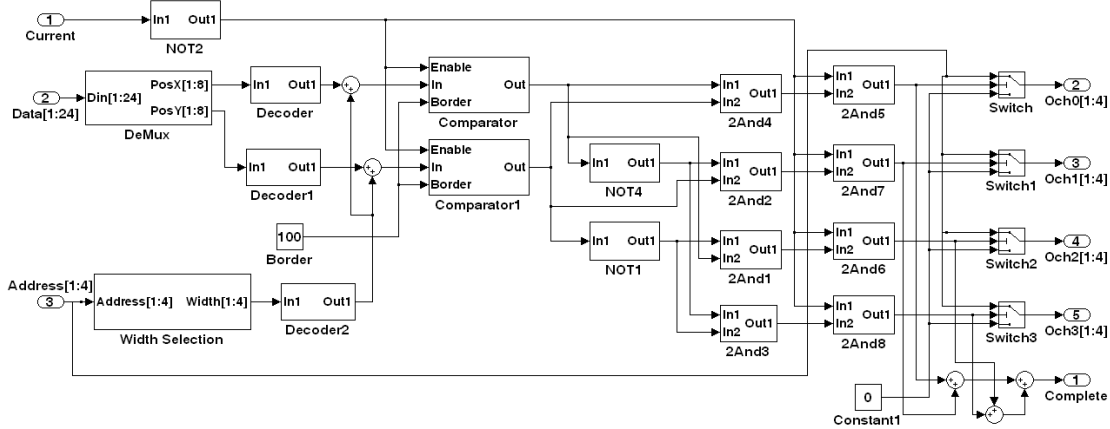


Figure 14: The Design of Output Control Part in Simulink

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Figure 15 is about the simulation result of this part. The Enable signal is the signal in the first input port of both Comparator and Comparator1 blocks. EdgeX and EdgeY is the X and Y position of the upper right edge of the current ball which is calculated in Comparator and Comparator1 blocks. When the Enable signal becomes 1, the two position parameters are used to decide which VSB will control the current ball (1).

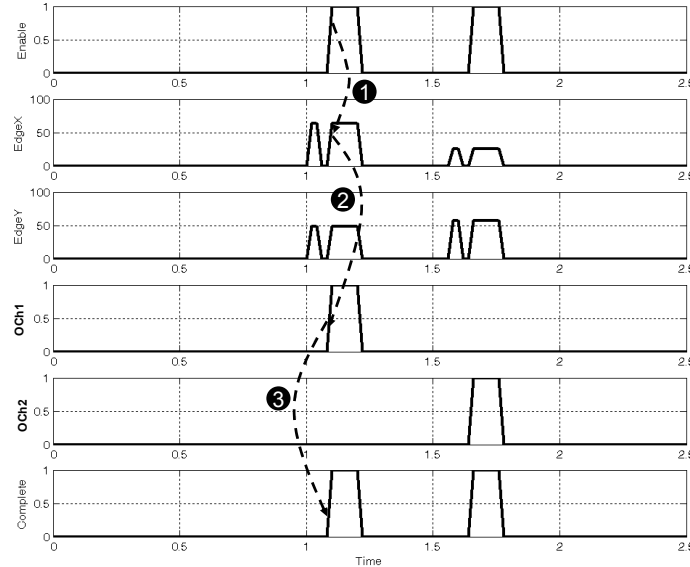


Figure 15: The Simulation Result of the Output Control Part

Och1 in Figure 15 is the output signal of block *2And2* in Figure 14. The validation of this signal indicates the current task will be sent out as an event from output channel 1 (2). At the same time, the Complete signal becomes valid (1) to enable the Interface part to start another task loading.

4. IP CORE DESIGN IN MATLAB SIMULINK

Figure 16 is about the design of the IP Core part in MATLAB Simulink. Two subsystem blocks contains in this part. One is called *OS* which will take charge of wakeup/shutdown the IP core according to the commands from the corresponding STEP. And it will load new task ID number from the STEP. The block of *Tasks* is the combination of four embedded tasks which is shown in Figure 17.

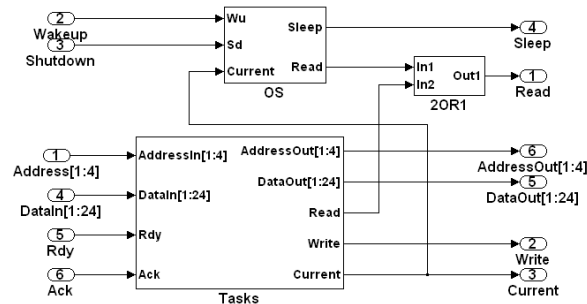


Figure 16: The Design of IP Core in Simulink

As introduced before, since we only care about the function of the IP core, five S-functions are used in this part to realize both the OS block as well as the four tasks embedded in this IP core. In Figure 17, four blocks *Input_i* ($i=1,2,3,4$) create input vectors u for each task S-function. And similarly the four blocks *Output_i* ($i=1,2,3,4$) get output

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vectors y from each task and turn them into signals that can be used in the other parts of the MATLAB model. The four S-Function blocks name as Task i ($i=1,2,3,4$) are the embedded codes for each task.

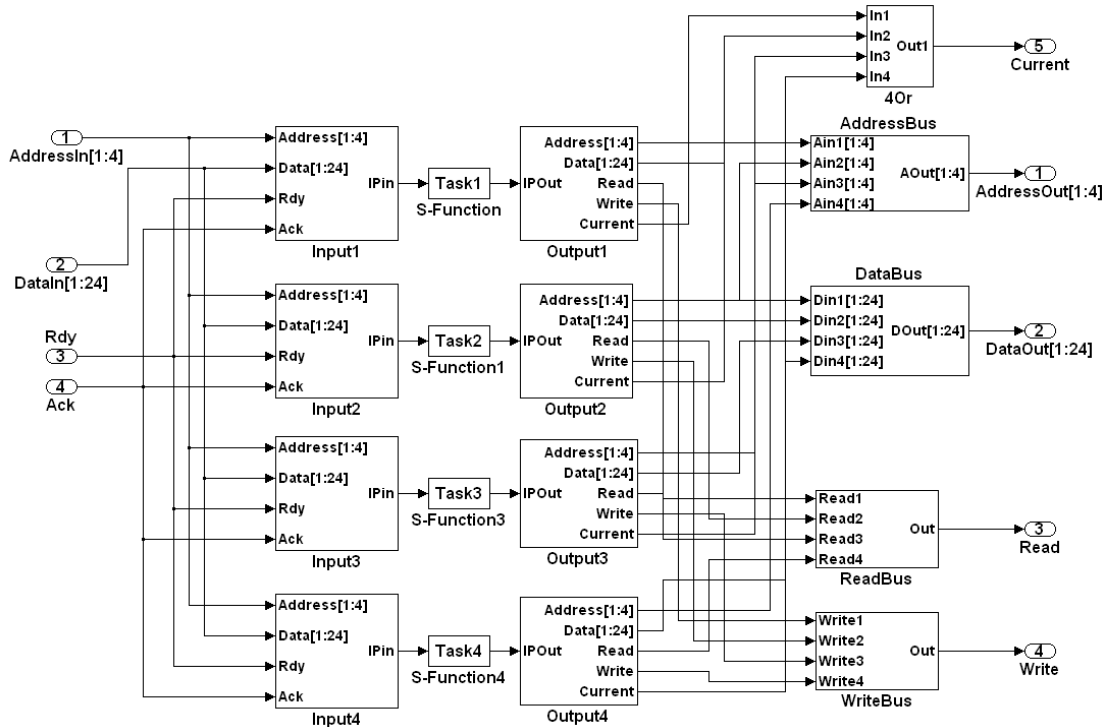


Figure 17: The Design of Task Subsystem Blocks in Simulink

4.1 Flow chart of the S-Function of OS

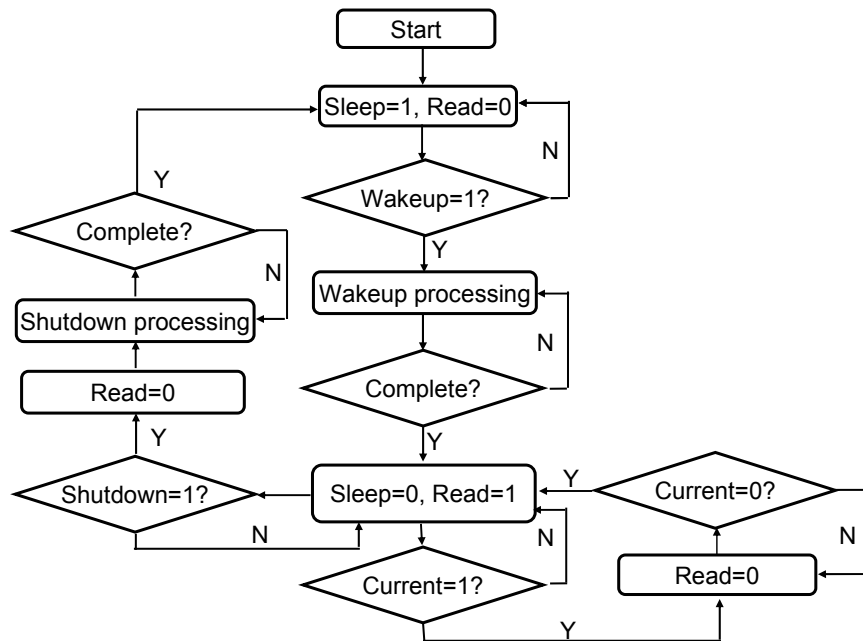


Figure 18: The Flow Chart of the OS Program

Erreur ! Source du renvoi introuvable. provides the flow chart of the S-function code for the OS program for VSB I. Initially when the program start, we suppose the IP core is

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sleeping. Therefore, variables *Sleep* and *Read* in the output vector are set to 1 and 0 respectively. When the *Wakeup* signal from the input vector becomes 1, the OS starts the wakeup processing. When the wakeup processing is completed, the *Sleep* signal is set to 0 so as to indicate the STEP that the IP core is ready for task processing. And the *Read* signal is set to 1 so as to read new task from the STEP. If the IP core begins executing the new task, the *Current* signal in the input vector will become 1, and it will set the *Read* signal in the output vector to 0.

When the *Current* signal becomes 0, it means the current task is completed, and the *Read* signal is set to 1 again to read new task from the STEP. This loop may continue several times before the shutdown signal from the input vector is captured. In this case, the *Read* signal will be first set to 0 since no new task will be read from the STEP, and the shutdown processing begins. When the shutdown processing is completed, the *Sleep* signal will be reset to 1 and the IP core starts sleeping until it is activated again.

4.2 Flow chart of the S-Function of TASK4

Figure 19 is about the flow chart of the S-function code for task4 (since all task codes are similar). The program starts when its ID number (for task4, [0 0 0 1]) is loaded in the address bus. Signal *Current* in the output vector will be set to 1 so as to indicate the OS to withdraw the *Read* signal. The first step of the task execution is to load parameter data of all four balls from the ACM, which is carried out by the function *DataLoad*. With parameters of the previous position of Ball4, task4 can calculate the next position of the ball by the function *NextPosition*. This function will let the ball to move one step (the size of the step is determined by the speed parameter) to the direction specified by the *History* parameter.

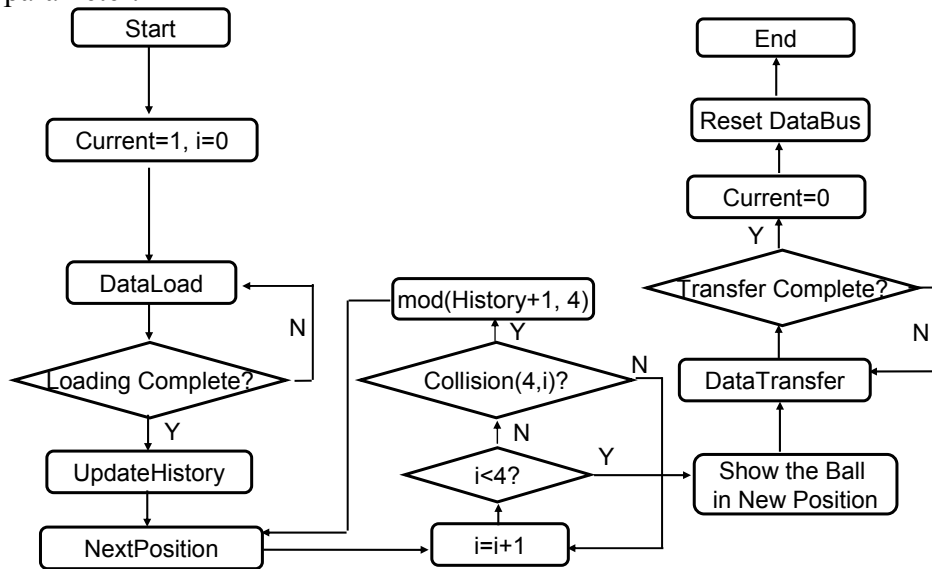


Figure 19: The Flow Chart of the Task4 Program

Therefore, if the history parameter loaded from the ACM is used directly in the *NextPosition* function, the new position calculated is totally determined by the current position (unless Ball4 is knocked back by the wall of playground or collides with other balls which will be discussed later). The *UpdateHistory* function (Figure 20) is used to introduce some degree of nondeterministic to the ball moving.

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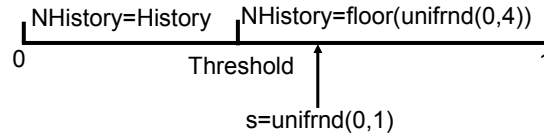


Figure 20: The Function of UpdateHistory

This function uses MATLAB command *unifrnd* to generate a random number from 0 to 1 which follows uniform distribution. If the random number is less than some Threshold ($0 \leq \text{Threshold} \leq 1$), Task4 will use the history parameter loaded from the ACM to generate the new ball position. Otherwise, a random integer number will be used to generate the new ball position. Therefore, the bigger the Threshold value is, the more deterministic the ball movement becomes. Otherwise, the ball movement becomes more random. Different Threshold will be used for the analysis achieved in Section 5.

The loading of parameters for Ball4 from ACM is used for new position calculation, and the loading of parameters of other three balls are used to check if the new position calculated by the NextPosition function can have any collision with others. Function *Collision* takes charge of the collision detection and Figure 21 indicates the mechanism used by this function. The variable *Dis_Centres* calculate the distance between two balls' centre. If *Width1* and *Width2* represent the width of the two balls separately, ball collision happens when $\text{Dis_Centres}^2 < 2\left(\frac{\text{Width1} + \text{Width2}}{2}\right)^2$.

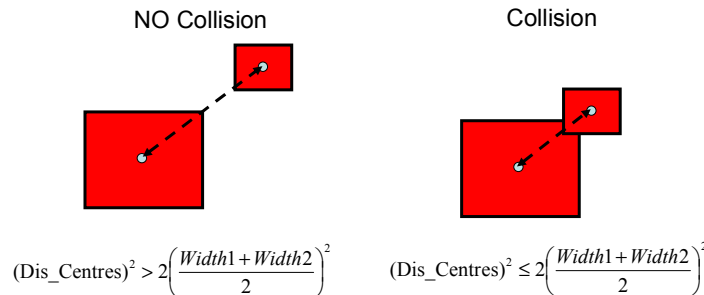


Figure 21: The Calculation of Collision

Therefore in Figure 19, when the new position of ball4 is calculated, the program will check if it has collision with other three balls in sequence (*i* in Figure 19 represents the ball's ID number). If any collision happens, the program will change the history parameter and re-calculate the new position of Ball4 until no collision is found. After collision detection, the program can safely show the ball in the new position, and then transfer the parameters of Ball4 to the ACM. This data transfer is carried out by the *DataTransfer* function. When the data transfer is completed, the task4 program reset the Current signal to 0 so as to indicate the STEP to do output control, and the execution will be stopped after the data bus is reset.

5. POWER AND LATENCY ANALYSIS

In our simulation, the time spent for one step movement of a ball without collision is set as one time unit. Both wakeup and shutdown executions have been adjusted so that their latency cost is one time unit as well. To simplify the analysis, we assume the power dissipation for task processing is one unit and that for wakeup and shutdown is 1.5 units. Because wire latency cannot be reflected by MATLAB Simulink, the time cost in a STEP

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model cannot be compared with that in its IP core model. Therefore, the benchmark achieved in this section takes the STEP as cost free in both power and latency.

With only four VSBs in the example SOC, events incoming to every VSB cannot be taken as ideal exponential distribution. And with only four tasks embedded in every IP core, the execution in every IP core cannot be taken as ideal exponential distribution either. Therefore the example SOC test bench will be used to analyze the power efficiency achieved by A&F policy in weak Markovian environment.

Four different DPM policies have been used to control the four VSBs in different tests. The first one is greedy policy which means the threshold in the PM part is set to 1, therefore any ball incoming to a black playground will activate the corresponding IP core.

A&F policy is used in our second simulation. As the priorities of the four balls have been set as 1, 2, 3, 5 respectively, we set 5 as the threshold in every A&F part of STEP. It means the incoming of ball4 only or several other balls to a black playground can activate a sleeping IP core.

Timeout policy [6] serves as the third DPM policy in our test where we set the timeout threshold to 5 and 10 time units in two different simulations.

Prediction policy is the fourth DPM policy that is implemented in our test. In [6], a T_{BE} time is defined as the minimum time spent in sleeping to compensate the wakeup and shutdown overhead. In our case, the T_{BE} is 3 time units. Furthermore, the implementation of prediction policy needs to predict the length of next idle period according to [6]. Linear function is used in our test for idle period prediction (Equation 1).

$$T_{idle_pred}^n = 0.5 * T_{idle}^{n-1} + 0.3 * T_{idle}^{n-2} + 0.2 * T_{idle}^{n-3} \quad \text{Equation 1}$$

The prediction of the next (n^{th}) idle period depends on the latest three idle periods with reliability of 0.5, 0.3 and 0.2 respectively. For the implementation of Timeout or Prediction policy, a subsystem block of state flow is used instead of the PM part in a STEP.

To make our test have wide representation of real systems, we vary the threshold in Figure 20 from 0 to 1 in 11 independent simulations for every DPM policy's implementation. The change of this threshold from 0 to 1 indicates the variation of ball movements from pure random to mostly history based.

Figure 22 presents the average power dissipation of one IP core for various ball movements when different DPM policies have been used. The Timeout1 in the legend indicates the case when Timeout parameter τ is set to 5, and Timeout2 is the case when τ is set to 10. From this figure, it is clear that A&F policy has the most power efficiency that the other policies, no matter what movement balls take.

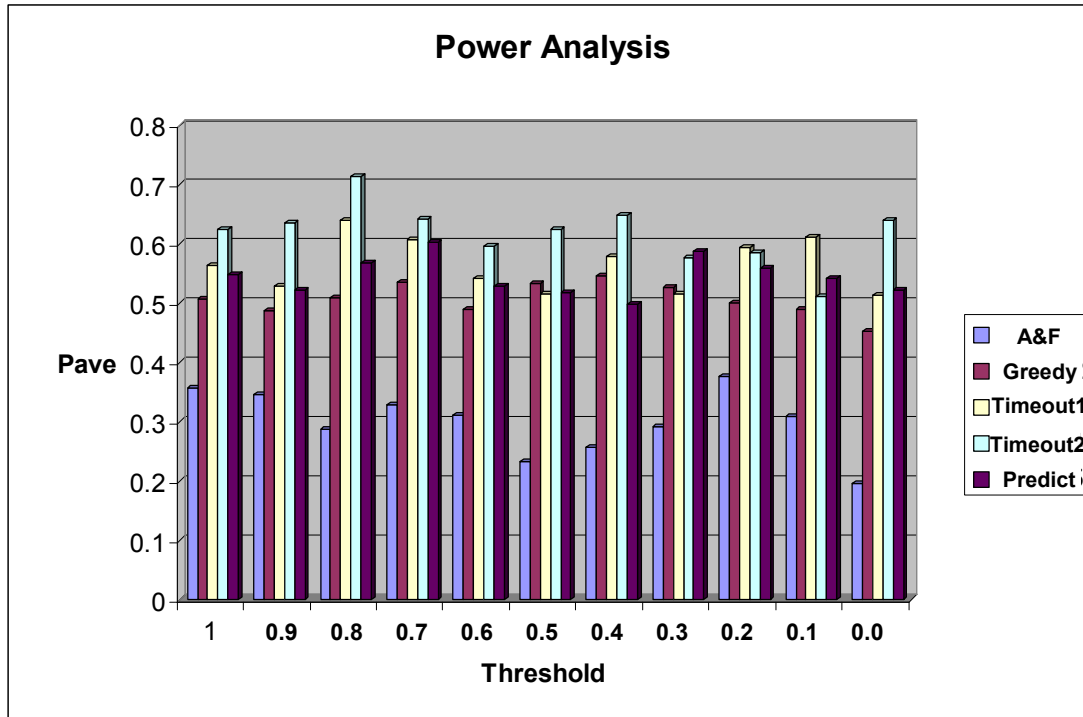


Figure 22: Power Analysis of the example SoC

Figure 23 is about the latency analysis of the test bench when A&F policy is used. If four tasks are ready in one IP core, 2 time units are needed by one task for scheduling before execution in average, and 1 time unit is needed for execution at least (suppose no collision happens). Therefore we set the deadline (DL) for every task's execution as 6 time units in our first simulation. It can be seen front the figure that A&F policy causes no more than 2.5% deadline violation in average. In most cases, this latency is acceptable. In our second simulation, the deadline is set to 8 time units to present the case when the deadline requirement is looser. It can be seen that the deadline violation becomes less accordingly.

As different priorities have been given to the four tasks, these tasks have different latency performance. Figure 24 presents the different latency performance of the four tasks when the deadline is set to 6. It can be seen that task4, who has the highest priority, has extreme low deadline violation cases. It is because no latency cost will be paid in task accumulation.

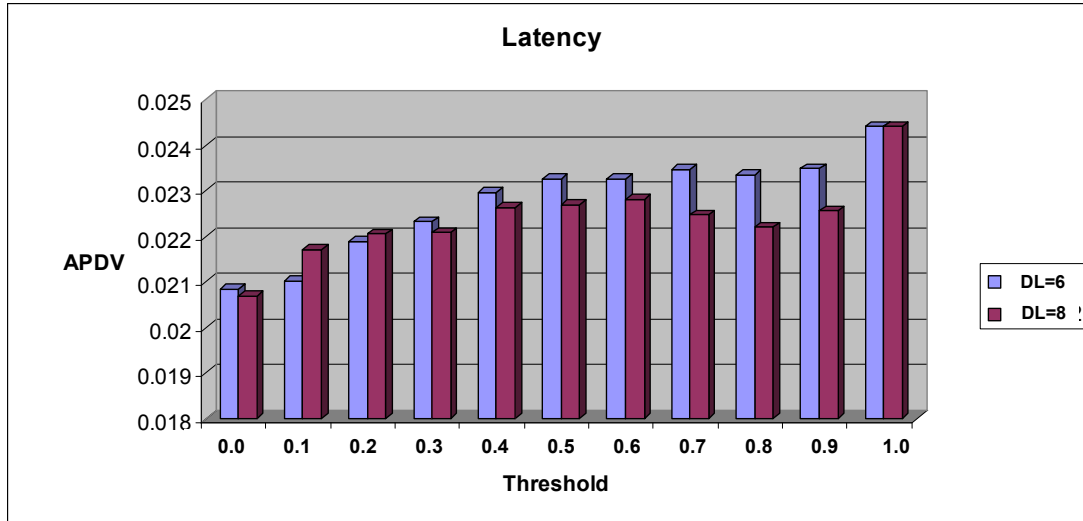


Figure 23: Latency Analysis of the example SoC

According to Figure 24, task2 and task3 have more frequent deadline violation than task1, although they have higher priority than the latter. It is mainly caused by parameters setting of these balls. According to **Erreur ! Source du renvoi introuvable.**, ball2 and ball3 have faster speed than ball1, which means ball2 or ball3 moves more frequently across different playgrounds than ball1. When ball2 or ball3 moves to a new playground whose corresponding IP core is sleeping, it needs another balls' coming to activate the IP core and much latency will be cost during task accumulation. On the other hand, ball1, which has small size and slow speed, will always move within one playground. Therefore this ball will pay less cost in accumulation latency than ball2 or ball3.

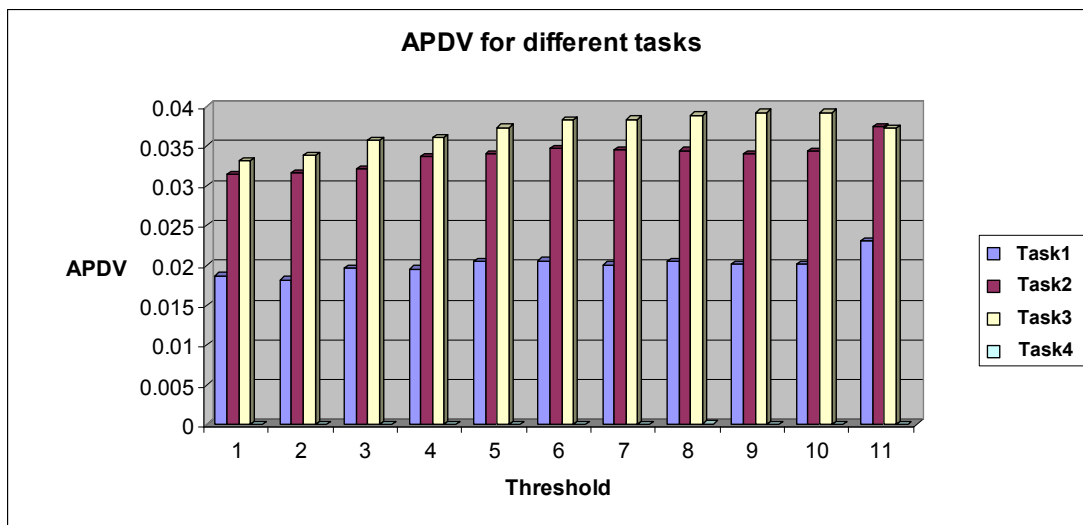


Figure 24: Latency Analysis of the example SoC (Continue)

6. CONCLUSION AND FUTURE WORK

This paper presents an example SoC which is constructed by four VSBs in MATLAB Simulink. All parts of a STEP that are modelled by CPN models in [4], have been built by basic components in Simulink Library. An example IP core with four embedded tasks

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is designed in Simulink S-function. The example SOC is used to carry out a test bench named as ball game in MATLAB simulation, and the simulation result achieved from the test bench not only proves the correctness of executions in the VSB based SOC, but also indicates the high energy efficiency of A&F policy even in a weak Markovian environment.

The STEP model has also been implemented into VLSI design flow and benchmarks will be achieved soon where the performance of the coprocessor is tested in real implementation.

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