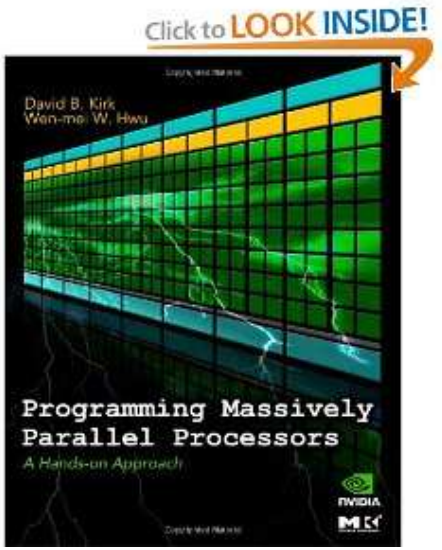
Introduction to GPU programming

Overview

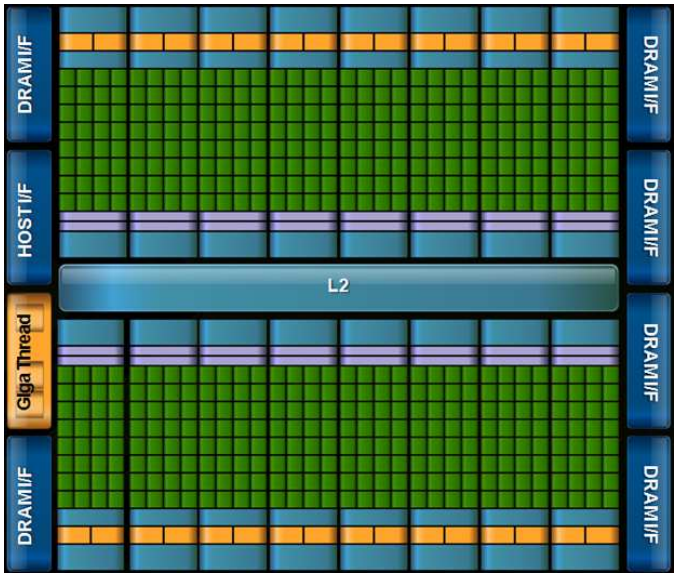
- GPUs & computing
- Principles of CUDA programming
- One good reference:
  David B. Kirk and Wen-mei W. Hwu, **Programming Massively Parallel Processors**, Morgan Kaufmann Publishers, 2010.



New trends of microprocessors

- Since 2003, there has been two main trajectories for microprocessor design
- *Multicore* – a relatively small number of cores per chip, each core is a full-flesh processor in the “traditional sense”
- *Many-core* – a large number of much smaller and simpler cores
  - NVIDIA Tesla K40 GPU has 2880 “cores” (streaming processors), each is heavily multi-threaded, in-order, single-instruction issue processor.
  - Peak performance of many-core GPUs can be 10 fold the peak performance of multicore CPUs
  - GPUs have larger memory bandwidth (simpler memory models and fewer legacy requirements)

NVIDIA's Fermi architecture



- Designed for GPU computing
- 16 streaming multiprocessors (SMs)
- 32 CUDA cores (streaming processors) in each SM (512 cores in total)
- Each streaming processor is massively threaded
- 6 DRAM 64-bit memory interfaces
- Peak double-precision floating-point rate: 768 GFLOPs

NVIDIA's Kepler architecture

- Each streaming multiprocessor is more powerful than Fermi
- Dynamic parallelism (nested kernels)
- Hyper-Q allows multiple CPU threads/processes to use a single GPU
- Peak double-precision floating-point rate of K40: 1430 GFLOPs

Massive (but simple) parallelism

- One streaming processor is the most fundamental execution resource
- Simpler than a CPU core
- But capable of executing a large number of threads simultaneously, where the threads carry out same instruction to different data elements —- single-instruction-multiple-data (SIMD)
- A number of streaming processors constitute one streaming multiprocessor (SM)

CUDA

- CUDA – Compute Unified Device Architecture
- C-based programming model for GPUs
- Introduced together with GeForce 8800
- Joint CPU/GPU execution (*host/device*)
- A CUDA program consists of one of more phases that are executed on either host or device
- User needs to manage data transfer between CPU and GPU
- A CUDA program is a unified source code encompassing both host and device code

More about CUDA

- To a CUDA programmer, the computing system consists of a host (CPU) and one or more devices (GPUs)
- Data must be explicitly copied from host to device (and back)
- On device, there is so-called *global memory*
- Device global memory tends to have long access latencies and finite bandwidth
- On-chip memories: registers and shared memory (per SM block) have limited capacity, but are much faster
- Registers are private for individual threads
- All threads with a thread block can access variables in the shared memory
- Shared memory is an efficient means for threads to cooperate, by sharing input data and intermediate results

Programming GPUs for computing (1)

- *Kernel functions* – the computational tasks on GPU
  - An application or library function may consist of one or more kernels
  - Kernels can be written in C, extended with additional keywords to express parallelism
- Once compiled, each kernel makes use of many threads that **execute the same program in parallel**
- Multiple threads are grouped into thread blocks
  - All threads in a thread block run on a single SM
  - Within a thread block, threads cooperate and share memory
  - A thread block is divided into warps of 32 threads
    - Warp is the fundamental unit of dispatch within an SM
  - Threads blocks may execute in any order

Programming GPUs for computing (2)

- When a kernel is invoked on host, a *grid* of parallel threads are generated on device
- Threads in a grid are organized in a two-level hierarchy
  - each grid consists of one or more thread blocks
  - all blocks in a grid have the same number of threads
  - each block has a unique 3D coordinate `blockIdx.x`, `blockIdx.y` and `blockIdx.z`
  - each thread block is organized as a 3D array of threads `threadIdx.x`, `threadIdx.y`, `threadIdx.z`
- The grid and thread block dimensions are set when a kernel is invoked
- A centralized scheduler

Programming GPUs for computing (3)

- Syntax for invoking a kernel

```
dim3 dimGrid(64,32,1)
dim3 dimBlock(4,2,2);
KernelFunction<<<dimGrid, dimBlock>>>(...);
```

- `gridDim` and `blockDim` contain the dimension info
- All threads in a block share the same `blockIdx`
- Each thread has its unique `threadIdx` within a block
- Values of `blockIdx` and `threadIdx` can be used to determine which data element(s) that a thread is to work on
- Often, one thread is used to compute one data element (fine-grain parallelism)

Thread execution

- Launching a CUDA kernel will generate a 1D or 2D or 3D array of thread blocks, each having a 1D or 2D or 3D array of threads
- The thread blocks can execute in any order relative to each other
- CUDA runtime system bundles several threads for simultaneous execution, by partitioning each thread block into *warps* (32 threads)
- Scheduling of warps is taken care by CUDA runtime system
- The hardware executes same instruction for all threads in the same warp
- If-tests can cause thread divergence, which will require multiple passes of divergent paths (involving all threads of a warp)

Simple example of CUDA program

Use GPU to calculate the square each element of an array

```
// Kernel that executes on the CUDA device
__global__ void square_array(float *a, int N)
{
  // 1D thread blocks and 1D thread array inside each block
  // N is the length of the data array a, stored in device memory

  int idx = blockIdx.x * blockDim.x + threadIdx.x;
  if (idx<N) a[idx] = a[idx] * a[idx];
}
```

Simple example of CUDA program (cont'd)

```
// main routine that executes on the CPU host
int main(void)
{
  float *a_h, *a_d;  // Pointer to host & device arrays
  const int N = 10;  // Number of elements in arrays
  size_t size = N * sizeof(float);
  a_h = (float *)malloc(size);        // Allocate array on host
  cudaMalloc((void **) &a_d, size);   // Allocate array on device
  // Initialize host array and copy it to CUDA device
  for (int i=0; i<N; i++) a_h[i] = (float)i;
  cudaMemcpy(a_d, a_h, size, cudaMemcpyHostToDevice);
  // Do calculation on device:
  int block_size = 4;
  int n_blocks = N/block_size + (N%block_size == 0 ? 0:1);
  square_array <<< n_blocks, block_size >>> (a_d, N);
  // Retrieve result from device and store it in host array
  cudaMemcpy(a_h, a_d, sizeof(float)*N, cudaMemcpyDeviceToHost);
  // Print results
  for (int i=0; i<N; i++) printf("%d %f\n", i, a_h[i]);
  // Cleanup
  free(a_h); cudaFree(a_d);
}
```

Matrix multiplication, example 1

- We want to compute $Q = M \times N$, assuming Q, M, N are all square matrices of same size `Width×Width`
- Each matrix has a 1D contiguous data storage
- Naive kernel implementation

```
__global__ void MatrixMulKernel(float* Md, float* Nd, float* Qd,
                                int Width)
{
  int Row = blockIdx.y*TILE_WIDTH + threadIdx.y;
  int Col = blockIdx.x*TILE_WIDTH + threadIdx.x;
  float Qvalue = 0;
  for (int k=0; k<Width; ++k)
    Qvalue += Md[Row*Width+k] * Nd[k*Width+Col];
  Qd[Row*Width+Col] = Qvalue;
}
```

Matrix multiplication, example 2

- The previous implementation is not memory efficient
- Each thread reads $2 \times$`Width` values from global memory
- A better approach is to let a patch of `TILE_WIDTH`$\times$`TILE_WIDTH` threads share the $2 \times$`TILE_WIDTH`$\times$`Width` data reads
- That is, each thread reads $2 \times$`Width`/`TILE_WIDTH` values from global memory
- Shared memory is important for performance!
- Also beware that size of shared memory is limited

Matrix multiplication, example 2 (cont'd)

```
__global__ void MatrixMulKernel(float* Md, float* Nd, float* Qd,
                                int Width)
{
  __shared__ float Mds[TILE_WIDTH][TILE_WIDTH];
  __shared__ float Nds[TILE_WIDTH][TILE_WIDTH];

  int bx = blockIdx.x;  int by = blockIdx.y;
  int tx = threadIdx.x; int ty = threadIdx.y;
  int Row = by * TILE_WIDTH + ty;
  int Col = bx * TILE_WIDTH + tx;

  float Qvalue = 0;
  for (int m = 0; m<Width/TILE_WIDTH; ++m) {
    Mds[ty][tx] = Md[Row*Width + (m*TILE_WIDTH + tx)];
    Nds[ty][tx] = Nd[(m*TILE_WIDTH + ty)*Width + Col];
    __syncthreads();

    for (int k=0; k<TILE_WIDTH; ++k)
      Qvalue += Mds[ty][k] * Nds[k][tx];
    __syncthreads();
  }

  Qd[Row*Width+Col] = Qvalue;
}
```