Drawbacks of single cycle implementation

- All instructions take the same time although
  - some instructions are longer than others;
    - e.g. load is longer than add since it has to access data memory in addition to all the other steps that add does
  - thus the "cycle" has to be for the "longest path"
- Some combinational units must be replicated since used in the same cycle
  - e.g., ALU for computing branch address and ALU for computing branch outcome
    - but this is no big deal (these duplicate resources will be needed when we will pipeline instructions)

Alternative to single cycle

- Have a shorter cycle and instructions execute in multiple (shorter) cycles
- The (shorter) cycle time determined by the longest delay in individual functional units (e.g., memory or ALU etc.)
- Possibility to streamline some resources since they will be used at different cycles
- Since there is need to keep information "between cycles", we'll need to add some stable storage (registers) not visible at the ISA level
- Not all instructions will require the same number of cycles

Multiple cycle implementation

- Follows the decomposition of the steps for the execution of instructions
  - Cycle 1. Instruction fetch and increment PC
  - Cycle 2. Instruction decode and read source registers and branch address computation
  - Cycle 3. ALU execution or memory address calculation or set PC if branch successful
  - Cycle 4. Memory access (load/store) or write register (arith/log)
  - Cycle 5 Write register (load)
- Note that branch takes 3 cycles, load takes 5 cycles, all others take 4 cycles

Instruction fetch

- Because fields in the instruction are needed at different cycles, the instruction has to be kept in stable storage, namely need to introduce an *Instruction Register* (IR)
- The register transfer level actions during this step

  IR ← Memory[PC]

  PC ← PC + 4
- Resources required
  - Memory (but no need to distinguish between instruction and data memories; later on we will because the need will reappear when we pipeline instructions)
  - Adder to increment PC
  - IR

Instruction decode and read source registers

- Instruction decode: send opcode to control unit and…(see later)
- Perform "optimistic" computations that are not harmful
  - Read rs and rt and store them in *non-ISA visible registers* A and B that will be used as input to ALU

  A ← REG[IR[25:21]] (read rs)

  B ← REG[IR[20:16]] (read rt)

  - Compute the branch address just in case we had a branch!

  ALUout ← PC +(sign-ext(IR[15:0]) *4 (ALUout is also a *non-ISA visible register*)
- New resources
  - A, B, ALUout

ALU execution

- If instruction is R-type

  ALUout ←A op. B

- If instruction is Immediate

  ALUout ←A op. sign-extend(IR[15:0])

- If instruction is Load/Store

  ALUout ← A + sign-extend(IR[15:0])

- If instruction is branch

  If (A=B) then PC ← ALUout (note this is the ALUout computed in the previous cycle)

- No new resources

Memory access or ALU completion

- If Load

  MDR ← Memory[ALUout] (MDR is the *Memory Data Register* non-ISA visible register)
- If Store

  Memory[ALUout] ← B
- If arith

  Reg[IR[15:11]] ← ALUout
- New resources
  - MDR

Load completion

- Write result register

  Reg[IR[20:16]] ← MDR

Streamlining of resources (cf. Figure 5.26)

- Comparing data path with that of a single cycle implementation
  - No distinction between instruction and data memory
  - Only one ALU
  - But a few more muxes and registers (IR, MDR etc.)

Control Unit for Multiple Cycle Implementation

- Control is more complex than in single cycle since:
  - Need to define control signals for each step
  - Need to know which step we are on
- Two methods for designing the control unit
  - Finite state machine and hardwired control (extension of the single cycle implementation)
  - Microprogramming (read the CD about it)

What are the control signals needed? (cf. Fig 5.27)

- Let’s look at control signals needed at each of 5 steps
- Signals needed for
  - reading/writing memory
  - reading/writing registers
  - control the various muxes
  - control the ALU (recall how it was done for single cycle implementation)

Instruction fetch

- Need to read memory
  - Choose input address (mux with signal *IorD = 0*)
  - Set *MemRead* signal
  - Set *IRwrite* signal (note that there is no write signal for MDR; Why?)
- Set sources for ALU
  - Source 1: mux set to “come from PC” (signal *ALUSrcA = 0*)
  - Source 2: mux set to “constant 4” (signal *ALUSrcB = 01)*
- Set ALU control to “+” (e.g., *ALUop = 00;* How about function bits?)

Instruction fetch (PC increment; cf. Figure 5.28)

- Set the mux to store in PC as coming from ALU (signal *PCsource = 01*)
- Set *PCwrite*
  - Note: this could be wrong if we had a branch but it will be overwritten in that case; see step 3 of branch instructions

Instruction decode and read source registers

- Read registers in A and B
  - No need for control signals. This will happen at every cycle. No problem since neither IR (giving names of the registers) nor the registers themselves are modified. When we need A and B as sources for the ALU, e.g., in step 3, the muxes will be set accordingly
- Branch target computations. Select inputs for ALU
  - Source 1: mux set to “come from PC” (signal *ALUSrcA = 0*)
  - Source 2: mux set to “come from IR, sign-extended, shifted left 2” (signal *ALUSrcB = 11*)
- Set ALU control to “+” (*ALUop = 00)*

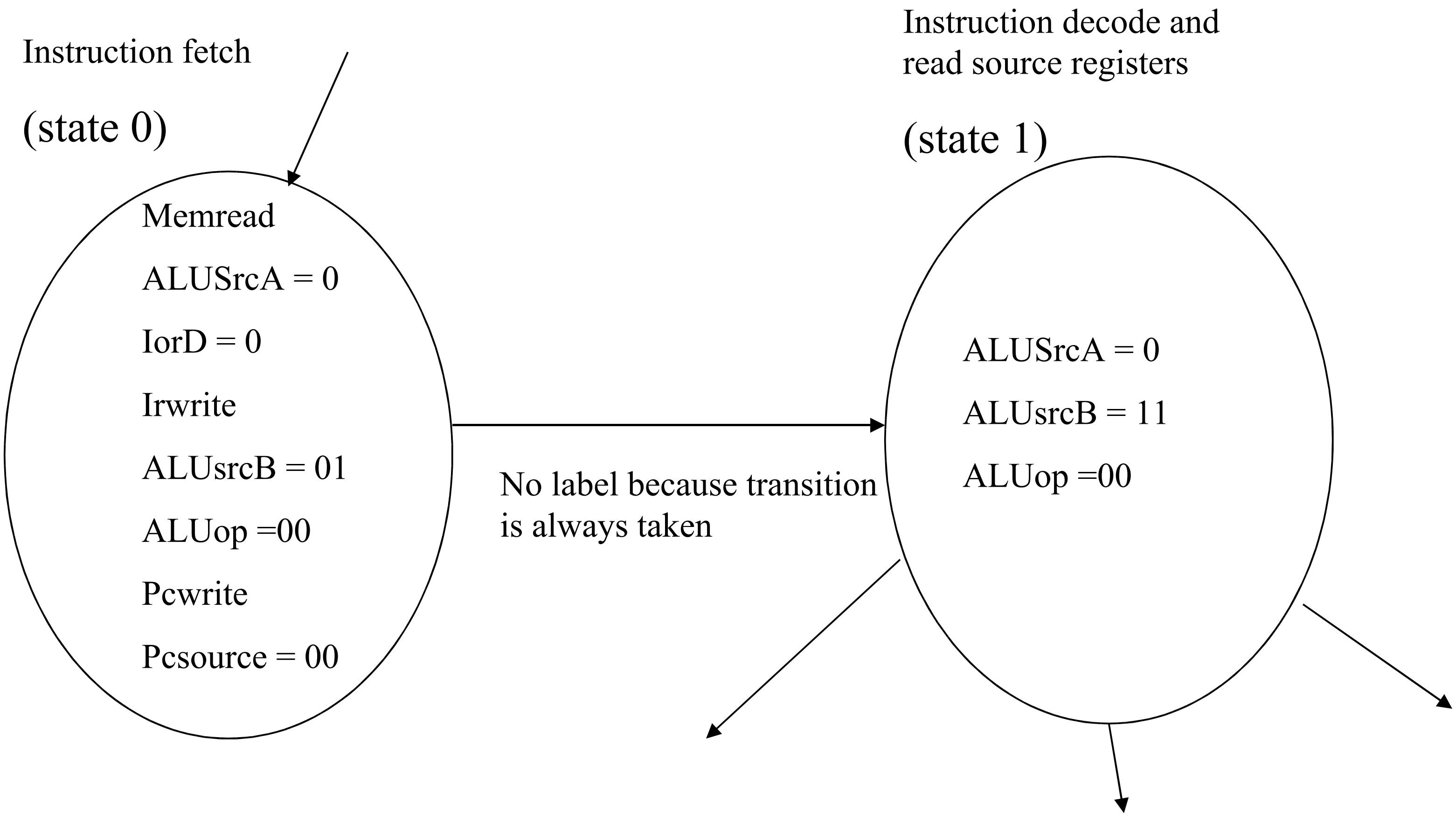
Concept of "state"

- During steps 1 and 2, all instructions do the same thing
- At step 3, opcode is directing
  - What control lines to assert (it will be different for a load, an add, a branch etc.)
  - What will be done at subsequent steps (e.g., access memory, writing a register, fetching the next instruction)
- At each cycle, the control unit is put in a specific state that depends only on the previous state and the opcode
  - (current state, opcode) → (next state) *Finite state machine* (cf. CSE370, CSE 322)

The first two states

- Since the data flow and the control signals are the same for all instructions in step 1 (instr. fetch) there is only one state associated with step 1, say *state 0*
- And since all operations in the next step are also always the same, we will have the transition
  - (state 0, all) → (state 1)

Customary notation



Instruction fetch

(state 0)

Memread

ALUSrcA = 0

IorD = 0

Irwrite

ALUsrcB = 01

ALUop =00

Pcwrite

Pcsource = 00

No label because transition is always taken

Instruction decode and read source registers

(state 1)

ALUSrcA = 0

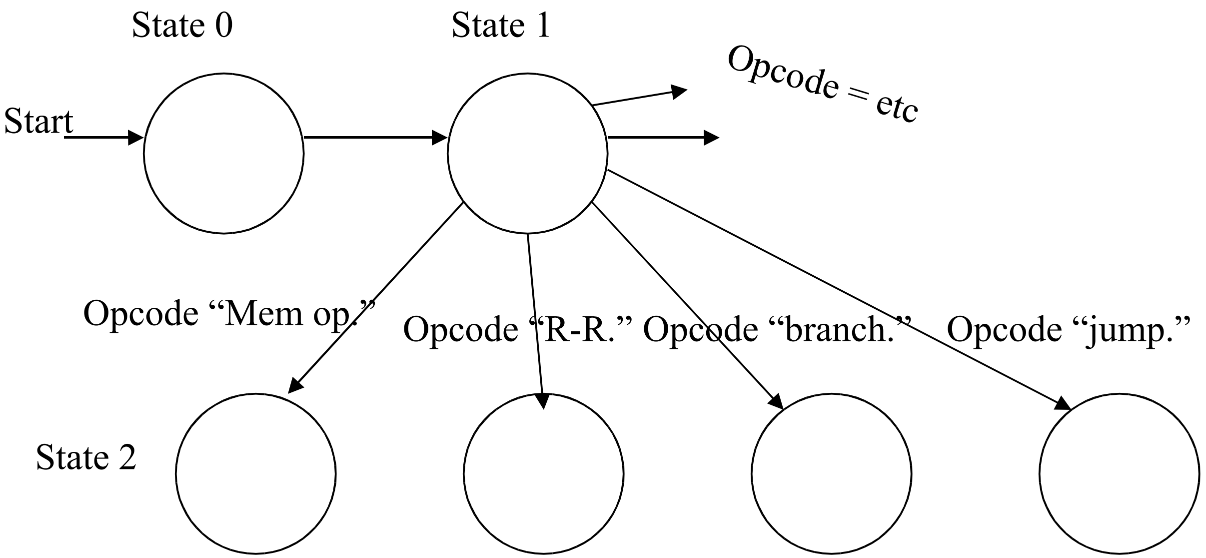
ALUsrcB = 11

ALUop =00

Transitions from State 1

- After the decode, the data flow depends on the type of instructions:
  - Register-Register : Needs to compute a result and store it
  - Load/Store: Needs to compute the address, access memory, and in the case of a load write the result register
  - Branch: test the result of the condition and, if need be, change the PC
  - Jump: need to change the PC
  - Immediate: Not shown in the figures. Do it as an exercise

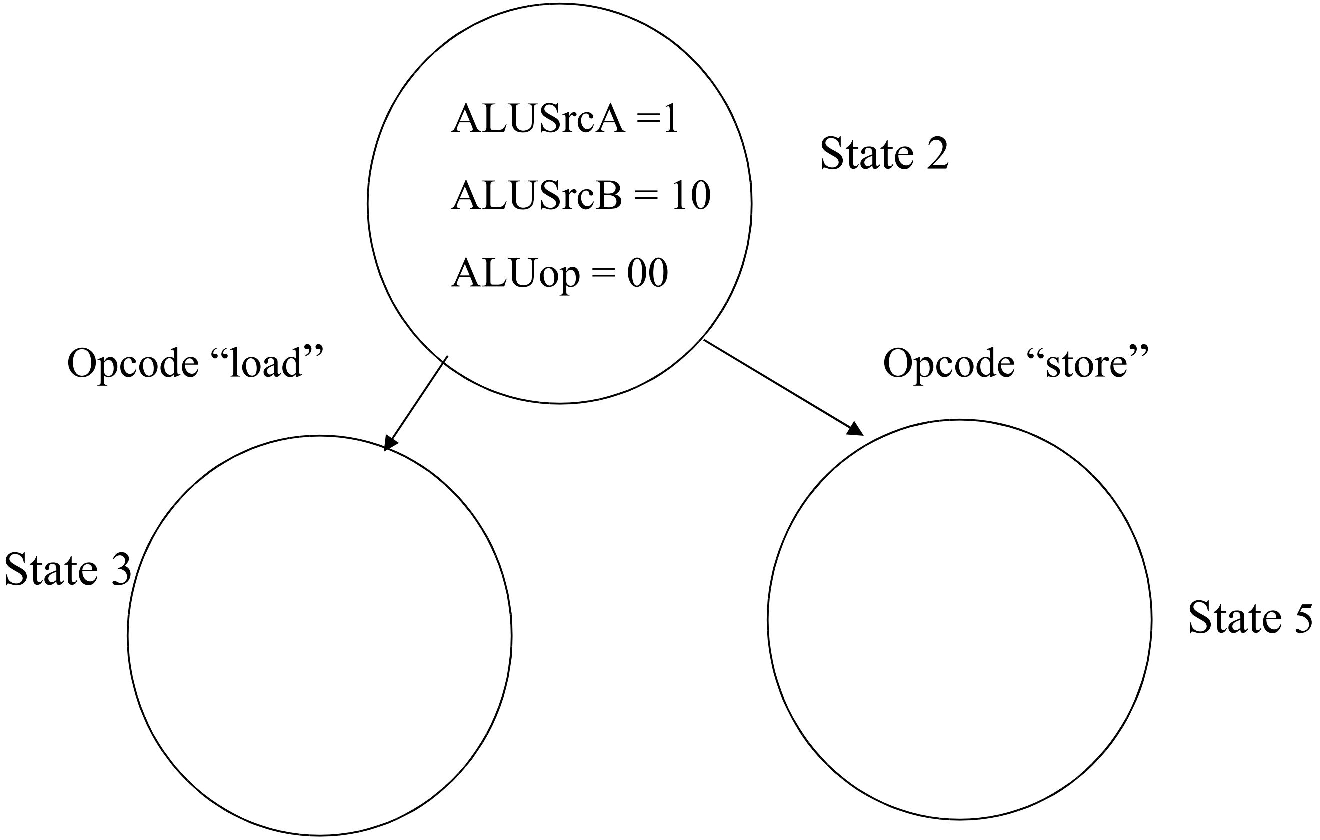
State transitions from State 1



State 2: Memory Address Computation

- Set sources for ALU
  - Source 1: mux set to “come from A” (signal *ALUSrcA = 1*)
  - Source 2: mux set to “imm. extended” (signal *ALUSrcB = 10)*
- Set ALU control to “+” (*ALUop = 00)*
- Transition from State 2
  - If we have a “load” transition to State 3
  - If we have a “store” transition to State 5

State 2: Memory address computation



ALUSrcA =1

ALUSrcB = 10

ALUop = 00

State 2

Opcode “load”

Opcode “store”

State 3

State 5

One more example: State 5 --Store

- The control signals are:
  - Set mux for address as coming from ALUout (*IorD = 1)*
  - Set *MemWrite*
  - Note that what has to be written has been sitting in B all that time (and was rewritten, unmodified, at every cycle).
- Since the instruction is completed, the transition from State 5 is always to State 0 to fetch a new instruction.
  - (State 5, always) → (State 0)

Hardwired implementation of the control unit

- Single cycle implementation:
  - Input (Opcode) ⇒ Combinational circuit (PAL) ⇒ Output signals (data path)
  - Input (Opcode + function bits) ⇒ ALU control
- Multiple cycle implementation
  - Need to implement the finite state machine
  - Input (Opcode + Current State -- stable storage) ⇒ Combinational circuit (PAL) ⇒ Output signals (data path + setting next state)
  - Input (Opcode + function bits + Current State) ⇒ ALU control

Hardwired "diagram"