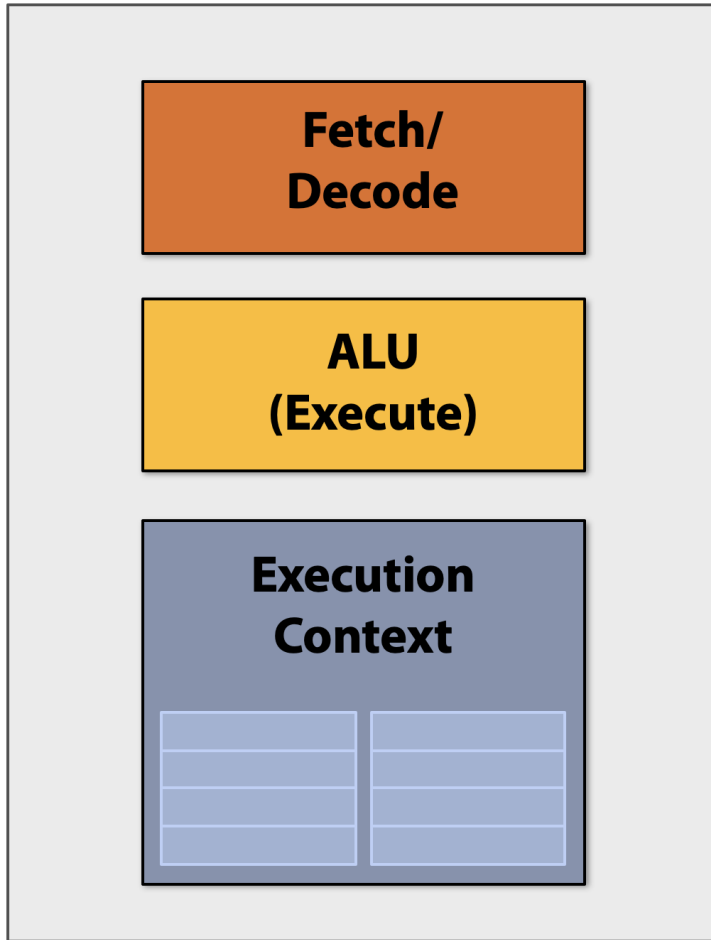


# **Lecture 5 & 6:**

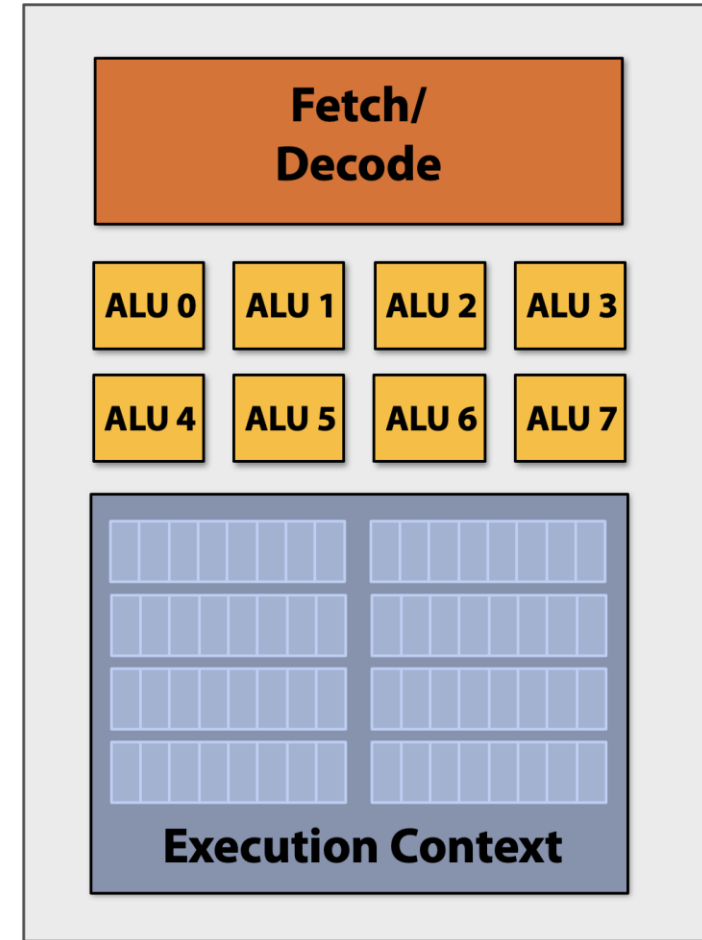
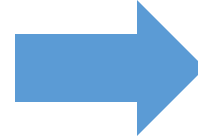
# **GPU Architecture & CUDA Programming**

**Parallel Computer Architecture and Programming**  
**CMU 15-418/15-618, Fall 2024**

# Single Instruction, Multiple Data



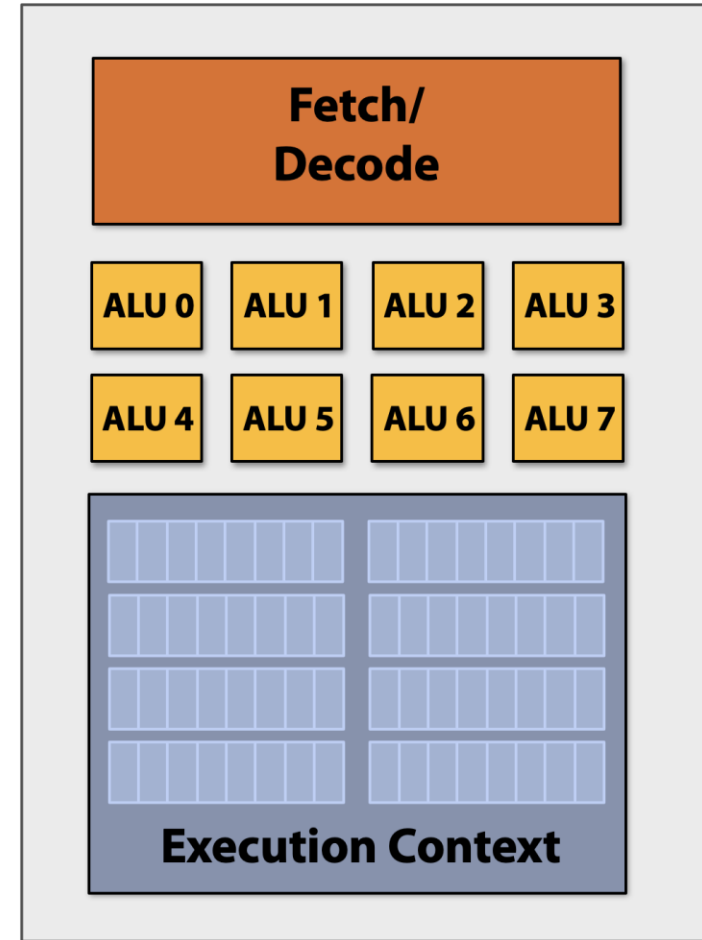
Conventional single instruction,  
**single data** processor



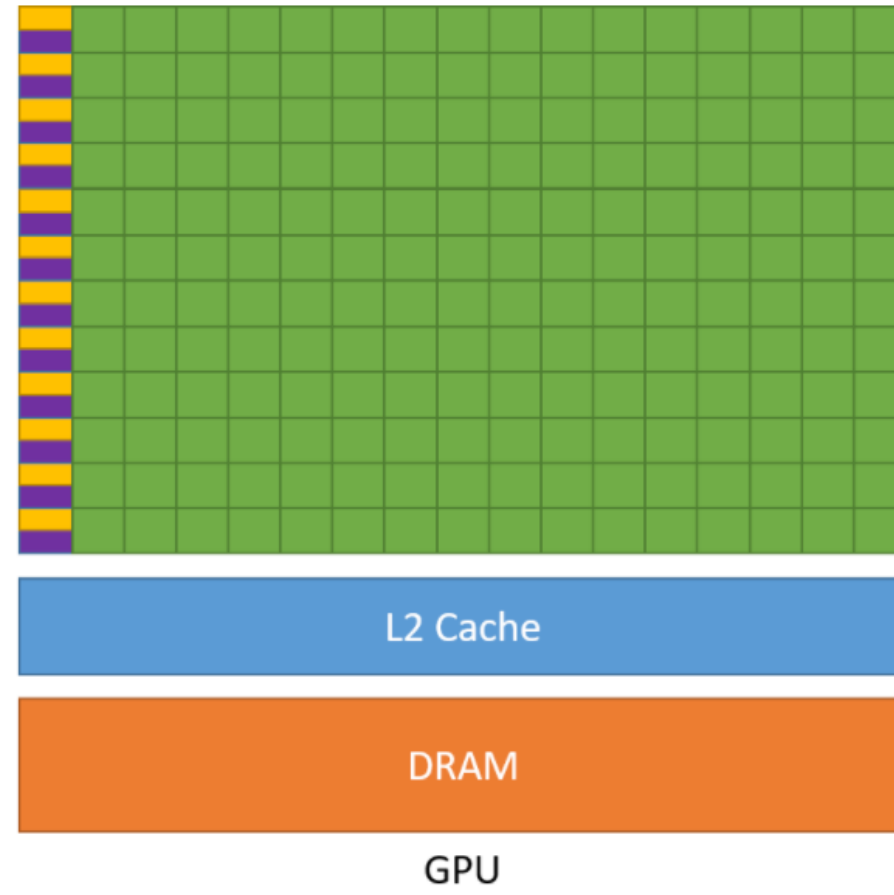
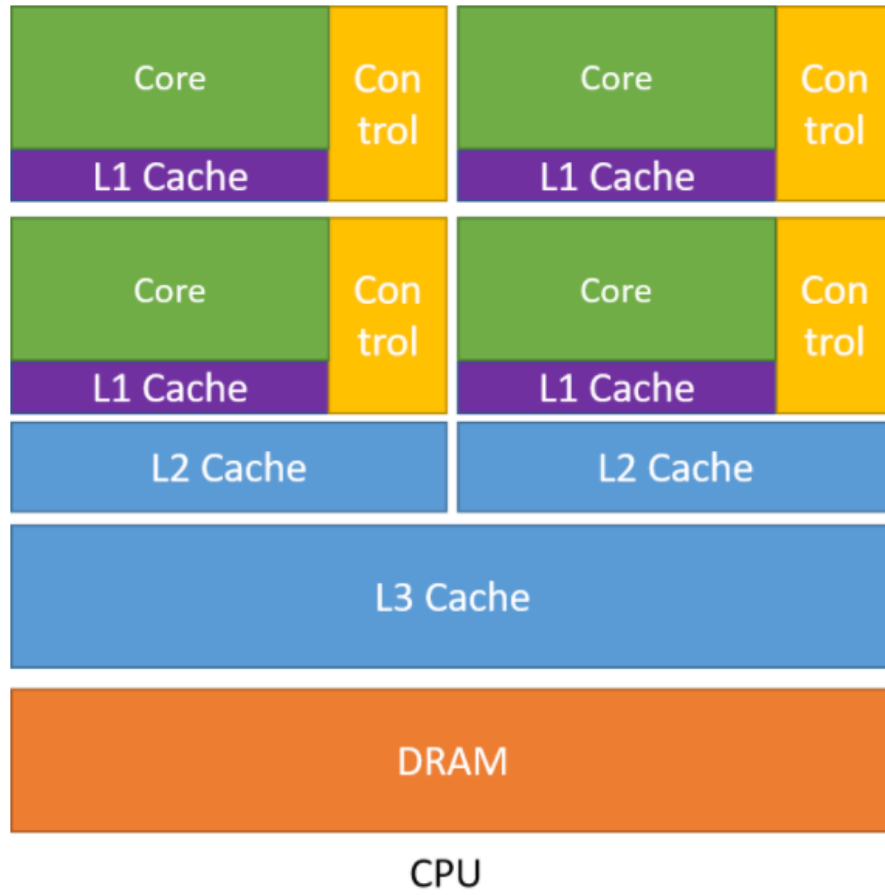
Modern single instruction,  
**multiple data** processor

# Single Instruction, Multiple Data

- Same instruction broadcast and executed in parallel on all ALUs
- Add ALUs to increase compute capability



# Massive Parallel Computing Units



# Outline

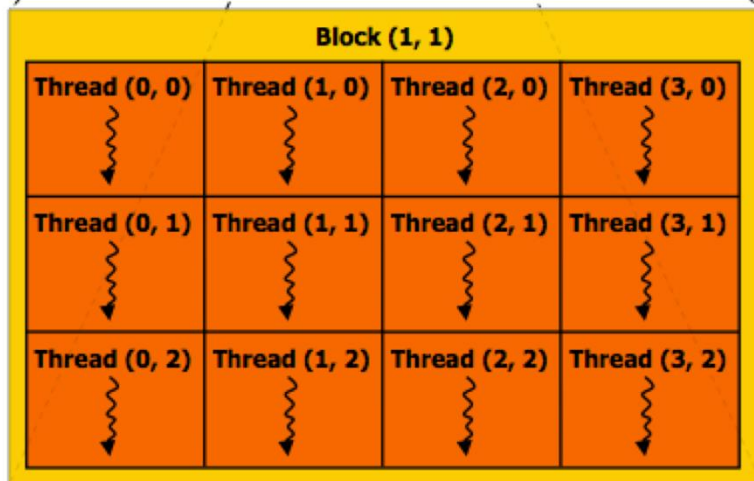
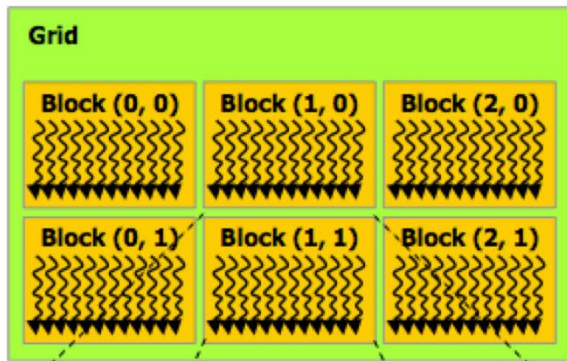
- CUDA Programming Abstractions
- GPU Architectures
- Cast Study 1: Matrix Multiplication in CUDA
- Cast Study 2: Parallel Reduction in CUDA

# CUDA Programming Language

- Introduced in 2007 with NVIDIA Tesla architecture
- "C-like" languages for programming on GPUs
- CUDA's abstractions closely match the capabilities/performance characteristics of modern GPUs
- Design goal: maintain low abstraction distance

# CUDA Programs Consist of a Hierarchy of Threads

- Thread IDs are up to 3-dimensional (2D example below)



```
const int Nx = 12;  
const int Ny = 6;
```

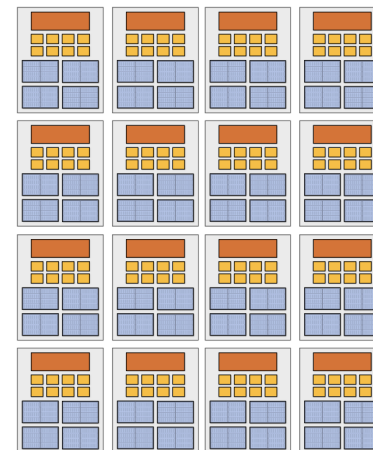
```
dim3 threadsPerBlock(4, 3, 1);  
dim3 numBlocks(Nx/threadsPerBlock.x,  
              Ny/threadsPerBlock.y, 1);
```

```
// assume A, B, C are allocated Nx x Ny float arrays
```

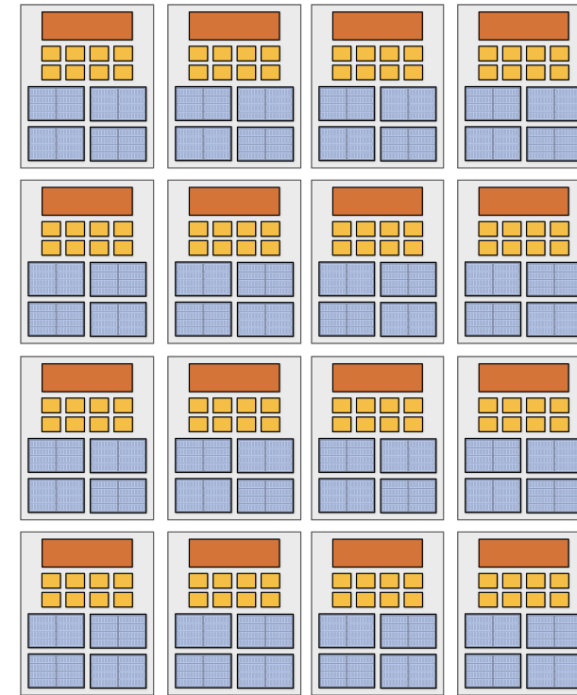
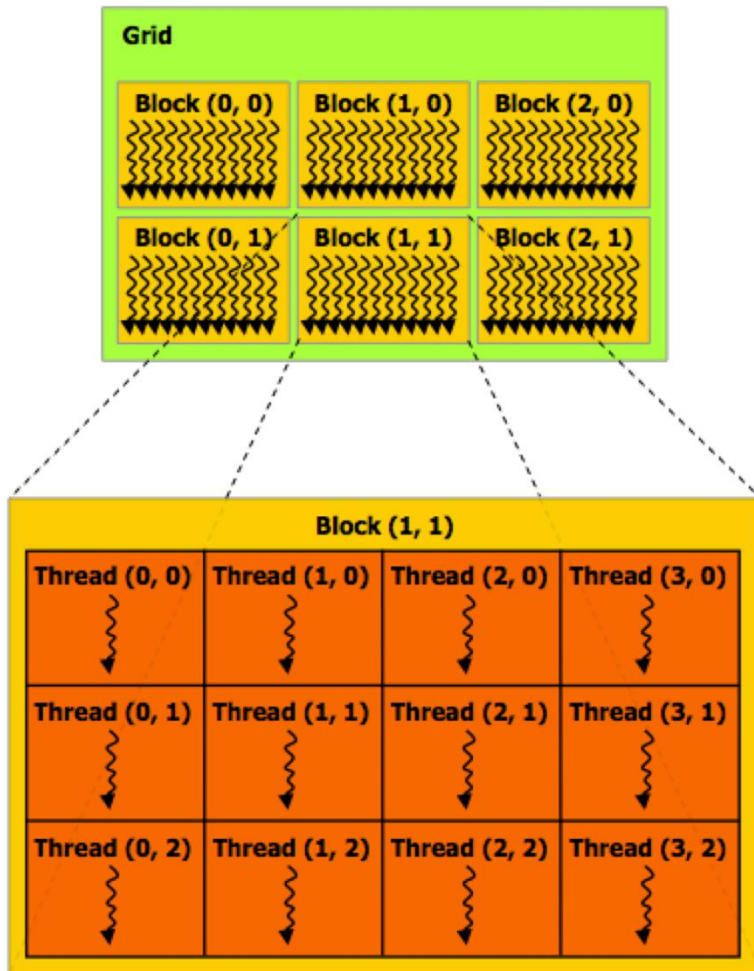
```
// this call will trigger execution of 72 CUDA threads:  
// 6 thread blocks of 12 threads each
```

```
matrixAdd<<<numBlocks, threadsPerBlock>>>(A, B, C);
```

Run on  
CPU



# CUDA Blocks Map to GPU Cores (Streaming Multiprocessors)



GPU

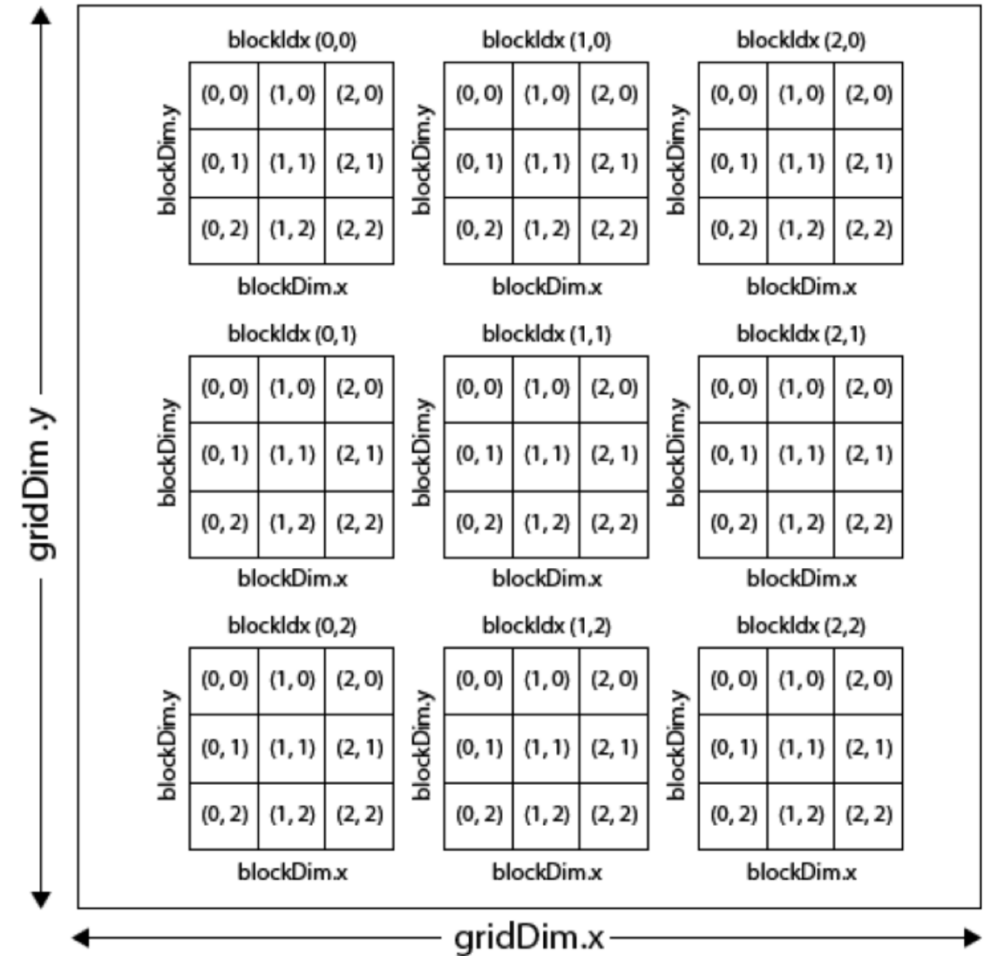


# Grid, Block, and Thread

- `gridDim`: The dimensions of the grid
- `blockIdx`: The block index within the grid
- `blockDim`: The dimensions of a block
- `threadIdx`: The thread index within a block

We always have:  
`gridIdx = (1, 1, 1)`  
`threadDim = (1, 1, 1)`

## CUDA Grid



# Basic CUDA syntax

Serial execution: running as part of normal C/C++ application on CPU

Host

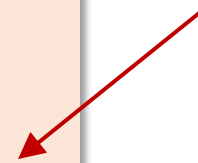
```
const int Nx = 12;
const int Ny = 6;

dim3 threadsPerBlock(4, 3, 1);
dim3 numBlocks(Nx/threadsPerBlock.x,
              Ny/threadsPerBlock.y, 1);

// assume A, B, C are allocated Nx x Ny float arrays

// this call will trigger execution of 72 CUDA threads:
// 6 thread blocks of 12 threads each
matrixAdd<<<numBlocks, threadsPerBlock>>>(A, B, C);
```

Bulk launch of many CUDA threads  
“launch a grid of CUDA thread blocks”  
Call returns when all threads have terminated



Device

```
// kernel definition
__global__ void matrixAdd(float A[Ny][Nx],
                          float B[Ny][Nx],
                          float C[Ny][Nx])
{
    int i = blockDim.x * blockIdx.x + threadIdx.x;
    int j = blockDim.y * blockIdx.y + threadIdx.y;

    C[j][i] = A[j][i] + B[j][i];
}
```

\_\_global\_\_ denotes a CUDA kernel function runs on GPU

Each thread computes its overall grid thread id from its position in its block (threadIdx) and its block's position in the grid (blockIdx)

CUDA kernel: executed in parallel on multiple CUDA cores

# Clear Separation of Host and Device Code

```
const int Nx = 12;
const int Ny = 6;

dim3 threadsPerBlock(4, 3, 1);
dim3 numBlocks(Nx/threadsPerBlock.x,
              Ny/threadsPerBlock.y, 1);

// assume A, B, C are allocated Nx x Ny float arrays

// this call will cause execution of 72 threads
// 6 blocks of 12 threads each
matrixAddDoubleB<<<numBlocks, threadsPerBlock>>>(A, B, C);
```

Separation of execution into host and device code is performed statically by the programmer

“Host” code : serial execution on CPU

```
__device__ float doubleValue(float x)
{
    return 2 * x;
}

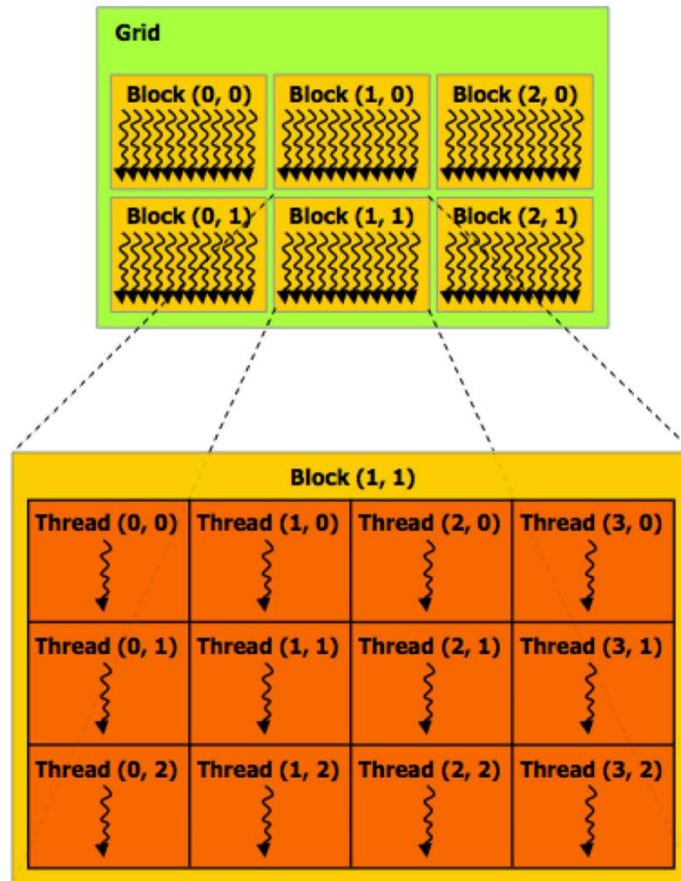
// kernel definition
__global__ void matrixAddDoubleB(float A[Ny][Nx],
                                float B[Ny][Nx],
                                float C[Ny][Nx])
{
    int i = blockIdx.x * blockDim.x + threadIdx.x;
    int j = blockIdx.y * blockDim.y + threadIdx.y;

    C[j][i] = A[j][i] + doubleValue(B[j][i]);
}
```

“Device” code (SIMD execution on GPU)

# Number of SIMD Threads is Explicit in Program

Number of kernel invocations is not determined by size of data collection



```
const int Nx = 11; // not a multiple of threadsPerBlk.x
const int Ny = 5; // not a multiple of threadsPerBlk.y
```

```
dim3 threadsPerBlk(4, 3, 1);
dim3 numBlocks(3, 2, 1);
```

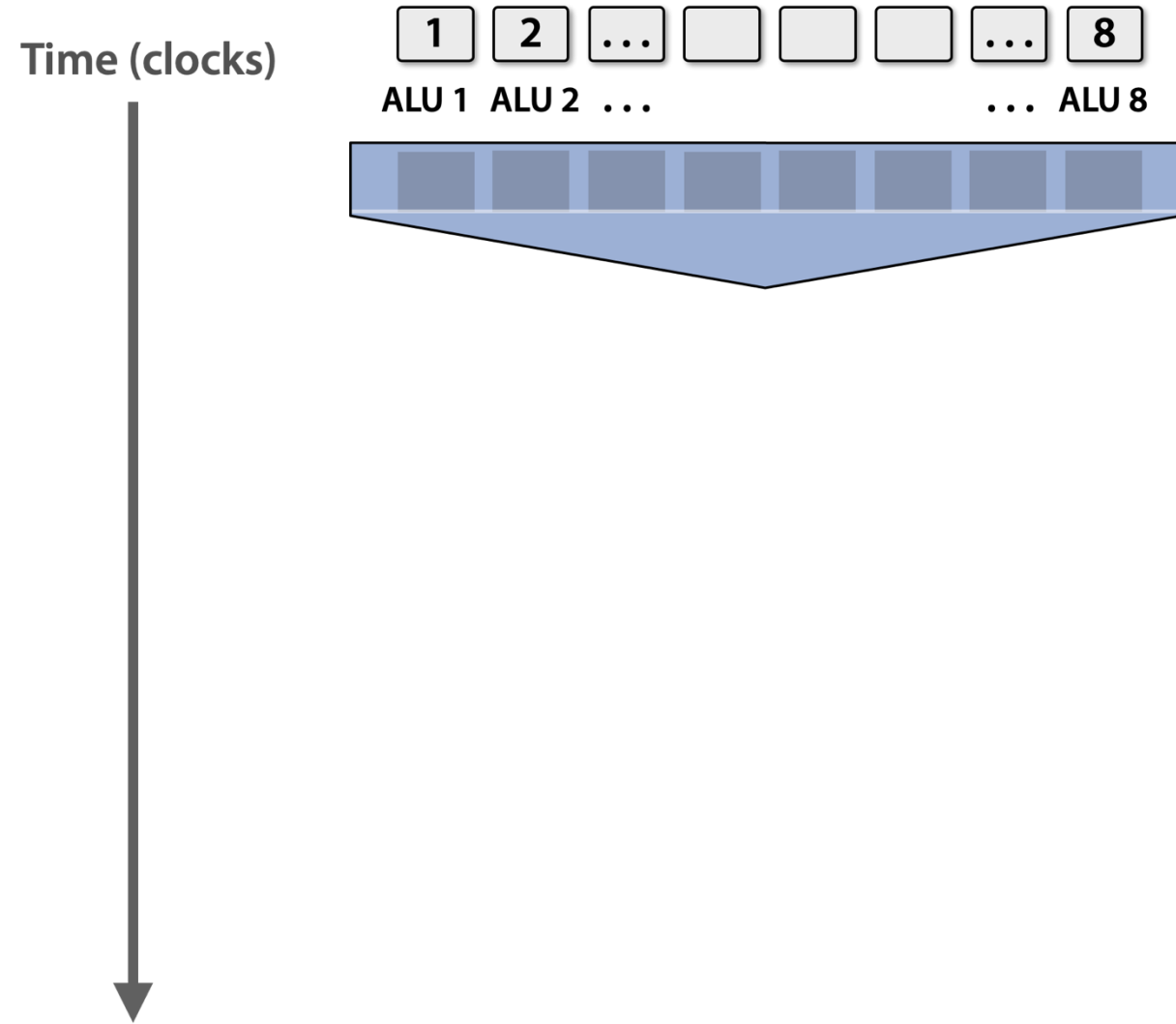
// assume A, B, C are allocated Nx x Ny float arrays

// this call will trigger execution of 72 CUDA threads:  
// 6 thread blocks of 12 threads each

```
matrixAdd<<<numBlocks, threadsPerBlk>>>(A, B, C);
```

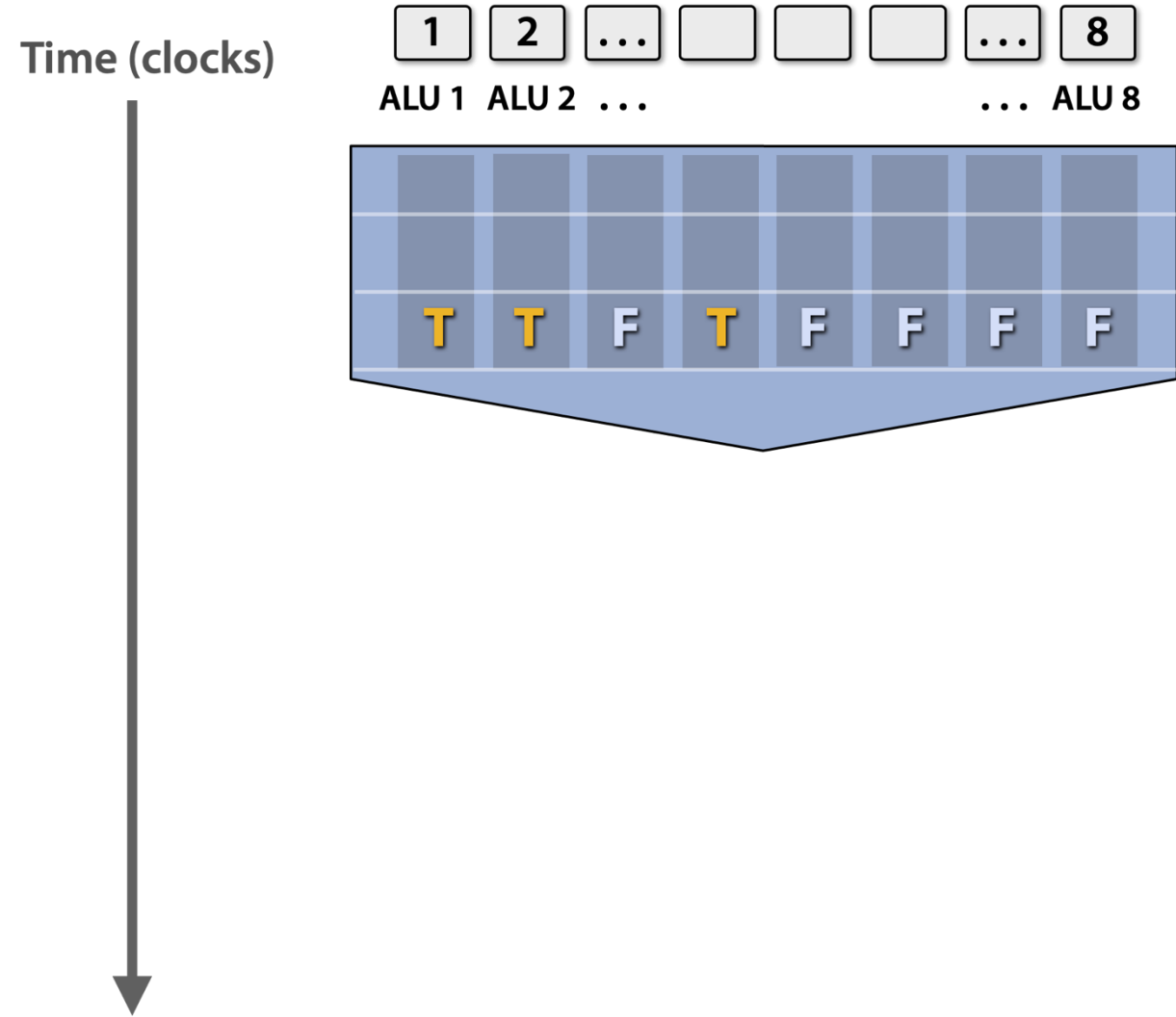
```
// kernel definition
__global__ void matrixAdd(float A[Ny][Nx],
                          float B[Ny][Nx],
                          float C[Ny][Nx])
{
    int i = blockIdx.x * blockDim.x + threadIdx.x;
    int j = blockIdx.y * blockDim.y + threadIdx.y;
    // guard against out of bounds array access
    if (i < Nx && j < Ny)
        C[j][i] = A[j][i] + B[j][i];
}
```

# What about Conditional Execution?



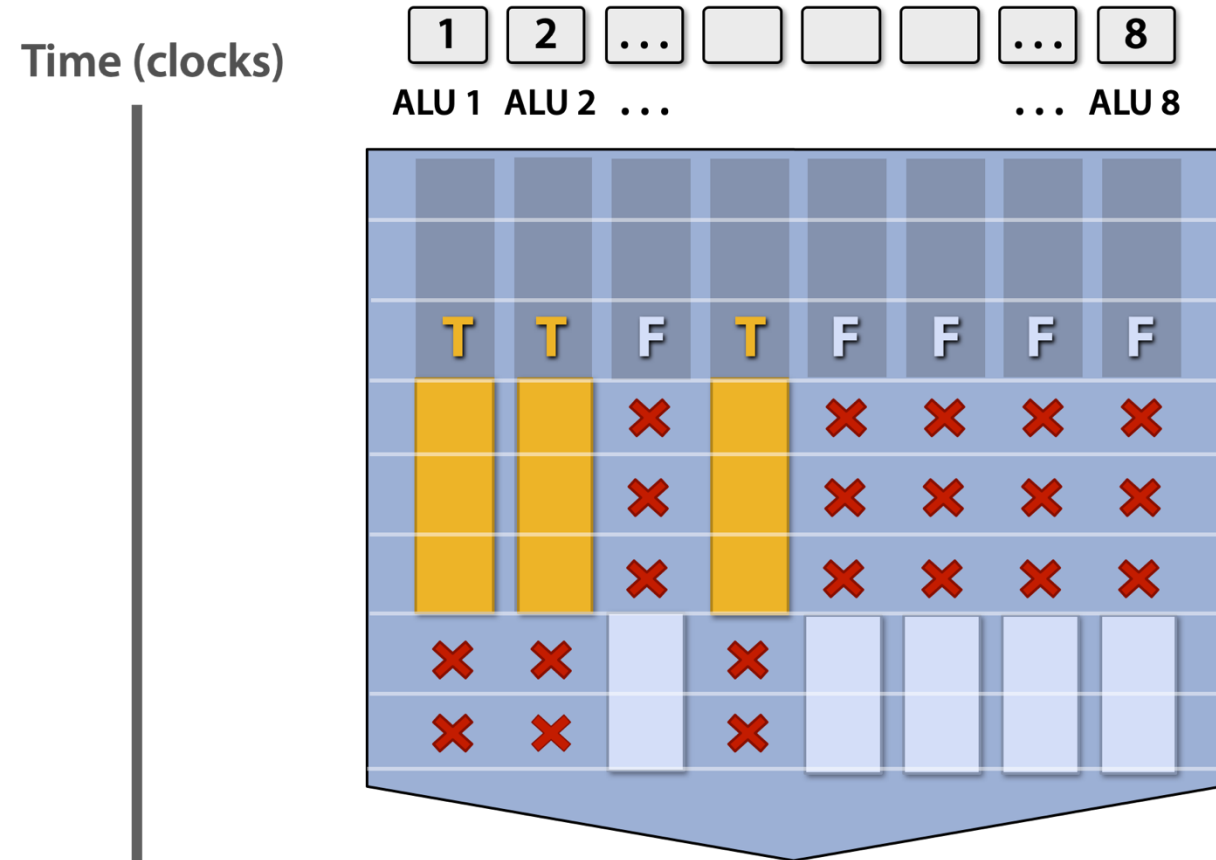
```
// kernel definition
__global__ void f(float A[N])
{
    int i = blockIdx.x * blockDim.x + threadIdx.x;
    float x = A[i];
    if (x > 0) {
        x = 2.0f * x;
    } else {
        x = exp(x, 5.0f);
    }
    A[i] = x;
}
```

# What about Conditional Execution?



```
// kernel definition
__global__ void f(float A[N])
{
    int i = blockIdx.x * blockDim.x + threadIdx.x;
    float x = A[i];
    if (x > 0) {
        x = 2.0f * x;
    } else {
        x = exp(x, 5.0f);
    }
    A[i] = x;
}
```

# Mask (discard) Output of ALU

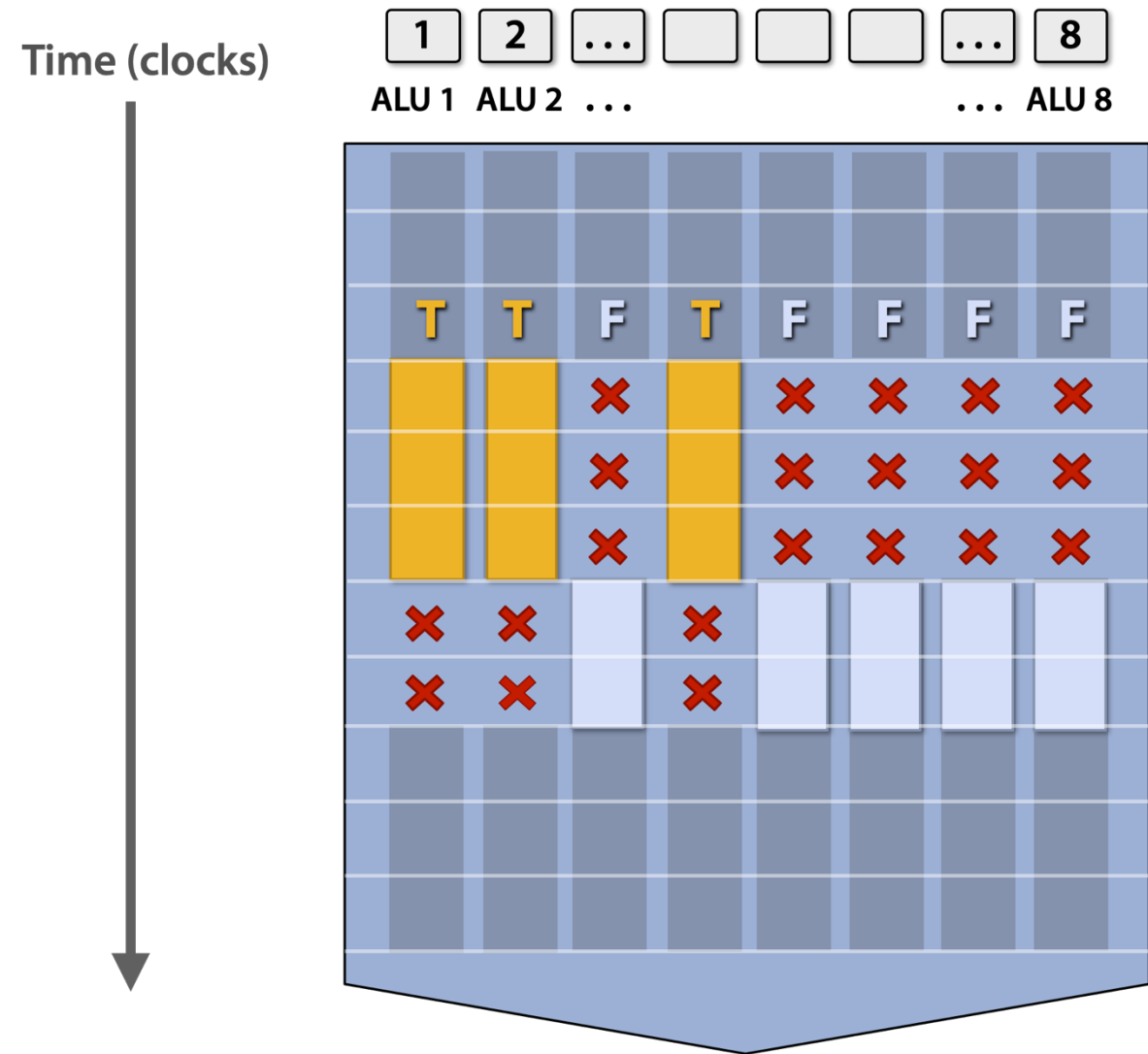


**Not all ALUs do useful work!**

**Worst case: 1/8 peak performance**

```
// kernel definition
__global__ void f(float A[N])
{
    int i = blockIdx.x * blockDim.x + threadIdx.x;
    float x = A[i];
    if (x > 0) {
        x = 2.0f * x;
    } else {
        x = exp(x, 5.0f);
    }
    A[i] = x;
}
```

# After Branch: Continue at Full Performance



```
// kernel definition
__global__ void f(float A[N])
{
    int i = blockIdx.x * blockDim.x + threadIdx.x;
    float x = A[i];
    if (x > 0) {
        x = 2.0f * x;
    } else {
        x = exp(x, 5.0f);
    }
    A[i] = x;
}
```



# Terminology

## Coherence execution

- Same instruction sequence applies to all elements
- Necessary for efficient use of GPUs

## Divergent execution

- A lack of coherence execution
- Should be minimized in CUDA programs

# CUDA Memory Model

Host (serial execution on CPU)



CUDA Device (SIMD execution on GPU)

# CUDA Memory Model

Host (serial execution on CPU)

Host memory address space

CUDA Device (SIMD execution on GPU)

Device memory address space

Distinct host and device address spaces

- Cannot access host memory from device
- Cannot access device memory from host

# cudaMemcpy: Move Data Between Host and Device

Host (serial execution on CPU)

Host memory address space

```
float* A = new float[N];

// populate host address space pointer A
for (int i=0; i<N; i++)
    A[i] = (float)i;

int bytes = sizeof(float) * N
float* deviceA; // allocate buffer in
cudaMalloc(&deviceA, bytes); // device address space

// populate deviceA
cudaMemcpy(deviceA, A, bytes, cudaMemcpyHostToDevice);

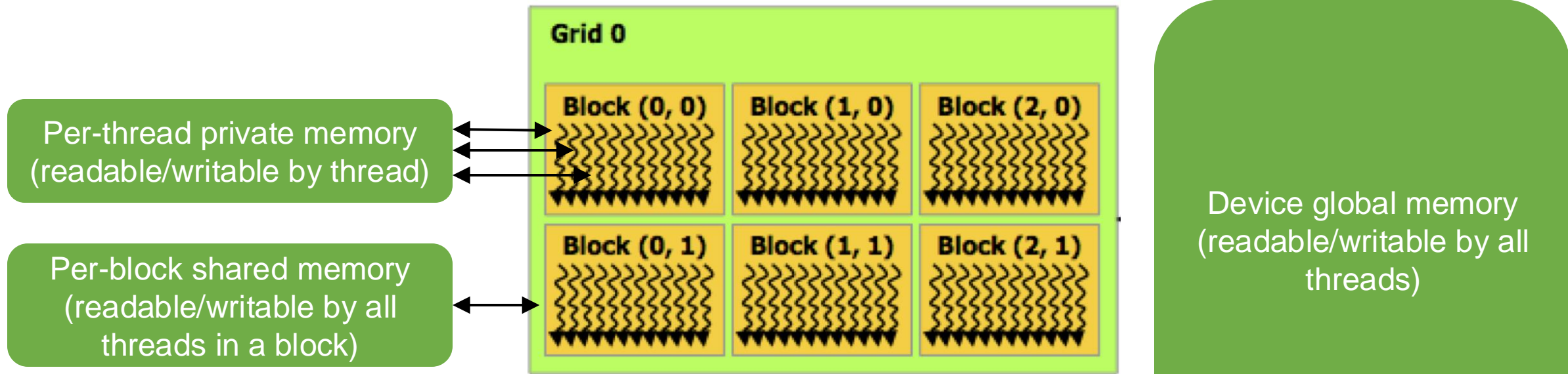
// note: deviceA[i] is an invalid operation here (cannot
// manipulate contents of deviceA directly from host.
// Only from device code.)
```

CUDA Device (SIMD execution on GPU)

Device memory address space

# CUDA Device Memory Model

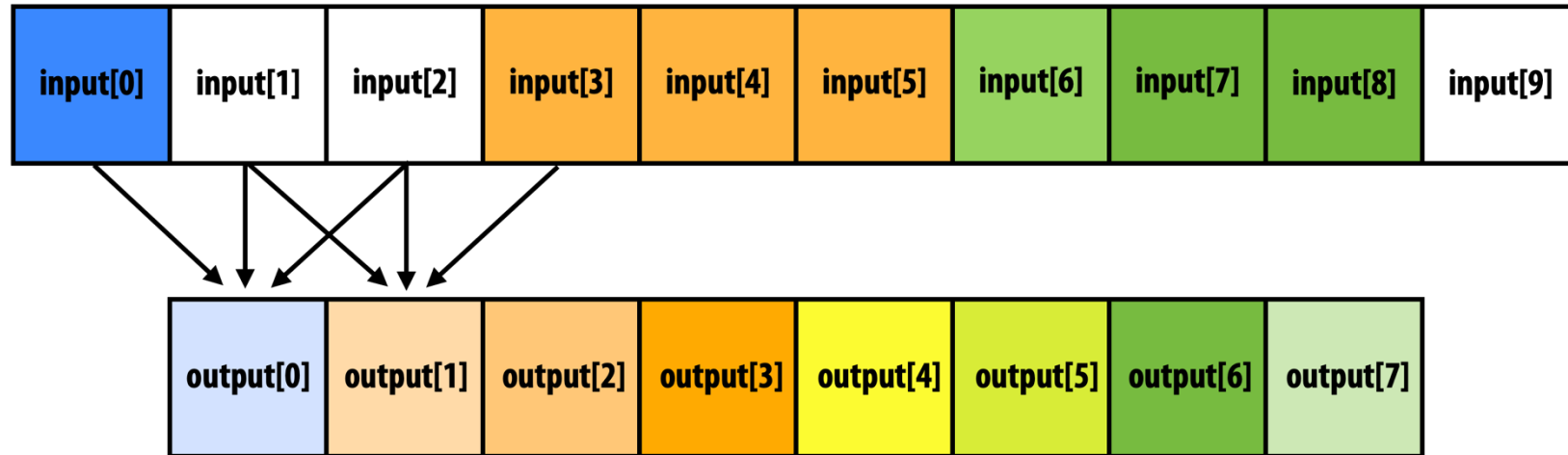
- Three distinct types of memory available to kernels



Why shared memory?

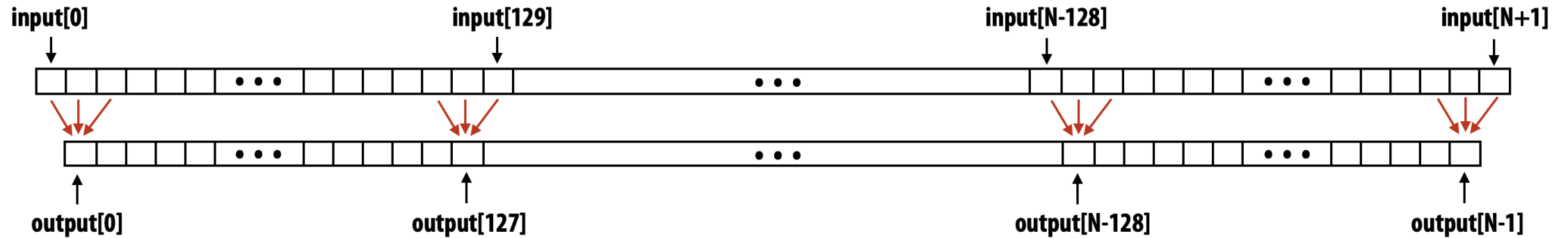
Enable cooperation across threads in a block

# CUDA Programming Example: 1D Convolution



`output[i] = (input[i] + input[i+1] + input[i+2]) / 3.f;`

# 1D Convolution (Version 1)



```
int N = 1024 * 1024
cudaMalloc(&devInput, sizeof(float) * (N+2)); // allocate array in device memory
cudaMalloc(&devOutput, sizeof(float) * N); // allocate array in device memory

// property initialize contents of devInput here ...

convolve<<<N/THREADS_PER_BLK, THREADS_PER_BLK>>>(N, devInput, devOutput);
```

```
#define THREADS_PER_BLK 128

__global__ void convolve(int N, float* input, float* output) {

    int index = blockIdx.x * blockDim.x + threadIdx.x; // thread local variable

    float result = 0.0f; // thread-local variable
    for (int i=0; i<3; i++)
        result += input[index + i];

    output[index] = result / 3.f;
}
```

each thread computes  
result for one element

# 1D Convolution (Reused Shared Memory)

```
int N = 1024 * 1024
cudaMalloc(&devInput, sizeof(float) * (N+2)); // allocate array in device memory
cudaMalloc(&devOutput, sizeof(float) * N); // allocate array in device memory

// property initialize contents of devInput here ...

convolve<<<N/THREADS_PER_BLK, THREADS_PER_BLK>>>(N, devInput, devOutput);
```

```
#define THREADS_PER_BLK 128

__global__ void convolve(int N, float* input, float* output) {

    int index = blockIdx.x * blockDim.x + threadIdx.x; // thread local variable

    __shared__ float support[THREADS_PER_BLK+2]; // per-block allocation
    support[threadIdx.x] = input[index];
    if (threadIdx.x < 2) {
        support[THREADS_PER_BLK + threadIdx.x] = input[index+THREADS_PER_BLK];
    }

    __syncthreads();

    float result = 0.0f; // thread-local variable
    for (int i=0; i<3; i++)
        result += support[threadIdx.x + i];

    output[index] = result / 3.f;
}
```

All threads cooperatively load block's support region from global into shared memory (total of 130 loads instead of 3 \* 128 loads)

barrier (all threads in block)

each thread computes result for one element



# CUDA Synchronization Primitives

- `__syncthreads()`: wait for **all threads in a block** to arrive at this point
- Atomic operations
  - e.g., `float atomicAdd(float* addr, float amount)`
  - Atomic operations on both global and shared memory
- Host/device synchronization
  - Implicit barrier across all threads at return of kernel

# CUDA Compilation

- Goal: run a CUDA program on various GPUs



Mid-range GPU (6 cores)



High-end GPU (16 cores)

# CUDA Compilation

```
int N = 1024 * 1024
cudaMalloc(&devInput, sizeof(float) * (N+2) );
cudaMalloc(&devOutput, sizeof(float) * N);

// property initialize contents of devInput here ...

convolve<<<N/THREADS_PER_BLK, THREADS_PER_BLK>>>(N, devInput, devOutput);
```

Launch 8K thread blocks

```
#define THREADS_PER_BLK 128

__global__ void convolve(int N, float* input, float* output) {

    int index = blockIdx.x * blockDim.x + threadIdx.x;

    __shared__ float support[THREADS_PER_BLK+2];
    support[threadIdx.x] = input[index];
    if (threadIdx.x < 2) {
        support[THREADS_PER_BLK + threadIdx.x] = input[index+THREADS_PER_BLK];
    }

    __syncthreads();

    float result = 0.0f; // thread-local variable
    for (int i=0; i<3; i++)
        result += support[threadIdx.x + i];

    output[index] = result / 3.f;
}
```

A compiled CUDA device binary includes:

Program text (instructions)

Information about required resources:

- 128 threads per block
- 8 bytes of local data per thread
- 130 floats (520 bytes) of shared space per thread block

# CUDA Thread Block Scheduling

- **Major CUDA assumption:** threadblocks can be executed in any order (no dependencies between threadblocks)
- GPU maps threadblocks to cores using a dynamic scheduling policy that respects resource requirements

Grid of 8K convolve thread blocks  
(specified by kernel launch)

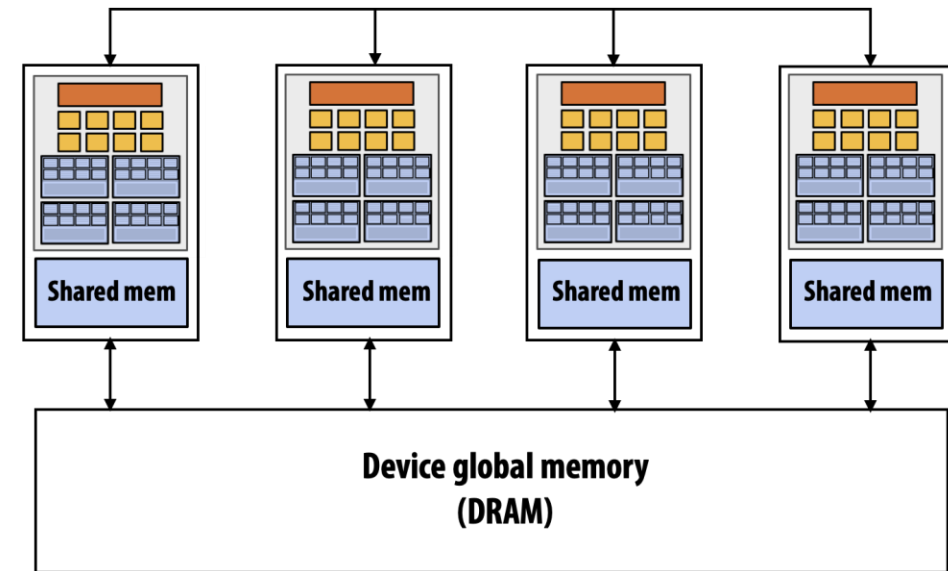
Block requirements:

- 128 threads
- 520 bytes of shared memory
- 1024 bytes of local memory



Special HW  
in GPU

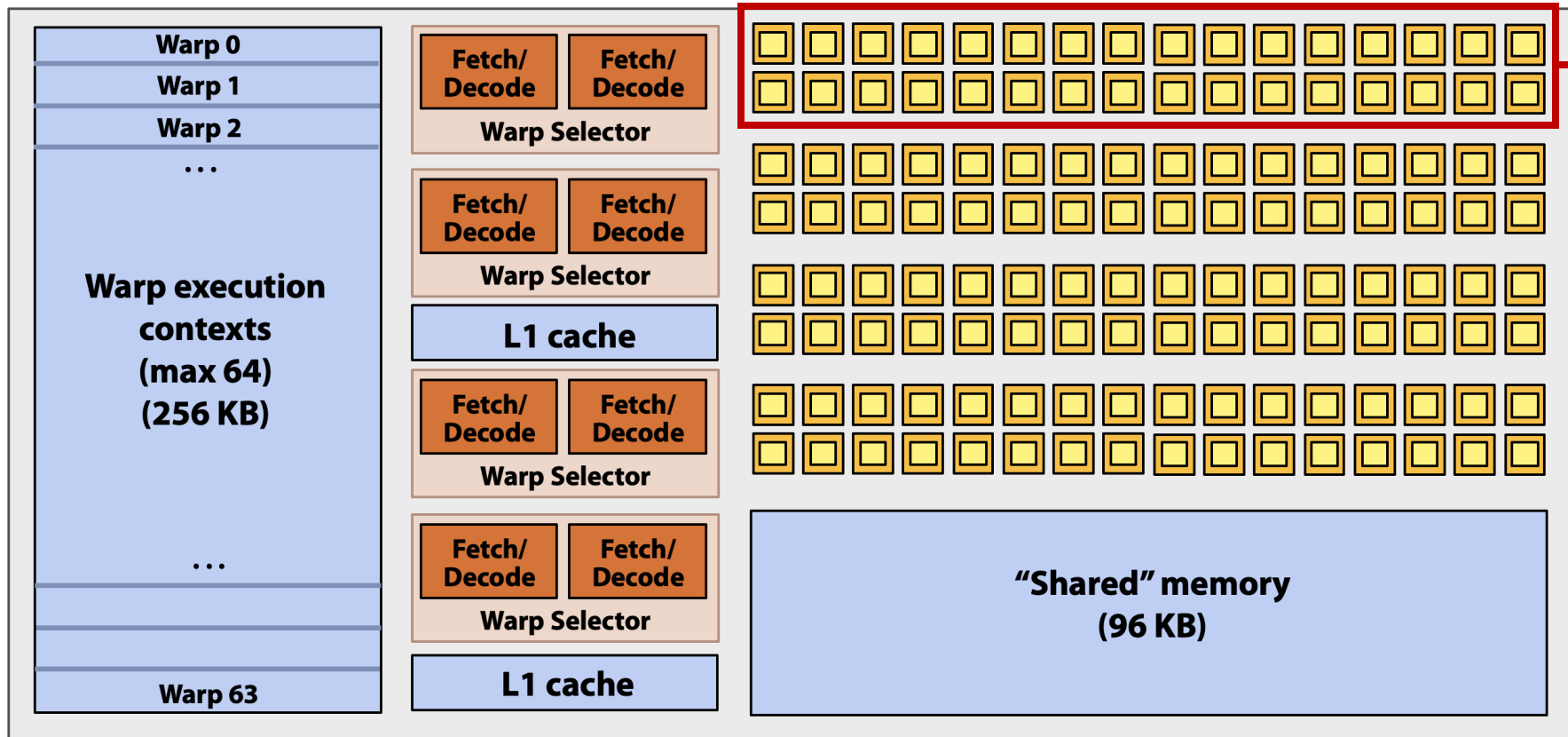
Thread block scheduler



# A GPU Core: Streaming Multiprocessor

SMM resource limits:

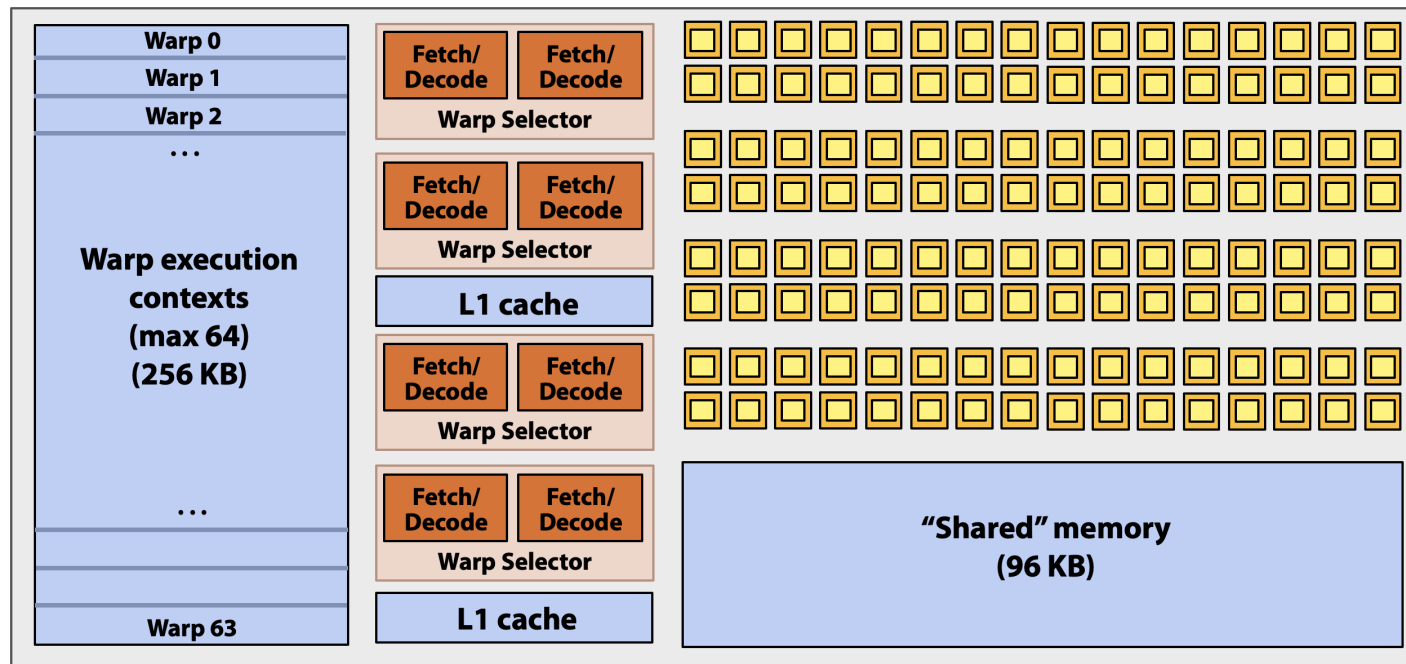
- Max warp execution contexts: 64 (up to  $64 * 32 = 2K$  total CUDA threads)
- 96 KB of shared memory



SIMD functional unit,  
control shared across 32 units  
(1 MUL-ADD per clock)

# Running a Thread Block on an SMM

- Warp: A group of 32 CUDA threads shared an instruction stream.
  - A convolve thread block is executed by 4 warps (4 warps x 32 threads / warp = 128 threads)
- SMM operation each clock:
  - Select up to four runnable warps from 64 resident on an SMM (thread-level parallelism)
  - Select up to two runnable instructions per warp (instruction-level parallelism)

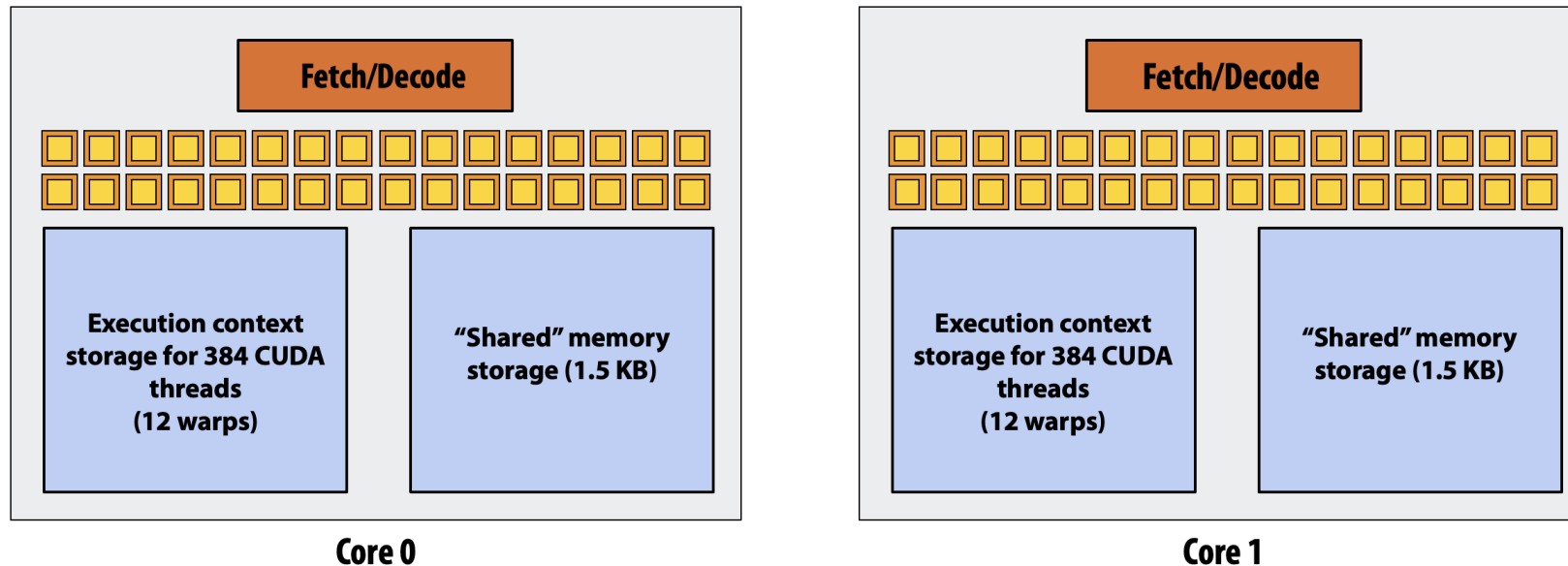


# Running a CUDA Kernel

- Convolve kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 520$  bytes of shared memory
- Assume the host side launches 1000 thread blocks

```
#define THREADS_PER_BLK 128  
convolve<<<N/THREADS_PER_BLK, THREADS_PER_BLK>>>(N, input_array, output_array);
```

- Run the program on a two-SMM GPU

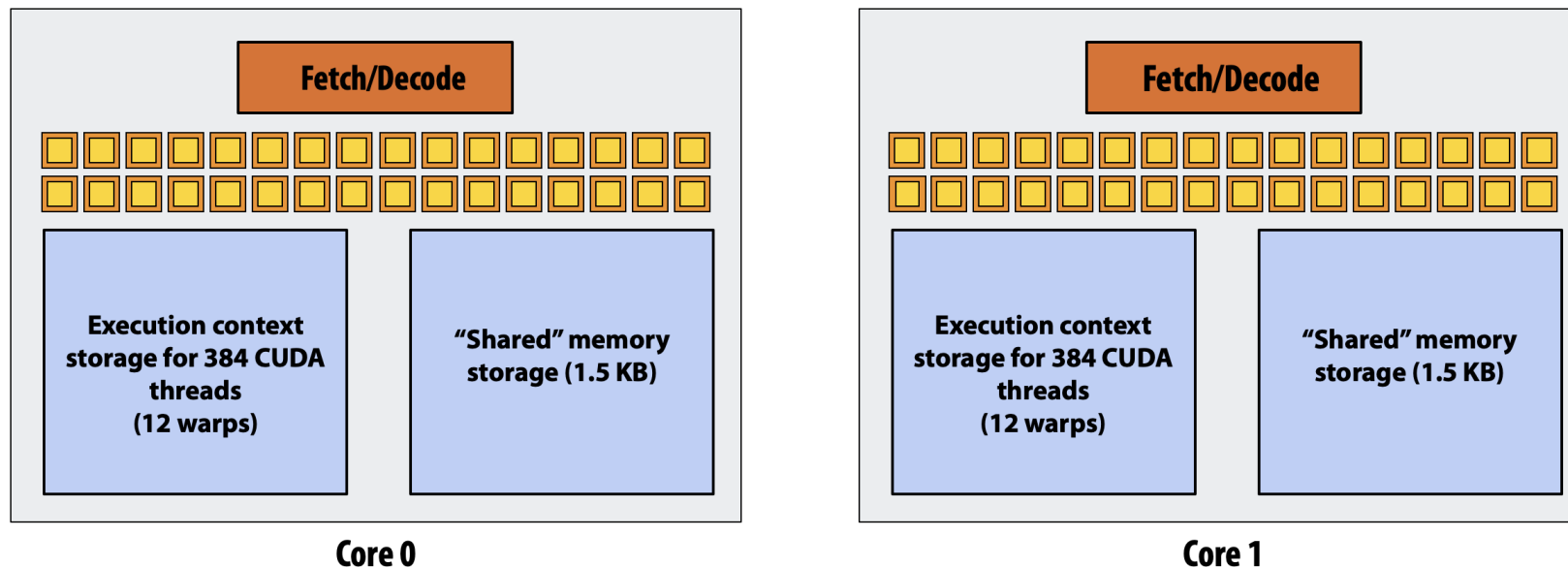


# Running a CUDA Kernel

- Convolve kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- Step 1: host sends CUDA kernel to device

## GPU Work Scheduler

```
EXECUTE: convolve  
ARGS:   N, input_array, output_array  
NUM_BLOCKS: 1000
```



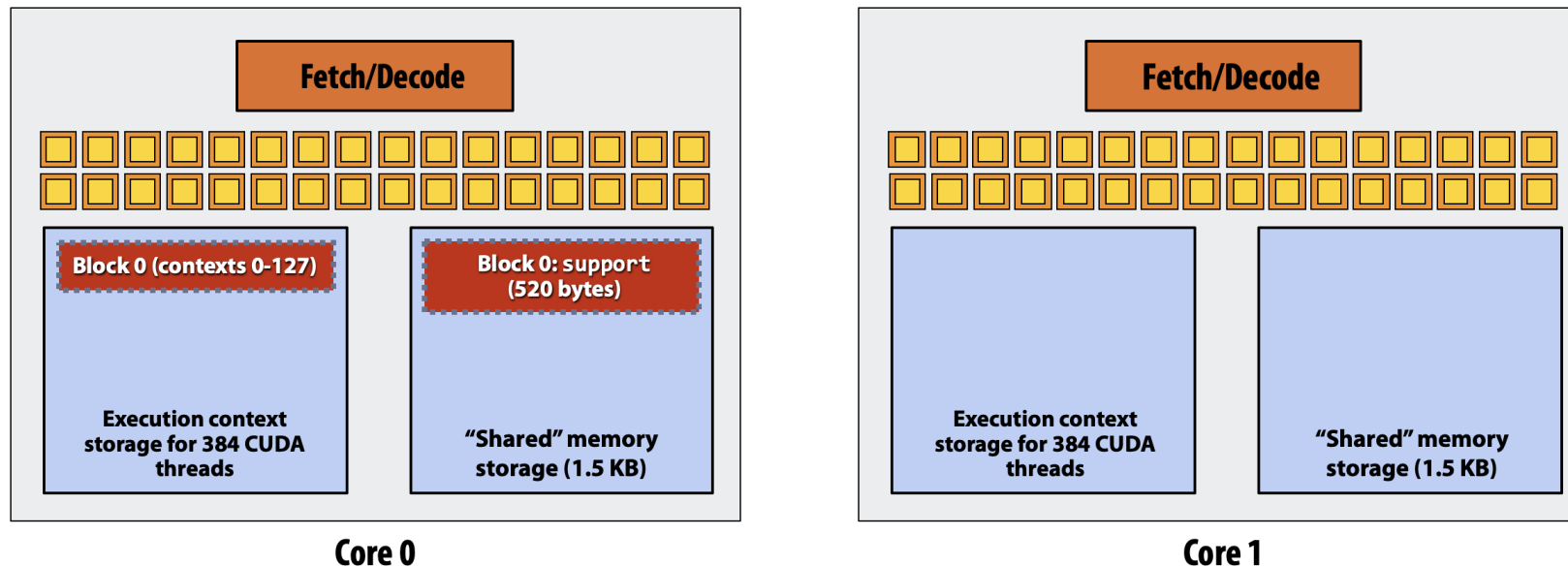


# Running a CUDA Kernel

- Convolve kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- Step 2: scheduler maps block 0 to core 0 (reserves execution contexts for 128 threads and 520 bytes of shared memory)

GPU Work Scheduler

```
EXECUTE: convolve  
ARGS:   N, input_array, output_array  
NUM_BLOCKS: 1000
```

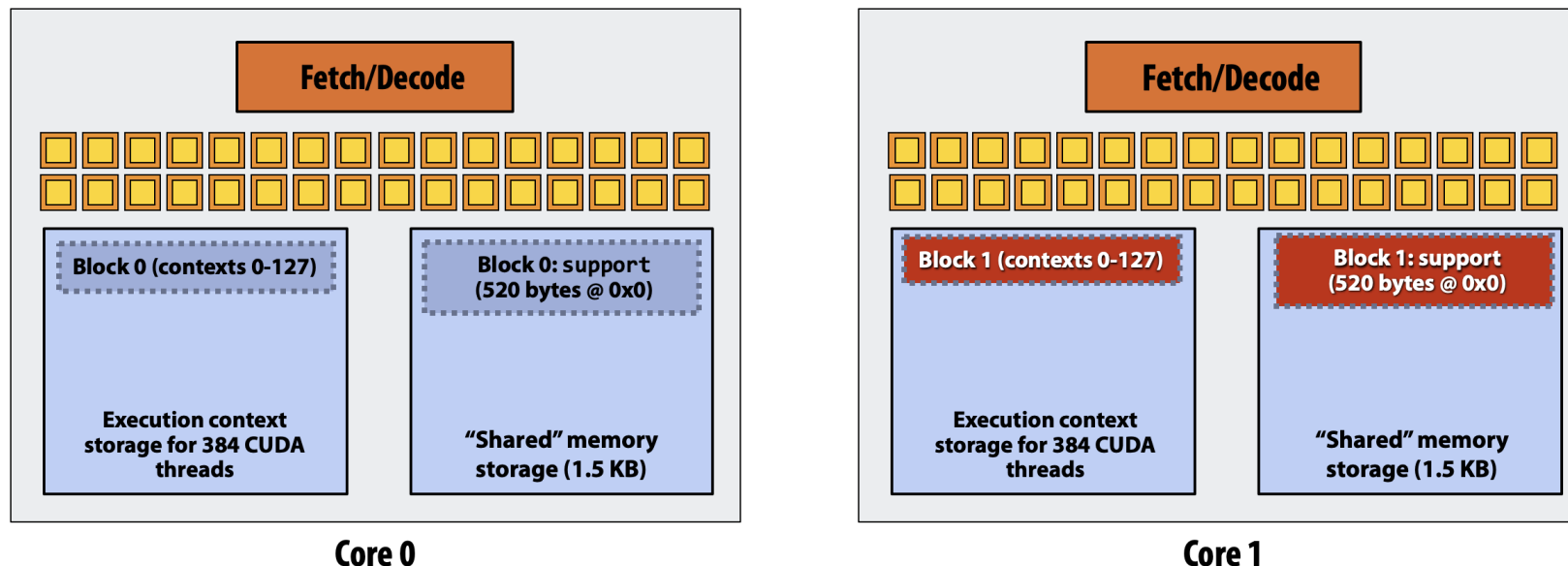


# Running a CUDA Kernel

- Convoke kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- Step 3: scheduler continues to map blocks to available execution contexts

## GPU Work Scheduler

```
EXECUTE: convolve  
ARGS:   N, input_array, output_array  
NUM_BLOCKS: 1000
```

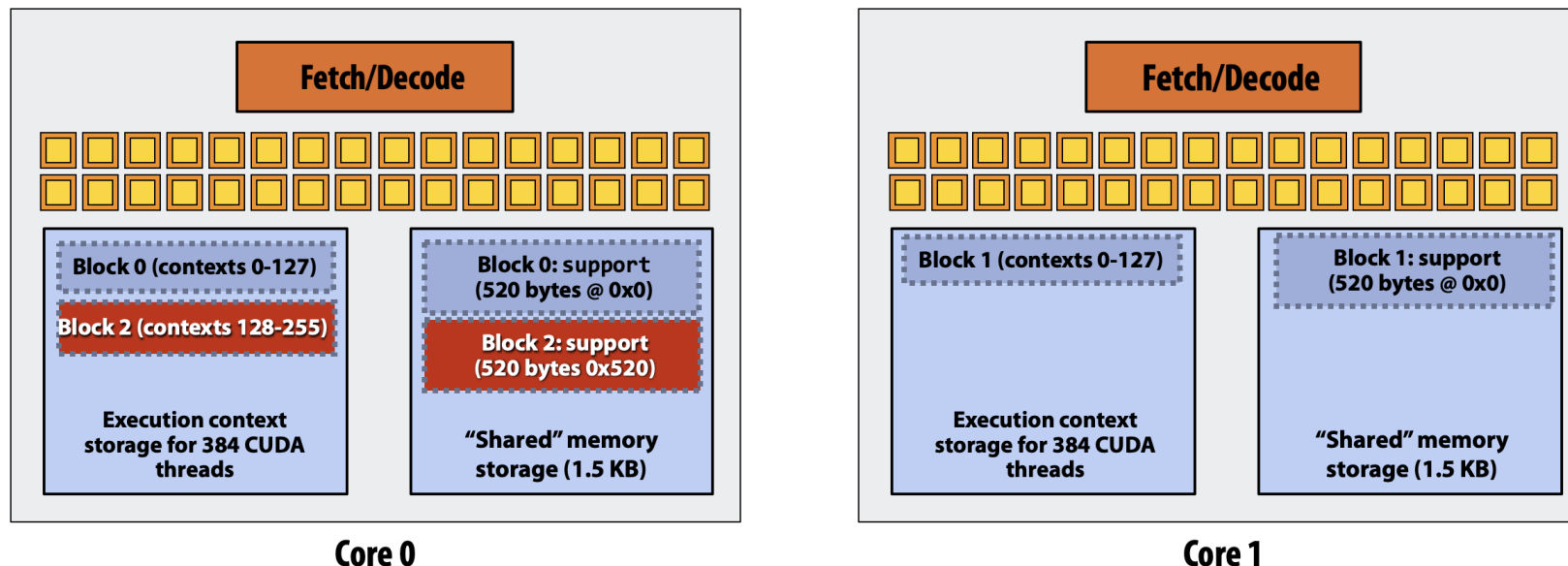


# Running a CUDA Kernel

- Convoke kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- Step 3: scheduler continues to map blocks to available execution contexts

## GPU Work Scheduler

```
EXECUTE: convolve  
ARGS: N, input_array, output_array  
NUM_BLOCKS: 1000
```

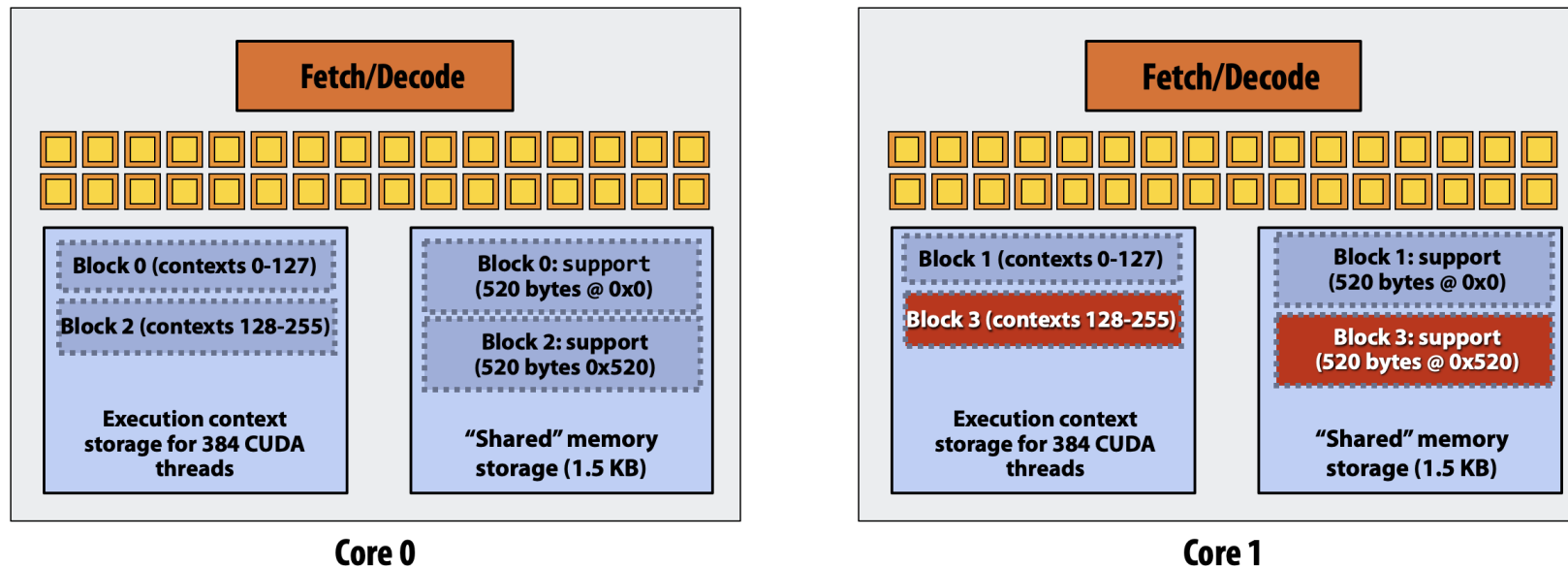


# Running a CUDA Kernel

- Convoke kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- (third block won't fit due to insufficient shared storage  $3 * 520B > 1.5KB$ )

## GPU Work Scheduler

```
EXECUTE: convolve  
ARGS:   N, input_array, output_array  
NUM_BLOCKS: 1000
```

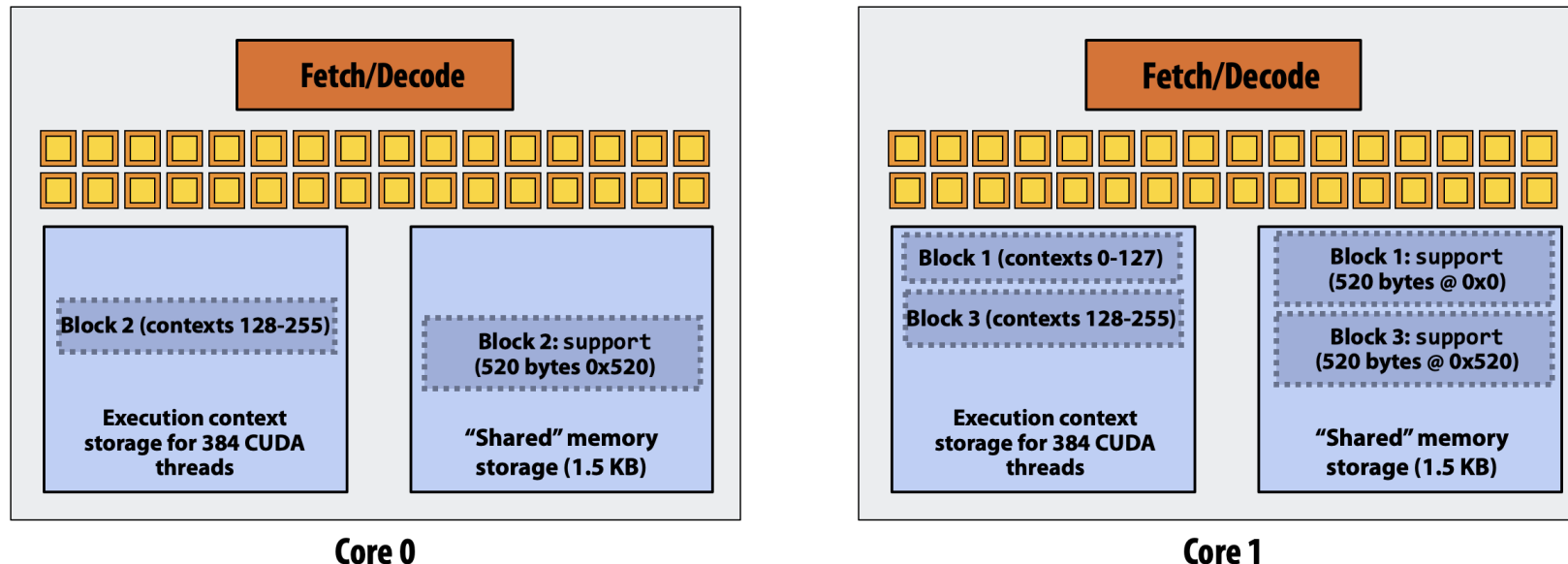


# Running a CUDA Kernel

- Convoke kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- Step 4: thread block 0 completes on core 0

## GPU Work Scheduler

```
EXECUTE: convolve  
ARGS:   N, input_array, output_array  
NUM_BLOCKS: 1000
```

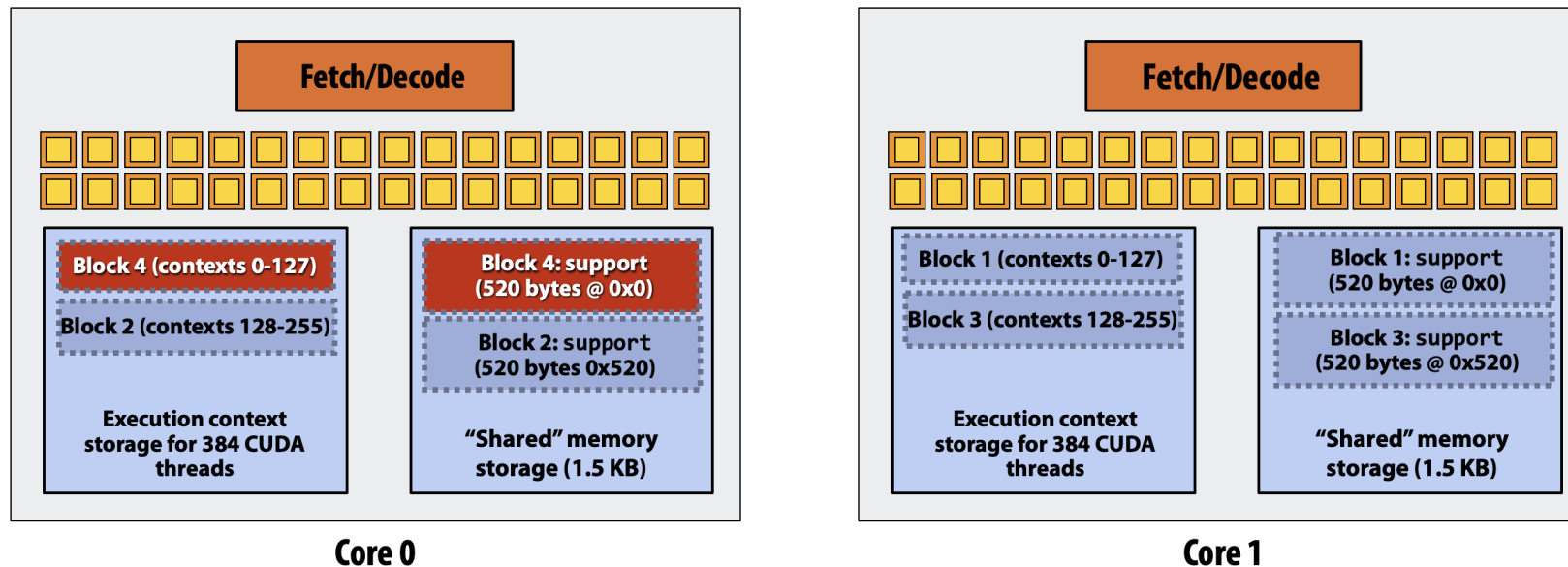


# Running a CUDA Kernel

- Convolve kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- Step 5: thread block 4 is scheduled on core 0 (mapped to execution contexts 0-127)

## GPU Work Scheduler

```
EXECUTE: convolve  
ARGS: N, input_array, output_array  
NUM_BLOCKS: 1000
```

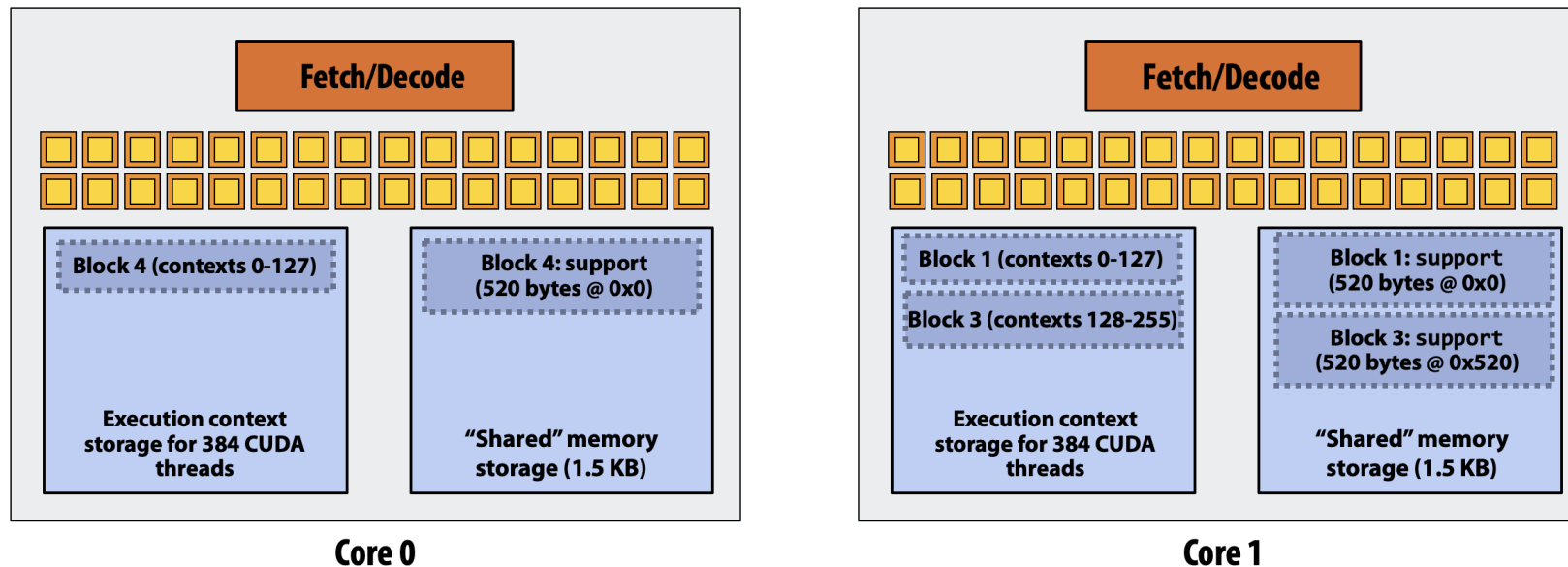


# Running a CUDA Kernel

- Convoke kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- Step 6: thread block 2 completes on core 0

## GPU Work Scheduler

EXECUTE: convolve  
ARGS: N, input\_array, output\_array  
NUM\_BLOCKS: 1000

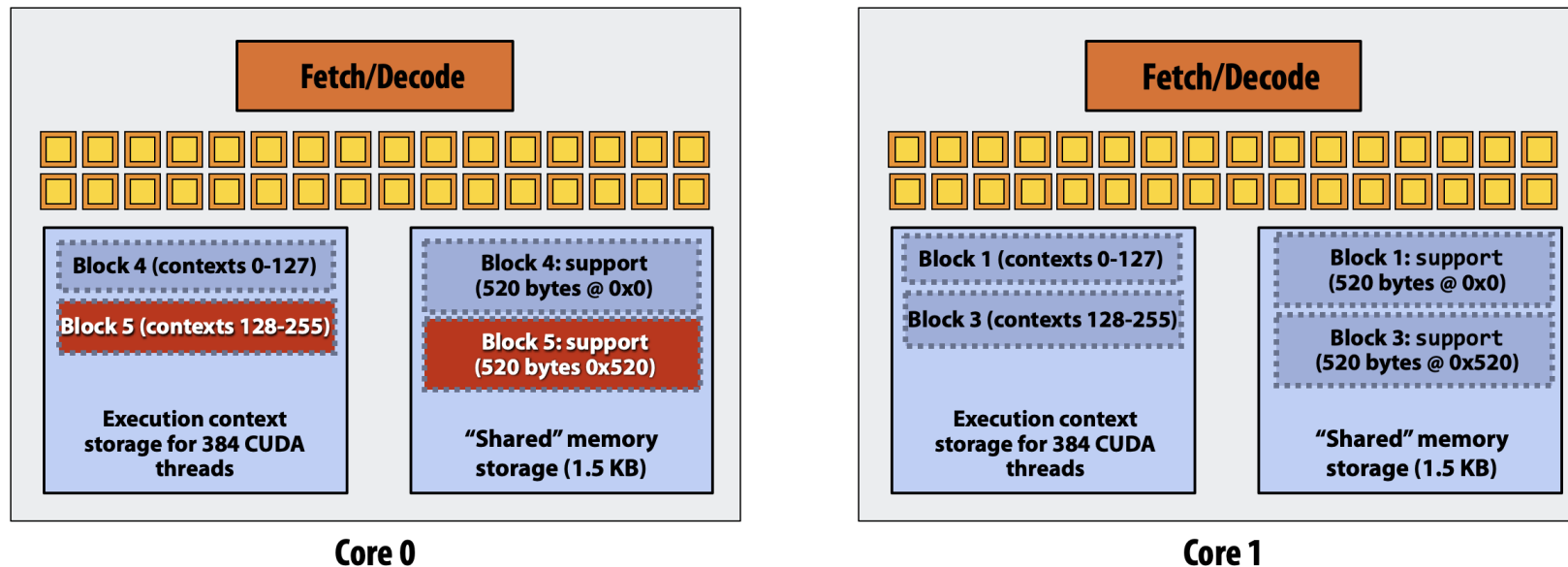


# Running a CUDA Kernel

- Convolve kernel's requirement:
  - Each thread block execute 128 CUDA threads
  - Each thread block allocate  $130 * 4 = 512$  bytes of shared memory
- Step 7: thread block 5 is scheduled on core 0 (mapped to execution contexts 128-255)

## GPU Work Scheduler

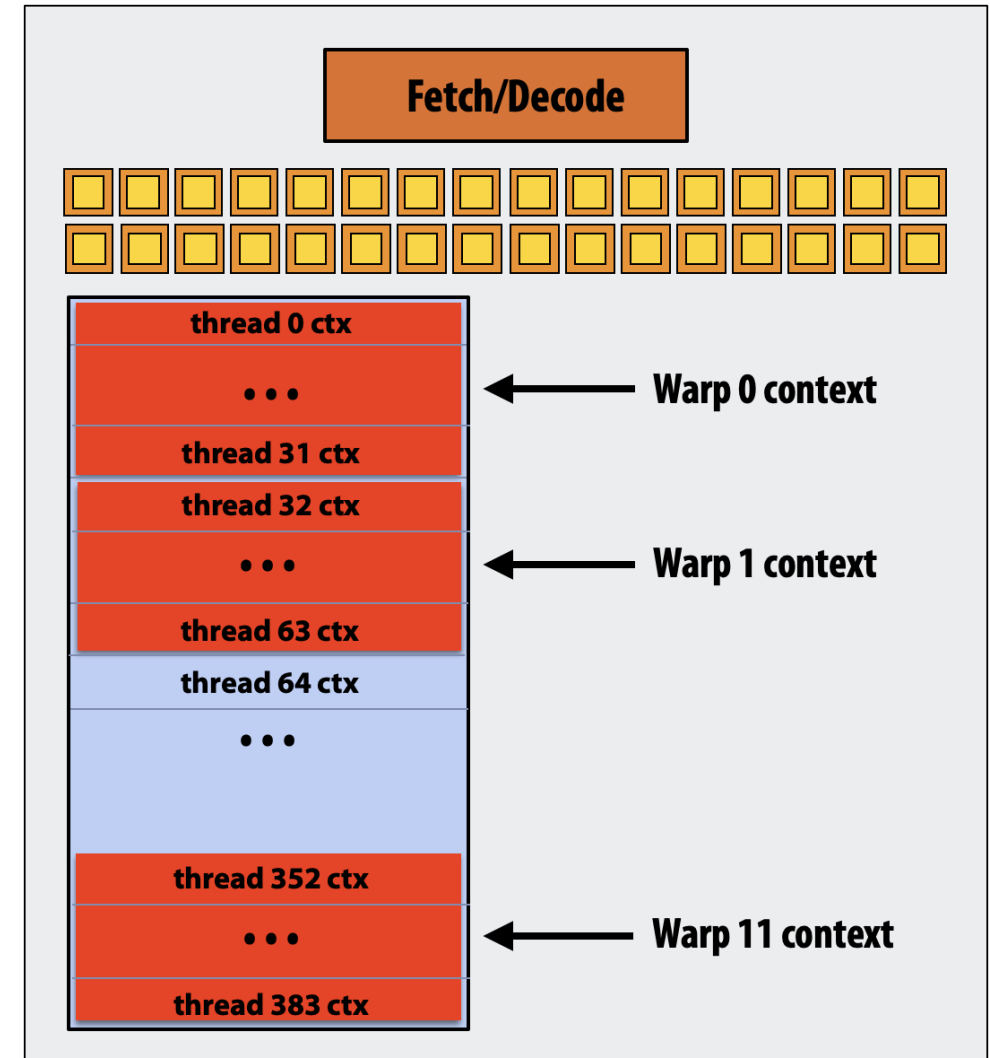
```
EXECUTE: convolve  
ARGS:   N, input_array, output_array  
NUM_BLOCKS: 1000
```





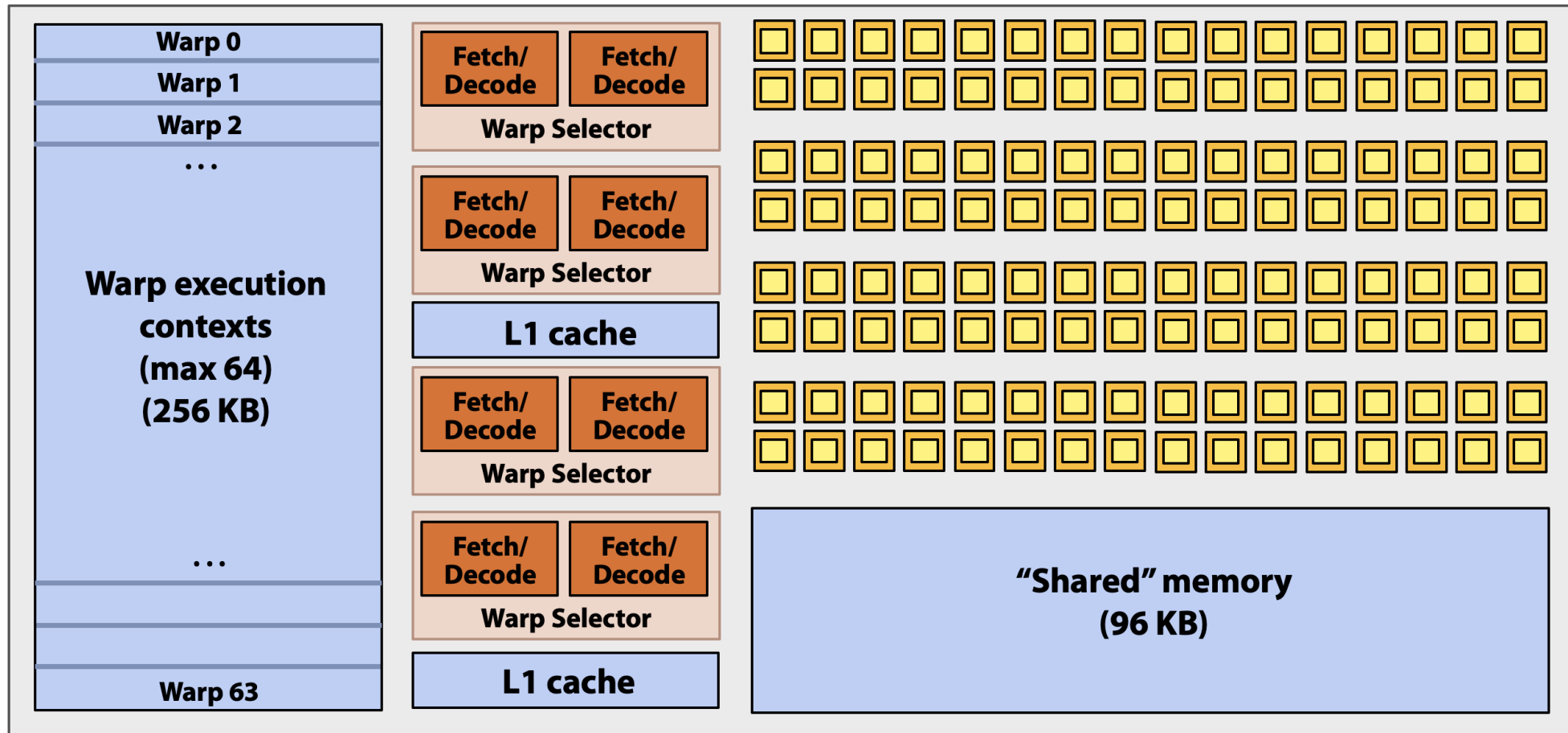
# What is a warp?

- A warp is a CUDA implementation detail on NVIDIA GPUs
- On modern NVIDIA GPUs, groups of 32 CUDA threads in a thread block are executed simultaneously using 32-wide SIMD execution

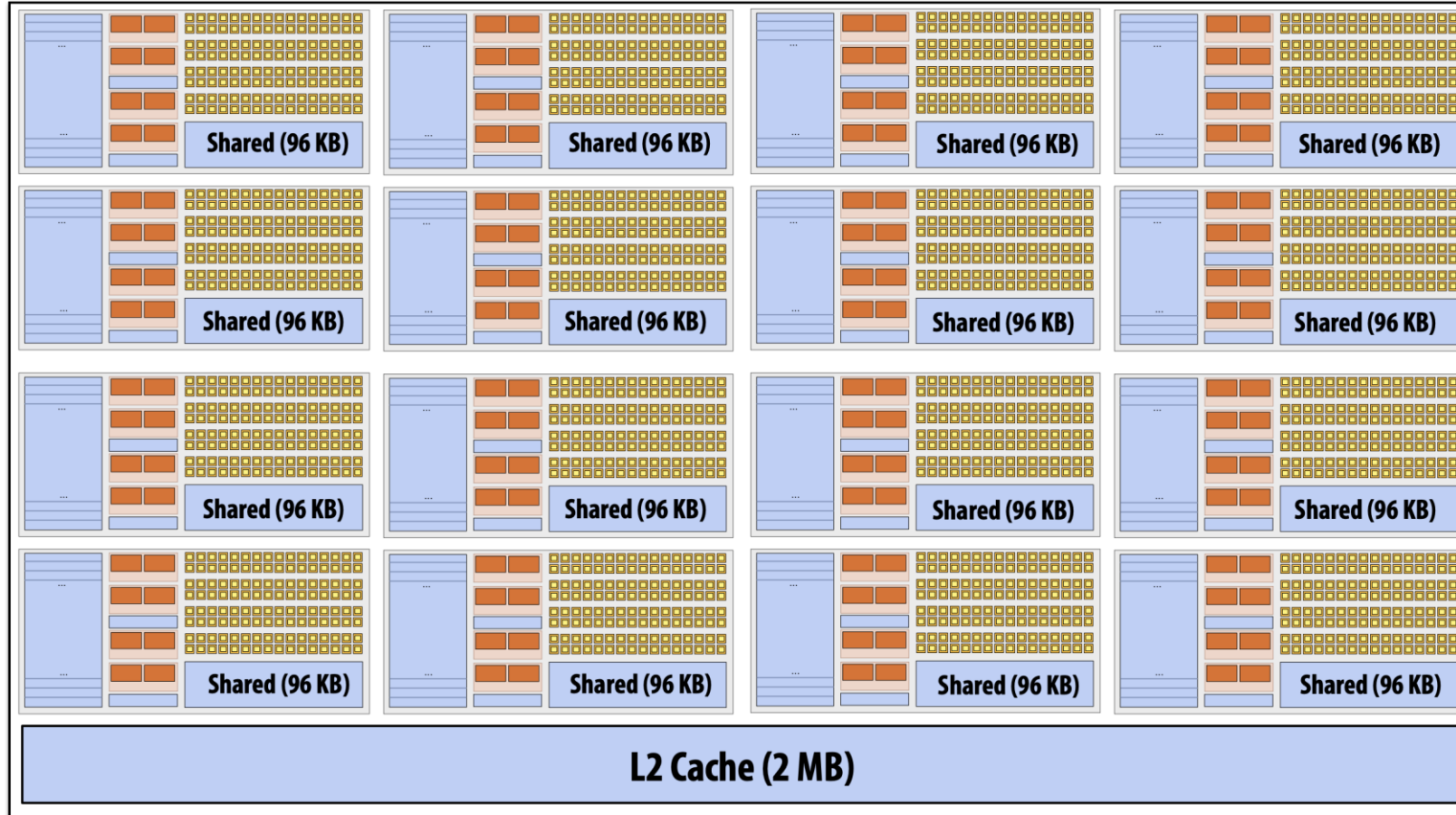


# Recall: An SMM on a NVIDIA GTX 980 (2014)

- SMM resource:
  - Map warp execution contexts: 64 ( $64 * 32 = 2048$  total CUDA threads)
  - 96 KB of shared memory



# NVIDIA GTX 980 Contains 16 SMMs



1.1 GHz clock

16 SMM cores per chip

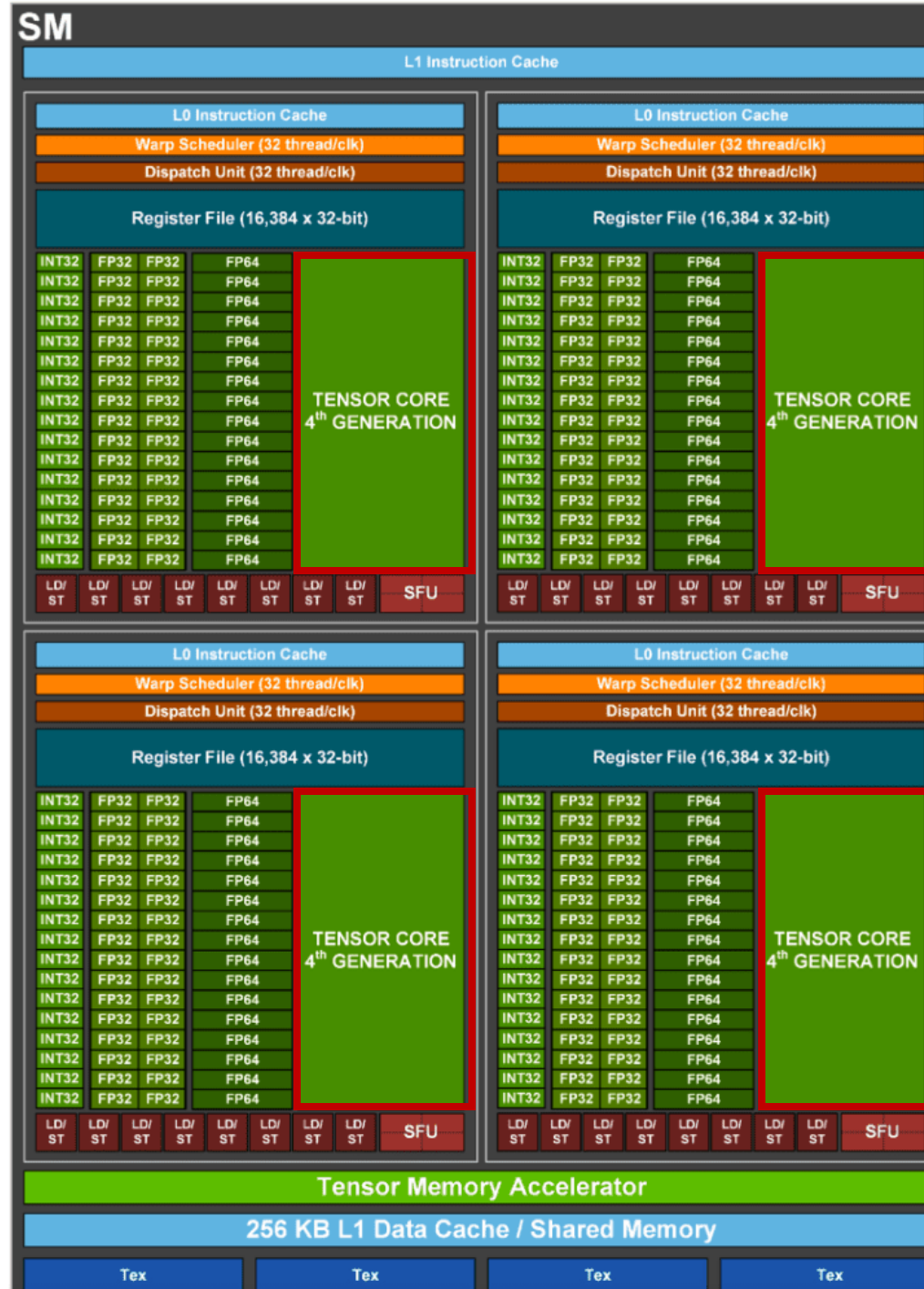
16 x 4 warps x 32 threads / warp  
= 2048 SIMD mul-add ALUs  
= 4.6 TFLOPs

Up to 16 x 64 = 1024 interleaved  
warps per chip  
(32,768 CUDA threads / chip)

# GTX 980 (2014) -> H100 (2022)

- SMMs remain the same
  - Clock speed: 1064 MHz -> 1110 MHz
  - Map warps per SMM: 64 -> 64
  - Threads per warp: 32 -> 32
  - Shared memory per SMM: 96 KB -> 168 KB (A100) -> 256 KB (H100)
- Streaming multiprocessors: 16 SMMs -> 132 SMMs
- Peak performance 4.6 TFLOPs -> 1000 TFLOPs (mainly because of tensor cores)

# H100 Architecture with Tensor Cores



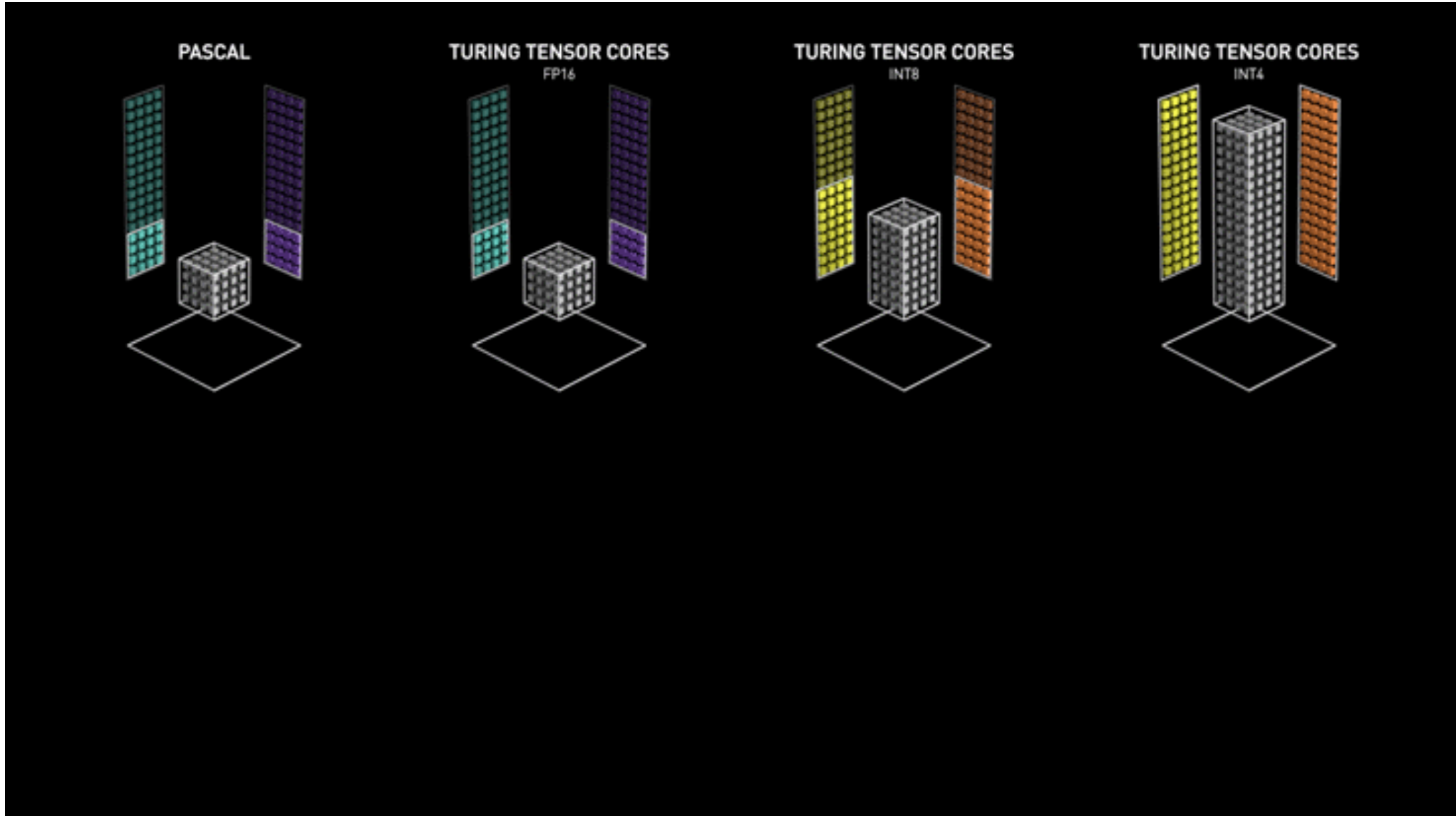
# Tensor Cores

- Matrix multiplication unit in SMM

$$\mathbf{D} = \begin{pmatrix} A_{0,0} & A_{0,1} & A_{0,2} & A_{0,3} \\ A_{1,0} & A_{1,1} & A_{1,2} & A_{1,3} \\ A_{2,0} & A_{2,1} & A_{2,2} & A_{2,3} \\ A_{3,0} & A_{3,1} & A_{3,2} & A_{3,3} \end{pmatrix} \begin{pmatrix} B_{0,0} & B_{0,1} & B_{0,2} & B_{0,3} \\ B_{1,0} & B_{1,1} & B_{1,2} & B_{1,3} \\ B_{2,0} & B_{2,1} & B_{2,2} & B_{2,3} \\ B_{3,0} & B_{3,1} & B_{3,2} & B_{3,3} \end{pmatrix} + \begin{pmatrix} C_{0,0} & C_{0,1} & C_{0,2} & C_{0,3} \\ C_{1,0} & C_{1,1} & C_{1,2} & C_{1,3} \\ C_{2,0} & C_{2,1} & C_{2,2} & C_{2,3} \\ C_{3,0} & C_{3,1} & C_{3,2} & C_{3,3} \end{pmatrix}$$

FP16 or FP32                      FP16                      FP16                      FP16 or FP32

# Tensor Cores



# Outline

- CUDA Programming Abstractions
- CUDA Implementation on Modern GPUs
- **Cast Study 1: Matrix Multiplication in CUDA**
- Cast Study 2: Parallel Reduction in CUDA



# Strawman Implementation of Matmul

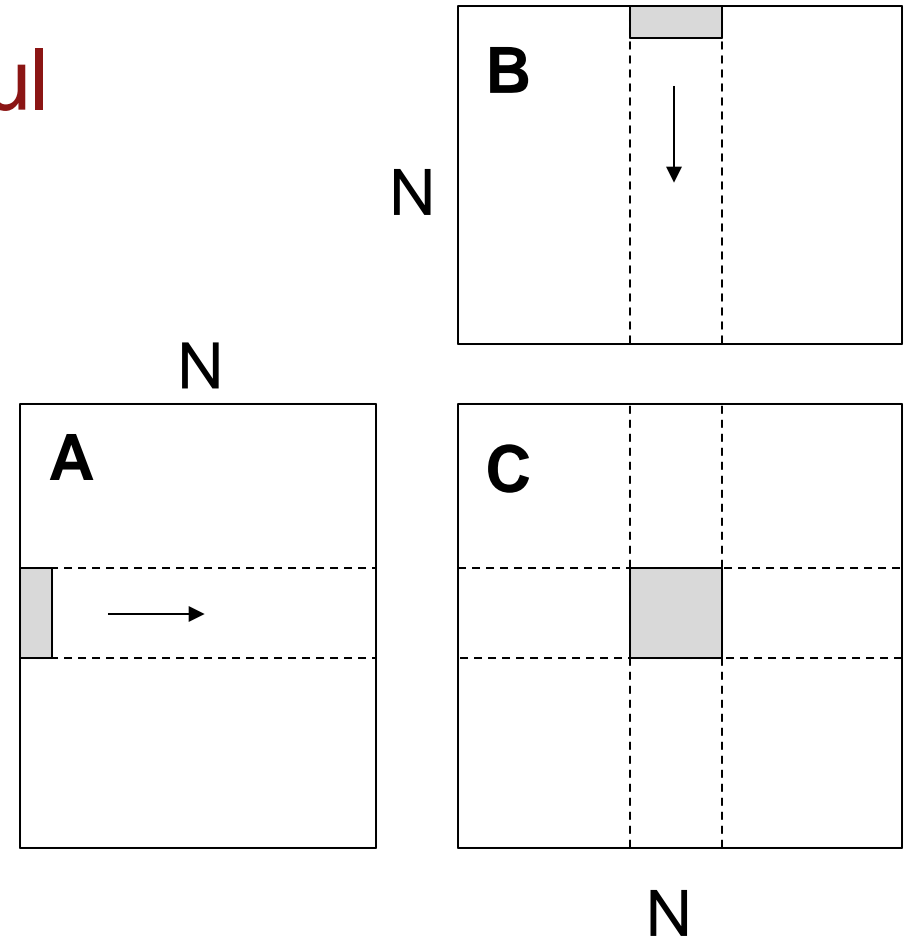
- Compute  $C = A \times B$
- Each thread computes one element

```
int N = 1024;
dim3 threadsPerBlock(32, 32, 1);
dim3 numBlocks(N/32, N/32, 1);

matmul<<<numBlocks, threadsPerBlock>>>(A, B, C);
```

```
__global__ void mm(float A[N][N], float B[N][N], float C[N][N]) {
    int x = blockIdx.x * blockDim.x + threadIdx.x;
    int y = blockIdx.y * blockDim.y + threadIdx.y;

    result = 0;
    for (int k = 0; k < N; ++k) {
        result += A[x][k] * B[k][y];
    }
    C[x][y] = result;
}
```

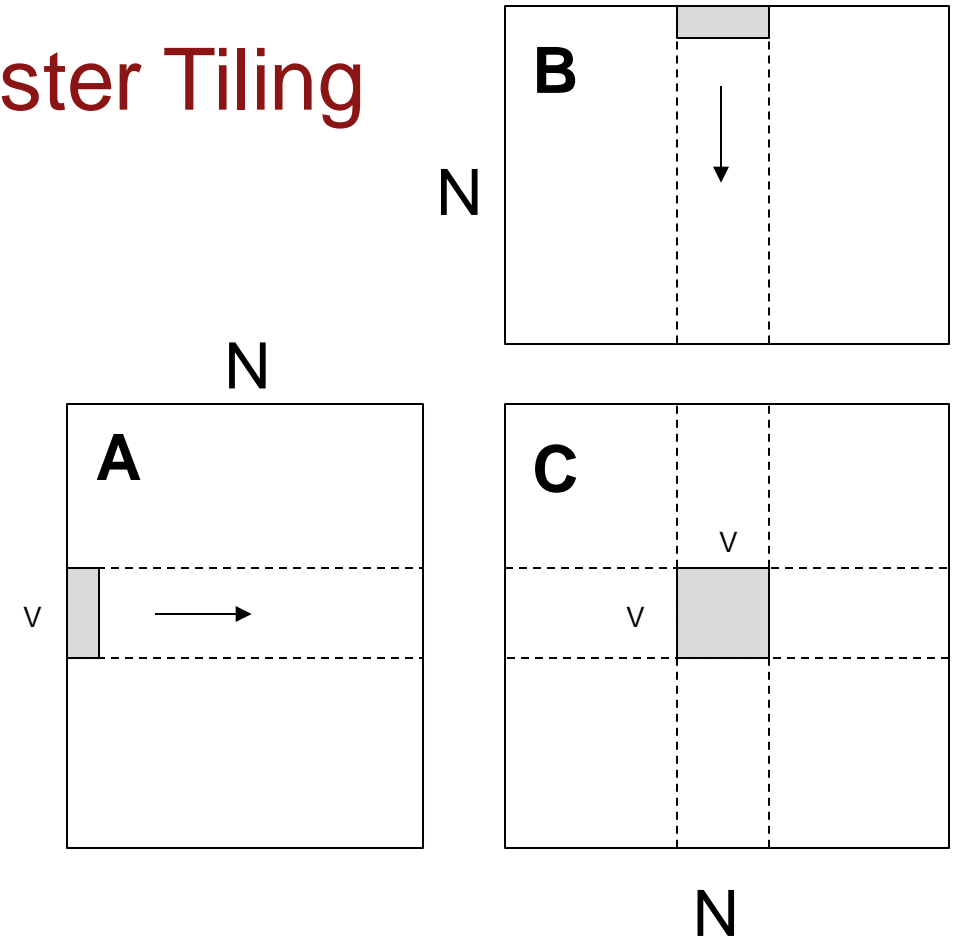


Global memory access per thread:  $2 \cdot N$   
Number of threads:  $N^2$   
**Total global memory access:  $2N^3$**

# Optimization 1: Thread-Level Register Tiling

- Compute  $C = A \times B$
- Each thread computes a  $V \times V$  submatrix

```
__global__ void mm(float A[N][N], float B[N][N], float C[N][N]) {  
    int ybase = blockIdx.y * blockDim.y + threadIdx.y;  
    int xbase = blockIdx.x * blockDim.x + threadIdx.x;  
  
    float c[V][V] = {0};  
    float a[V], b[V];  
    for (int k = 0; k < N; ++k) {  
        a[:] = A[xbase*V : xbase*V + V, k];  
        b[:] = B[k, ybase*V : ybase*V + V];  
        for (int y = 0; y < V; ++y) {  
            for (int x = 0; x < V; ++x) {  
                c[x][y] += a[x] * b[y];  
            }  
        }  
    }  
    C[xbase * V : xbase*V + V, ybase*V : ybase*V + V] = c[:];  
}
```



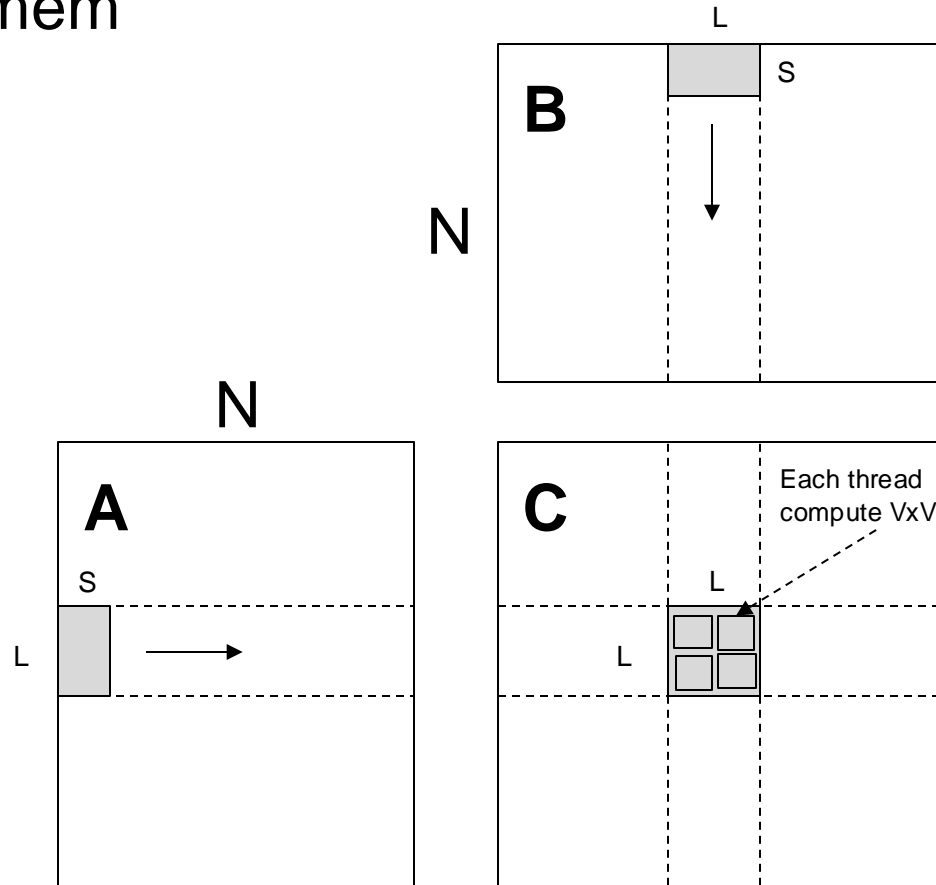
Global memory access per thread:  $2NV$

Number of threads:  $N^2/V^2$

**Total global memory access:  $2N^3/V$**

# Optimization 2: Block-Level Shared Memory Tiling

- A block computes a  $L \times L$  submatrix
- A thread computes a  $V \times V$  submatrix and reuses the matrices in shared mem

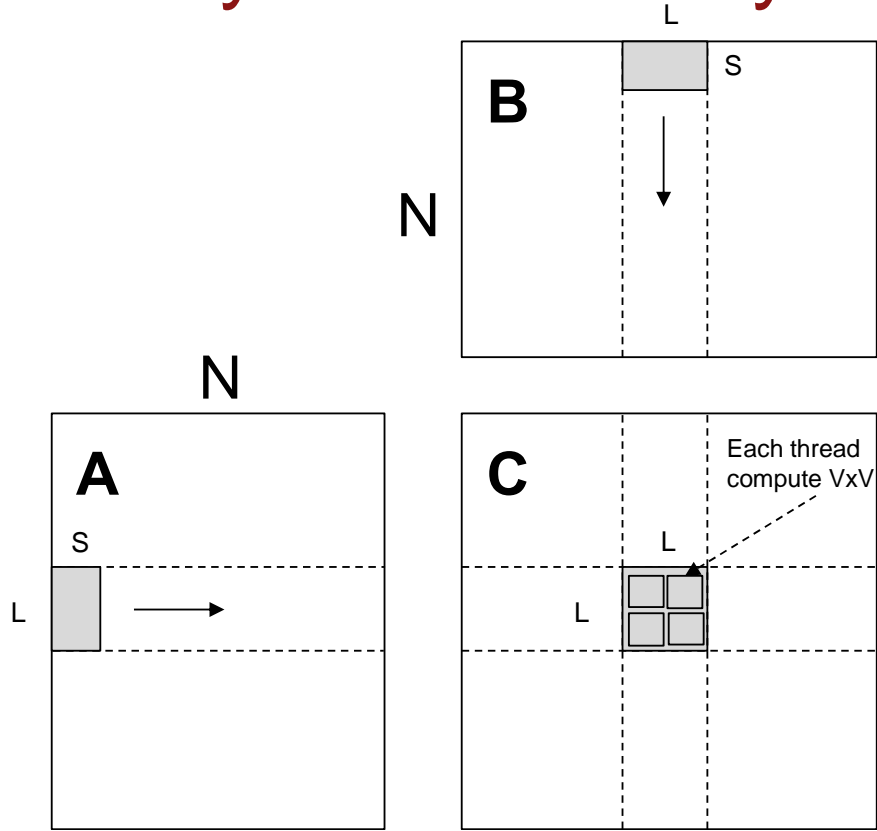


```

__global__ void mm(float A[N][N], float B[N][N], float C[N][N]) {
    __shared__ float sA[S][L], sB[S][L];
    float c[V][V] = {0};
    float a[V], b[V];
    int yblock = blockIdx.y;
    int xblock = blockIdx.x;

    for (int ko = 0; ko < N; ko += S) {
        __syncthreads();
        // needs to be implemented by thread cooperative fetching
        sA[:, :] = A[k : k + S, yblock * L : yblock * L + L];
        sB[:, :] = B[k : k + S, xblock * L : xblock * L + L];
        __syncthreads();
        for (int ki = 0; ki < S; ++ki) {
            a[:] = sA[ki, threadIdx.y * V : threadIdx.y * V + V];
            b[:] = sA[ki, threadIdx.x * V : threadIdx.x * V + V];
            for (int y = 0; y < V; ++y) {
                for (int x = 0; x < V; ++x) {
                    c[y][x] += a[y] * b[x];
                }
            }
        }
    }
    int ybase = blockIdx.y * blockDim.y + threadIdx.y;
    int xbase = blockIdx.x * blockDim.x + threadIdx.x;
    C[ybase * V : ybase * V + V, xbase * V : xbase * V + V] = c[:];
}
    
```

# Analysis of Memory Reuse



Global memory access per thread block:  $2LN$

Number of thread blocks:  $N^2/L^2$

**Total global memory access:  $2N^3/L$**

Shared memory access per thread:  $2VN$

Number of threads:  $N^2/V^2$

**Total shared memory access:  $2N^3/V$**

```

__global__ void mm(float A[N][N], float B[N][N], float C[N][N]) {
    __shared__ float sA[S][L], sB[S][L];
    float c[V][V] = {0};
    float a[V], b[V];
    int yblock = blockIdx.y;
    int xblock = blockIdx.x;

    for (int ko = 0; ko < N; ko += S) {
        __syncthreads();
        // needs to be implemented by thread cooperative fetching
        sA[:, :] = A[k : k + S, yblock * L : yblock * L + L];
        sB[:, :] = B[k : k + S, xblock * L : xblock * L + L];
        __syncthreads();
        for (int ki = 0; ki < S; ++ki) {
            a[:] = sA[ki, threadIdx.y * V : threadIdx.y * V + V];
            b[:] = sA[ki, threadIdx.x * V : threadIdx.x * V + V];
            for (int y = 0; y < V; ++y) {
                for (int x = 0; x < V; ++x) {
                    c[y][x] += a[y] * b[x];
                }
            }
        }
    }

    int ybase = blockIdx.y * blockDim.y + threadIdx.y;
    int xbase = blockIdx.x * blockDim.x + threadIdx.x;
    C[ybase * V : ybase * V + V, xbase * V : xbase * V + V] = c[:];
}
    
```

# Cooperative Fetching

```
sA[:, :] = A[k : k + S, yblock * L : yblock * L + L];
```



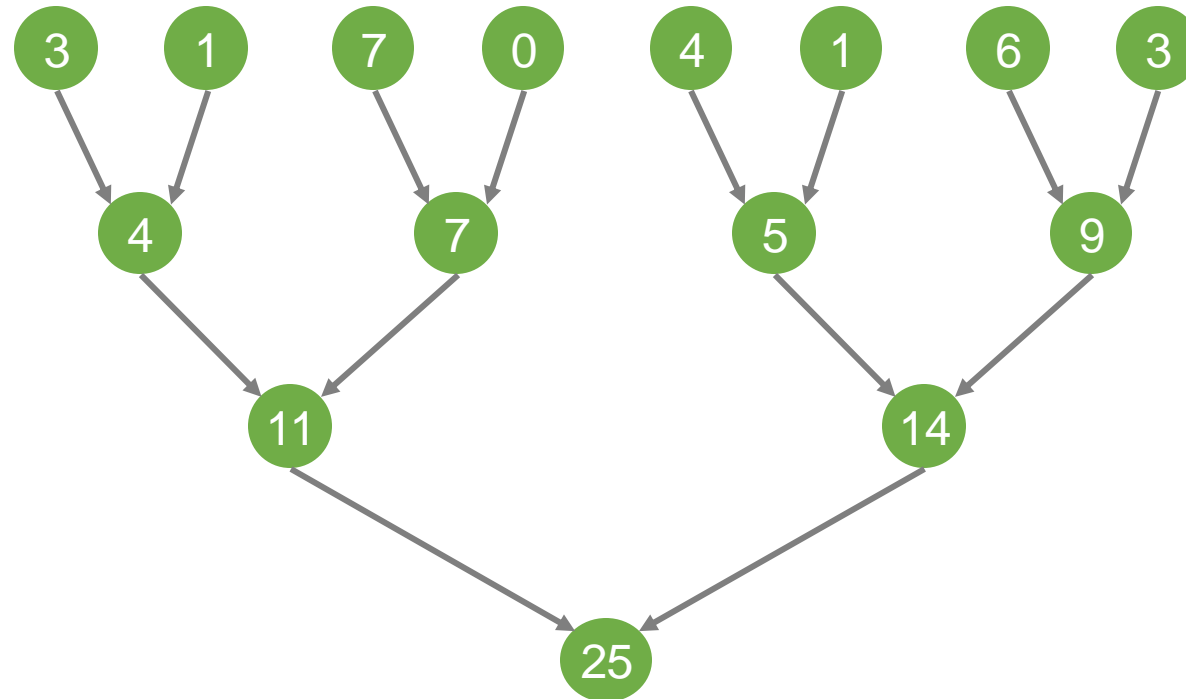
```
int nthreads = blockDim.y * blockDim.x;  
int tid = threadIdx.y * blockDim.x + threadIdx.x;  
  
for(int j = 0; j < L * S / nthreads; ++j) {  
    int y = (j * nthreads + tid) / L;  
    int x = (j * nthreads + tid) % L;  
    s[y, x] = A[k + y, yblock * L + x];  
}
```

# Outline

- CUDA Programming Abstractions
- CUDA Implementation on Modern GPUs
- Cast Study 1: Matrix Multiplication in CUDA
- **Cast Study 2: Parallel Reduction in CUDA**

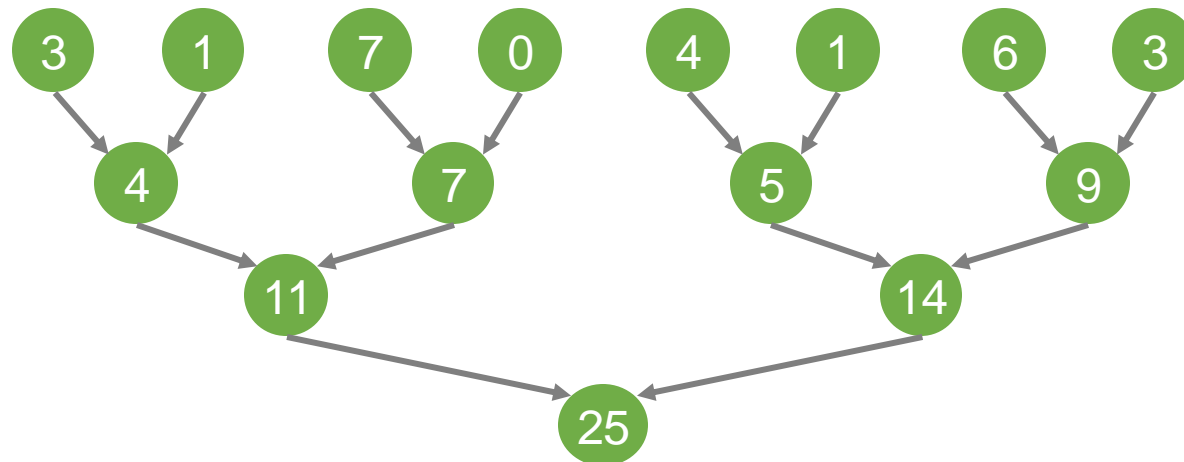
# Parallel Reduction

- Common and important primitive used by many ML Sys operators: normalization, softmax, etc
- Tree-based approach to reduce elements within each thread block



# Challenges of Parallel Reduction in CUDA

- Task: for a large array of n elements, compute  $\sum_{i=1}^n A[i]$
- To achieve high GPU utilization
  - Need to use multiple thread blocks (since a block is assigned to one SMM)
  - Each thread block reduces a portion of the array
- How to communicate partial results between thread blocks?





# Problem: CUDA has no Global Synchronization

**Recall CUDA assumption:** thread blocks can be executed in any order, cannot sync between them

Why?

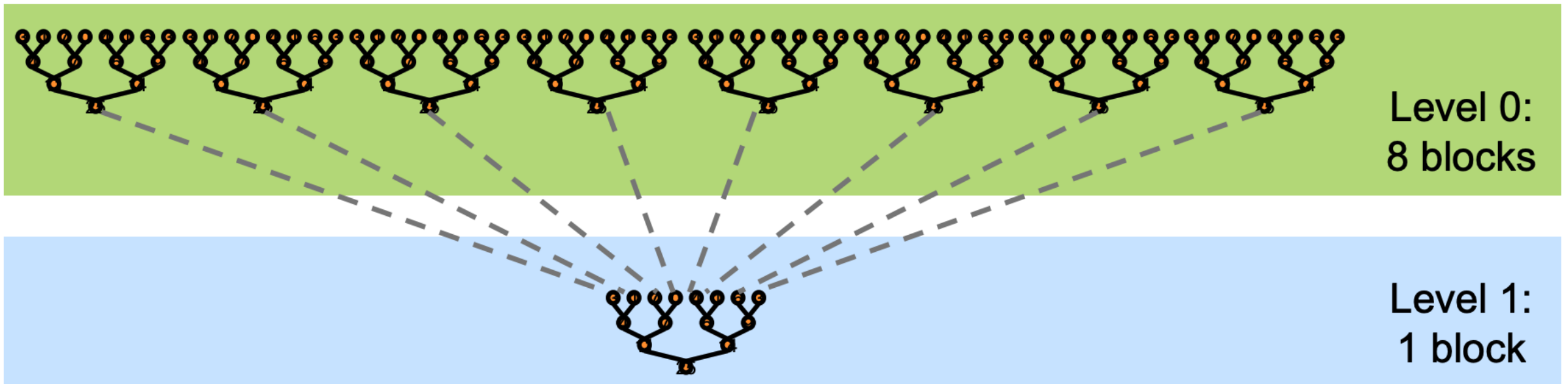
- Expensive to build hardware for GPUs with high processor count
- Potential deadlock when  $\# \text{ blocks} > \# \text{ multiprocessors} * \# \text{ resident blocks}$

Solution: decompose into multiple kernels

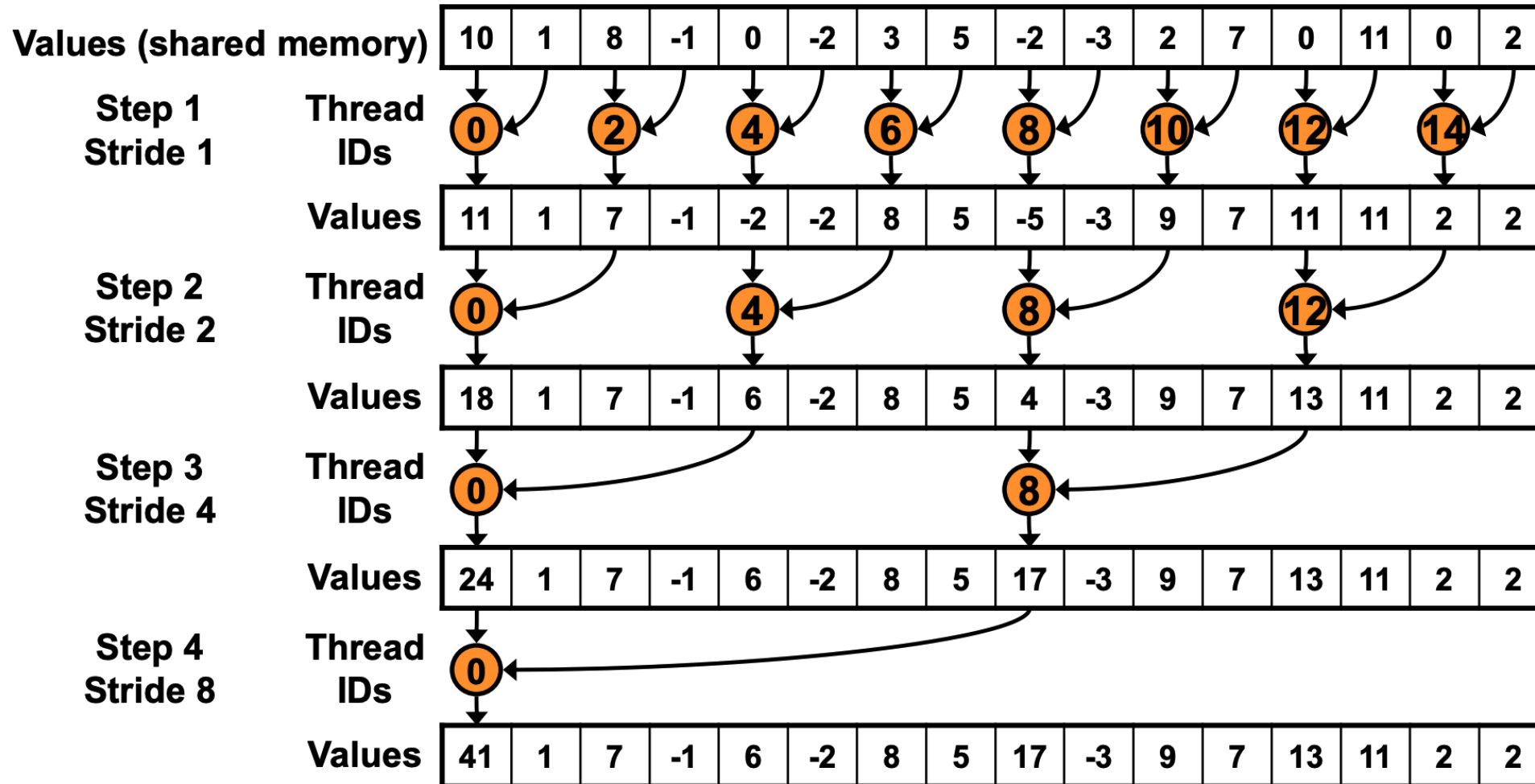
- Kernel launch serves a global synchronization
- Kernel launch has very low hardware/software overhead

# Solution: Kernel Decomposition

- Avoid global synchronization by decompose computation into multiple kernel invocations
- Code for all levels is the same



# Version 1: Interleaved Addressing



# Version 1: Interleaved Addressing

```
__global__ void reduce0(int *g_idata, int *g_odata) {  
    extern __shared__ int sdata[];
```

```
    // each thread loads one element from global to shared mem  
    unsigned int tid = threadIdx.x;  
    unsigned int i = blockIdx.x*blockDim.x + threadIdx.x;  
    sdata[tid] = g_idata[i];
```

```
    __syncthreads();
```

```
    // do reduction in shared mem  
    for(unsigned int s=1; s < blockDim.x; s *= 2) {  
        if (tid % (2*s) == 0) {  
            sdata[tid] += sdata[tid + s];  
        }  
    }
```

```
    __syncthreads();
```

```
    // write result for this block to global mem  
    if (tid == 0) g_odata[blockIdx.x] = sdata[0];  
}
```

Why we need the two  
\_\_syncthreads?

# Version 1: Interleaved Addressing

```
__global__ void reduce0(int *g_idata, int *g_odata) {  
    extern __shared__ int sdata[];
```

```
    // each thread loads one element from global to shared mem  
    unsigned int tid = threadIdx.x;  
    unsigned int i = blockIdx.x*blockDim.x + threadIdx.x;  
    sdata[tid] = g_idata[i];  
    __syncthreads();
```

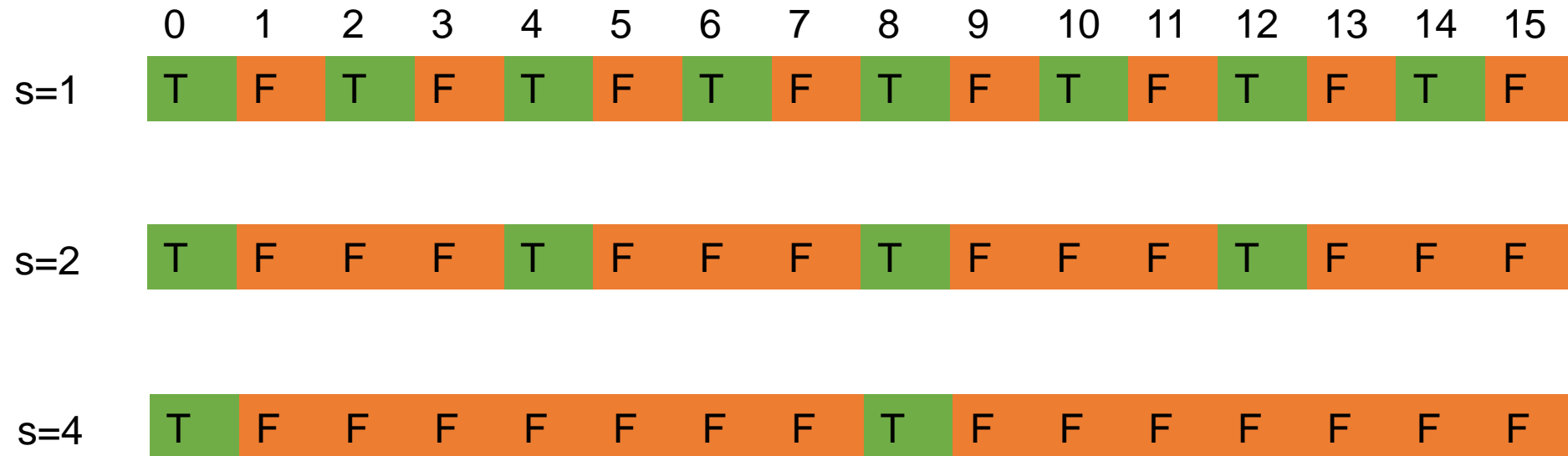
```
    // do reduction in shared mem  
    for(unsigned int s=1; s < blockDim.x; s *= 2) {  
        if (tid % (2*s) == 0) {  
            sdata[tid] += sdata[tid + s];  
        }  
        __syncthreads();  
    }
```

```
    // write result for this block to global mem  
    if (tid == 0) g_odata[blockIdx.x] = sdata[0];  
}
```

Problem: highly  
divergent warps

# Version 1: Divergent Warps

```
for(unsigned int s=1; s < blockDim.x; s *= 2) {  
  if (tid % (2*s) == 0)  
    sdata[tid] += sdata[tid + s];  
}
```



## Version 2: Strided Index and Non-divergent warp

Original  
Version

```
for(unsigned int s=1; s < blockDim.x; s *= 2) {  
    if (tid % (2*s) == 0) {  
        sdata[tid] += sdata[tid + s];  
    }  
    __syncthreads();  
}
```



Replace divergent branch with strided  
index and non-divergent branch

Optimized  
Version

```
for(unsigned int s=1; s < blockDim.x; s *= 2) {  
    int index = 2 *s * threadIdx.x;  
    if (index < blockDim.x) {  
        sdata[index] += sdata[index + s];  
    }  
    __syncthreads();  
}
```

## Version 2: Strided Index and Non-divergent warp

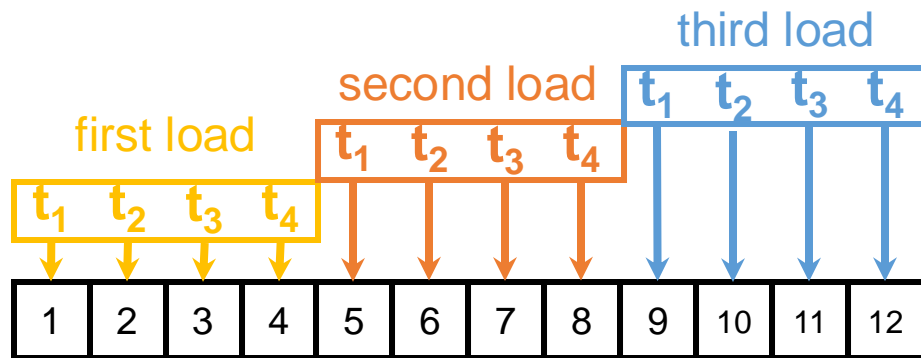
```
for(unsigned int s=1; s < blockDim.x; s *= 2) {  
    int index = 2 * s * threadIdx.x;  
    if (index < blockDim.x)  
        sdata[index] += sdata[index + s];  
}
```

	0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
s=1	T	T	T	T	T	T	T	T	F	F	F	F	F	F	F	F
s=2	T	T	T	T	F	F	F	F	F	F	F	F	F	F	F	F
s=4	T	T	F	F	F	F	F	F	F	F	F	F	F	F	F	F

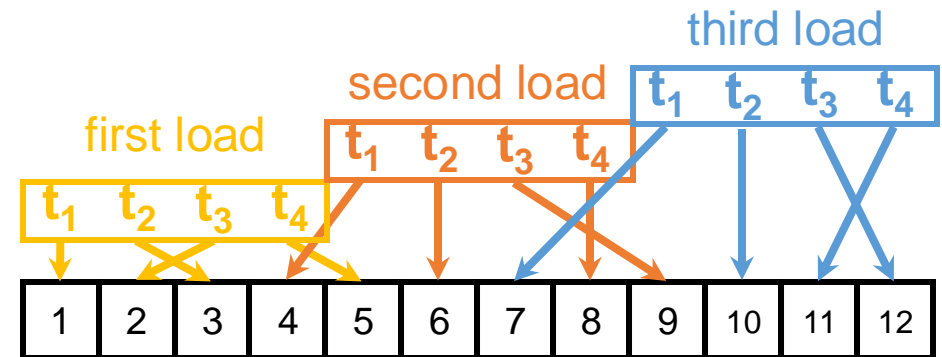


# Coalesced Memory Access

- Multiple GPU threads access **consecutive** memory addresses
- Maximize GPU memory usage

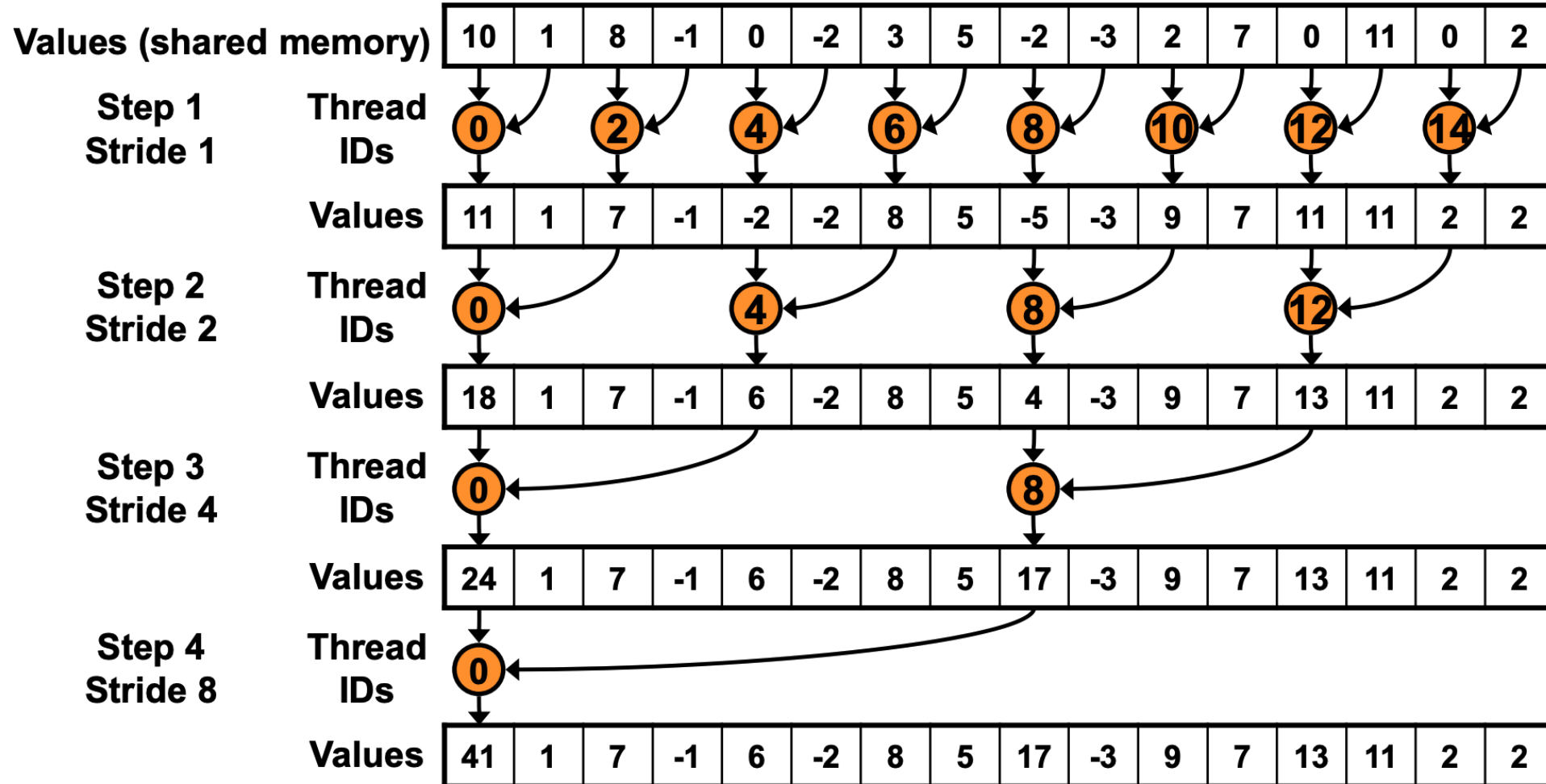


coalesced access (optimal usage)



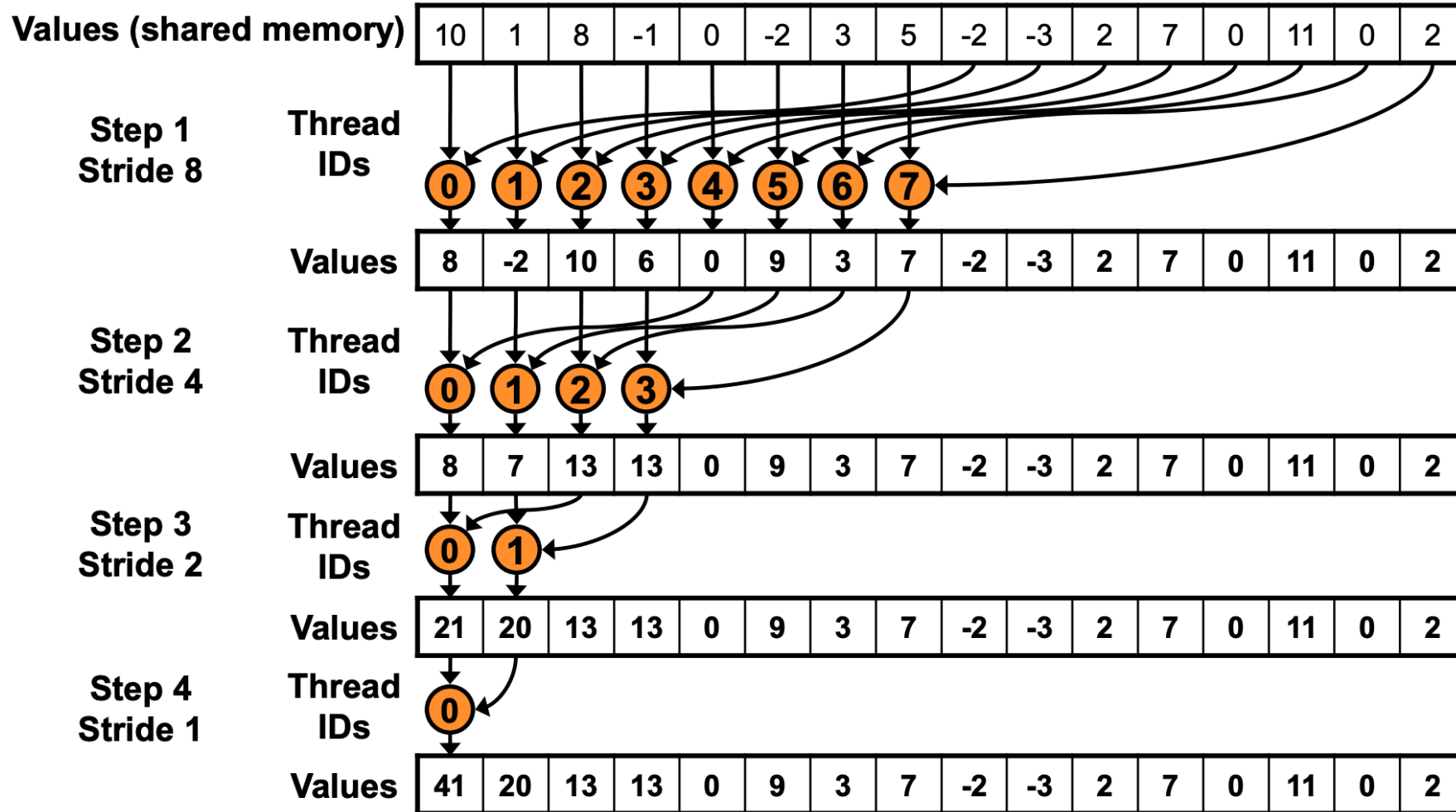
Non-coalesced access (suboptimal usage)

# Version 1: Interleaved Addressing



**Suboptimal memory accesses**

# Version 2: Sequential Addressing



Fully coalesced memory access

# Version 2: Sequential Addressing

Original  
Version

```
for(unsigned int s=1; s < blockDim.x; s *= 2) {  
    int index = 2 *s * threadIdx.x;  
    if (index < blockDim.x) {  
        sdata[index] += sdata[index + s];  
    }  
    __syncthreads();  
}
```



Replace strided index with reversed  
loop and threadIdx-based index

Original  
Version

```
for(unsigned int s=blockDim.x / 2; s > 0; s /= 2) {  
    if (threadIdx.x < s) {  
        sdata[threadIdx.x] += sdata[threadIdx.x + s];  
    }  
    __syncthreads();  
}
```

# Recap

- CUDA programming and GPU architecture
- GPU optimization techniques:
  - Coherence warps
  - Coalesced memory access
  - Shared memory bank conflict
  - Warp level optimizations
  - Tensor core