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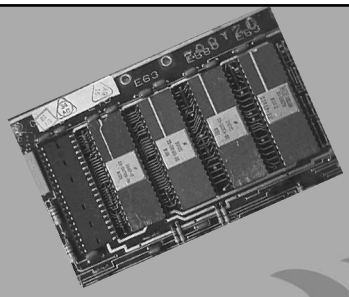
Lecture 10



Control Unit (*Ohjausyksikkö*)

Ch 15-16 [Sta09] (Sta06:16-17)

- Micro-operations
- Control signals (*Ohjaussignaalit*)
- Hardwired control (*Langoitettu ohjaus*)
- Microprogrammed control (*Mikro-ohjelmoitu ohjaus*)

What is control?

Functional requirements for CPU

1. Operations
2. Addressing modes
3. Registers
4. I/O module interface
5. Memory module interface
6. Interrupt processing structure

- Architecture determines the CPU functionality that is visible to 'programs'
  - What is the instruction set ?
  - What do instructions do?
  - What operations, opcodes?
  - Where are the operands?
  - How to handle interrupts?
- Control Unit, CU (*ohjausyksikkö*) determines how these things happen in hardware (CPU, MEM, bus, I/O)
  - What gate and circuit should do what at any given time
  - Selects and gives the control signals to circuits in order
  - Physical control wires transmit the control signals
    - Timed by clock pulses
    - Control unit decides values of the signals

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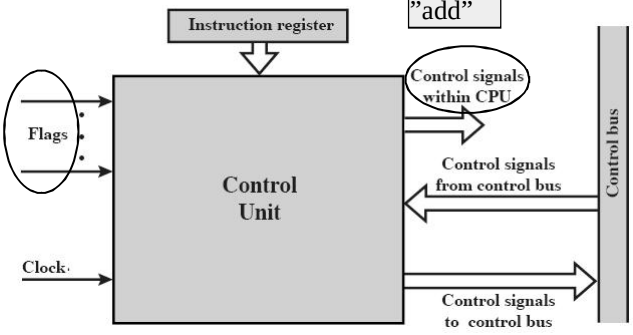
Control signals

"read"
"write"
"add"

(Sta09 Fig 15.4)
(Sta06 Fig 16.4)



- Main task: control data transfers
  - Inside CPU: REG ⇔ REG, ALU ⇔ REG, ALU-ops
  - CPU ⇔ MEM (I/O-controller): address, data, control
- Timing (*ajoitus*), Ordering (*järjestys*)

Micro-operations

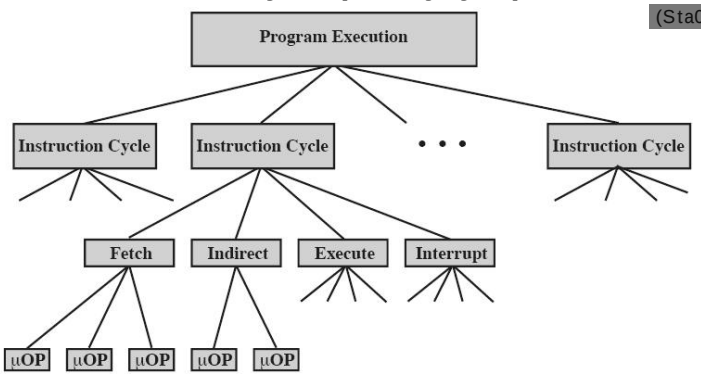
- Simple control signals that cause one very small operation (*toiminto*)
  - E.g. Bits move from reg 1 through internal bus to ALU
- Subcycle duration determined from the longest operation
- During each subcycle multiple micro-operations in action
  - Some can be done simultaneously, if in different parts of the circuits
  - Must avoid resource conflicts
    - WAR or RAW, ALU, bus
  - Some must be executed sequentially to maintain the semantics

t1: MAR ← PC
t2: MBR ← MEM[MAR]
PC ← PC + 1
t3: IR ← (MBR)

If implemented without ALU

Instruction cycle (Käskysykli)

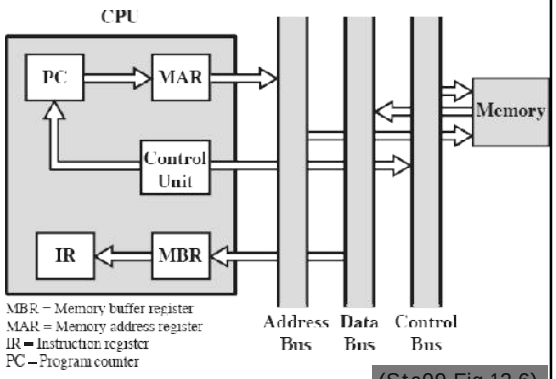
(Sta09 Fig 15.1)
(Sta06 Fig 16.1)



- When micro-operations address different parts of the hardware, hardware can execute them parallel
- See Chapter 12 instruction cycle examples (next slide)

Instruction fetch cycle (*Käskyn noutosykli*)

Example:
t1: MAR ← PC
t2: MAR ← MMU(MAR)
Control Bus ← Reserve
wait?
t3: Control Bus ← Read
PC ← PC + 1
t4: MBR ← MEM[MAR]
Control Bus ← Release
t5: IR ← MBR



(Sta09 Fig 12.6)

Execution order? What can be executed parallel? Which micro-ops to same subcycle, which need own cycle?

Instruction cycle

- Operand fetch cycle(s)
  - From register or from memory
  - Address translation
- Execute cycle(s)
  - Execution often in ALU
  - Operands in and control operation
  - Result from output to register /memory
  - flags ← status
- Interrupt cycle(s)
  - See examples (Ch 12): Pentium
  - What to do using same micro-operation?
  - What micro-ops parallel / sequentially?

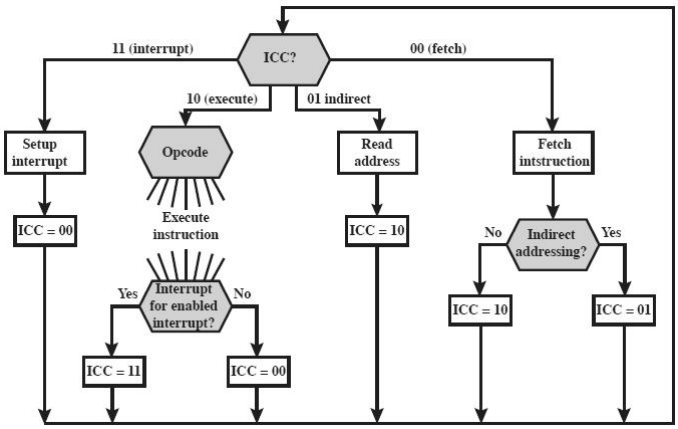
ADD r1,r2,r3:
t1: ALUin1 ← r2
t2: ALUin2 ← r3
ALUoper ← IR.oper
t3: r1 ← ALUout
flags ← xxx

ISZ X, Increment and Skip if zero:
t1: MAR ← IR.address
t2: MBR ← MEM[MAR]
t3: MBR ← MBR+1
t4: MEM[MAR] ← MBR
if (MBR=0) then PC ← PC +1

Conditional operation possible

Instruction cycle flow chart (as state-machine?)

- ICC: Instruction Cycle Code register 's state

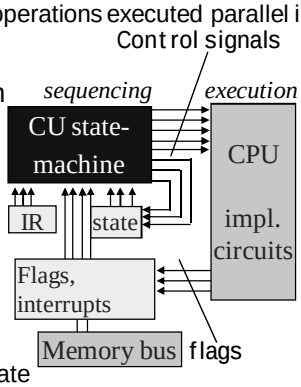


(Sta09 Fig 15.3)

(Sta06 Fig 16.3)

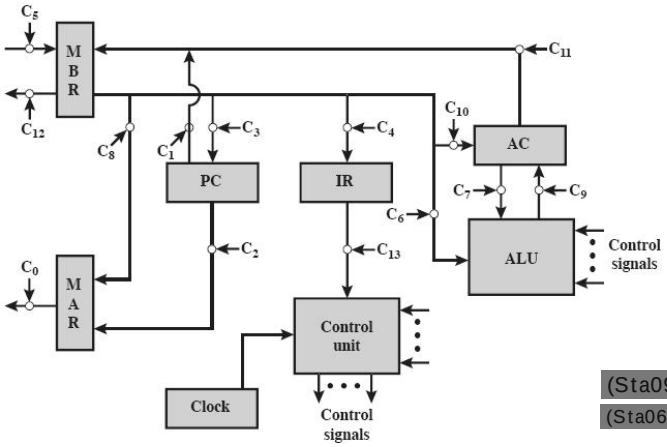
Instruction cycle control as state-machine (*tila-automaatti)*

- Functionality of Control Unit can be presented as state-machine
  - State: What stage of the instruction cycle is going on in CPU
  - Substate: timing based, group of micro-operations executed parallel in one (sub)cycle
- Control signals of substate are based on
  - (sub)state itself
  - Fields of IR-register (opcode, operands)
  - Previous results (flags)
    = Execution
- New state based on previous state and flags
  - Also external interrupts effect the new state
    = Sequencing



Control signals

- Micro-operation ⇨ CU emits a set of control signals
- Example: processor with single accumulator



(Sta09 Fig 15.5)
(Sta06 Fig 16.5)

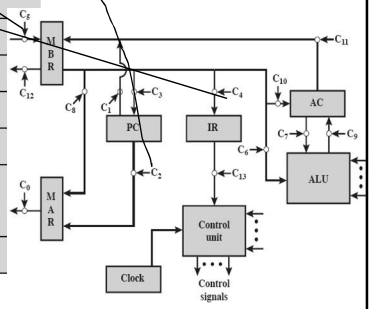
Control signals and micro-operations

Micro-operations	Timing	Active Control Signals
Fetch:	t_1: MAR ← (PC)	C_2
	t_2: MBR ← Memory PC ← (PC) + 1	C_5, C_R ??
	t_3: IR ← (MBR)	C_4
Indirect:	t_1: MAR ← (IR(Address))	C_8
	t_2: MBR ← Memory	C_5, C_R
	t_3: IR(Address) ← (MBR(Address))	C_4
Interrupt:	t_1: MBR ← (PC)	C_1
	t_2: MAR ← Save-address PC ← Routine-address	??
	t_3: Memory ← (MBR)	C_{12}, C_W

C_R = Read control signal to system bus.
C_W = Write control signal to system bus.

Sta09 Fig 15.5

Sta06 Fig 16.5

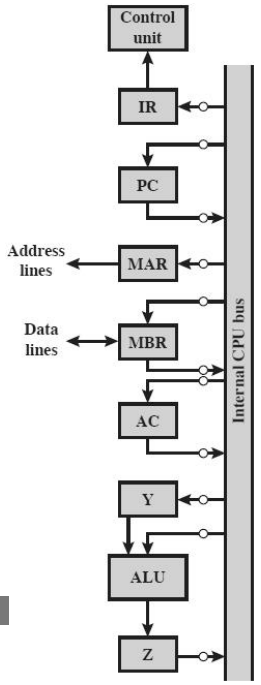


(Sta09 Table 15.1) (Sta06 Table 16.1)

Internal Processor Organization

- Fig 15.5 too complex for implementation
- Use internal processor bus to connect the components
- ALU usually has temporary registers Y and Z

ADD I:
t1: MAR ← IR.address
t2: MBR ← MEM[MAR]
t3: Y ← MBR
t4: Z ← AC + Y
t5: AC ← Z



(Sta09 Fig 15.6)

(Sta06 Fig 16.6)

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Hardwired implementation

(*Langoitettu ohjaus*)

Hardwired control unit (*Langoitettu ohjausyksikkö*)

- Can be used when CU's inputs and outputs fixed
  - Functionality described using Boolean logic
  - CU implemented by one logical circuit
- Eg. C5 = $\overline{P}$*$\overline{Q}$*T2 + $\overline{P}$*Q*(LDA)*T2 + ...

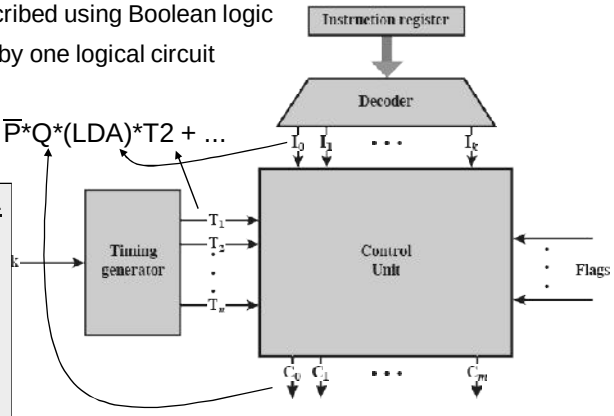


Fig 15.3, 15.5 and Tbl 15.1

ICC - bits P and Q

PQ = 00 Fetch Cycle

PQ = 01 Indirect Cycle

PQ = 10 Execute Cycle

PQ = 11 Interrupt Cycle

(Sta09 Fig 15.10)

(Sta06 Fig 16.10)

Hardwired control unit

(Sta09 Table 15.3)

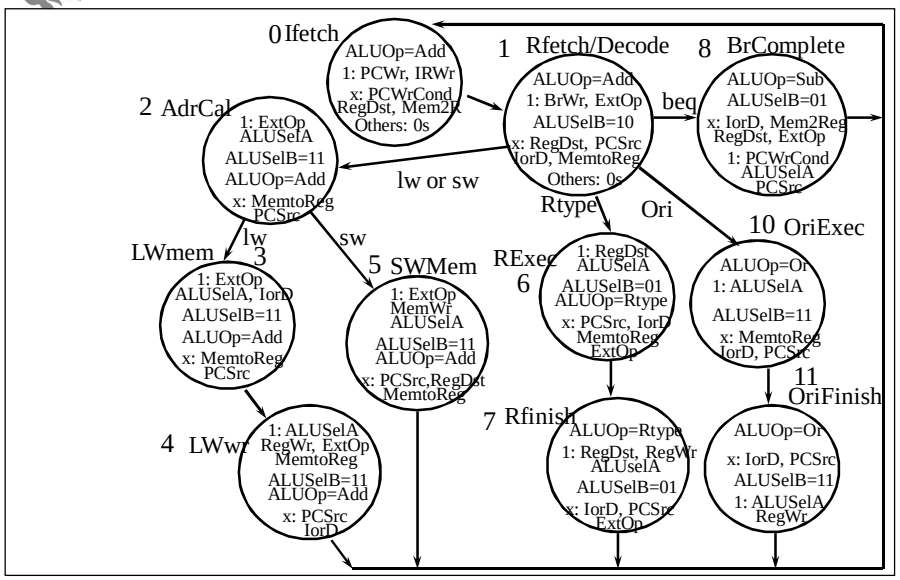
(Sta06 Table 15.3)

- Decoder (4-to-16)
  - 4-bit instruction code as input to CU
  - Only one signal active at any given stage

I1	I2	I3	I4	O1	O2	O3	O4	O5	O6	O7	O8	O9	O10	O11	O12	O13	O14	O15	O16
0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1
0	0	0	1	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0
0	0	1	0	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0	0
0	0	1	1	0	0	0	0	0	0	0	0	0	0	0	0	1	0	0	0
0	1	0	0	0	0	0	0	0	0	0	0	0	0	0	1	0	0	0	0
0	1	0	1	0	0	0	0	0	0	0	0	0	0	1	0	0	0	0	0
0	1	1	0	0	0	0	0	0	0	0	0	0	1	0	0	0	0	0	0
0	1	1	1	0	0	0	0	0	0	0	0	1	0	0	0	0	0	0	0
1	0	0	0	0	0	0	0	0	0	0	1	0	0	0	0	0	0	0	0
1	0	0	1	0	0	0	0	0	0	1	0	0	0	0	0	0	0	0	0
1	0	1	0	0	0	0	0	0	1	0	0	0	0	0	0	0	0	0	0
1	0	1	1	0	0	0	0	1	0	0	0	0	0	0	0	0	0	0	0
1	1	0	0	0	0	0	1	0	0	0	0	0	0	0	0	0	0	0	0
1	1	0	1	0	0	1	0	0	0	0	0	0	0	0	0	0	0	0	0
1	1	1	0	0	1	0	0	0	0	0	0	0	0	0	0	0	0	0	0
1	1	1	1	1	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0

C5: opcode = 5 (bits I1, I2, I3, I4) ⟶ signal O11 is true (1)

Finite State Diagram



State transitions (2)

Next state from current state

- State 0 -> State1
- State 1 -> S2, S6, S8, S10
- State 2 -> S5 or ...
- State 3 -> S9 or ...
- State 4 ->State 0
- State 5 -> State 0
- State 6 -> State 7
- State 7 -> State 0
- State 8 -> State 0
- State 9-> State 0
- State 10 -> State 11
- State 11 -> State 0

Alternatively,
prior state & condition

S4, S5, S7, S8, S9, S11	-> State0
_____	-> State1
_____	-> State 2
_____	-> State 3
_____	-> State 4
State2 & op = SW	-> State 5
_____	-> State 6
State 6	-> State 7
_____	-> State 8
State3 & op = JMP	-> State 9
_____	-> State 10
State 10	-> State 11

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Hardwired control

- Control signal generation in hardware is fast
- Weaknesses
  - CU difficult to design
    - Circuit can become large and complex
  - CU difficult to modify and change
    - Design and 'minimizing' must be done again
- RISC-philosophy makes it a bit easier
  - Simple instruction set makes the design and implementation easier

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Microprogrammed control (*Mikro-ohjelmoitu ohjaus*)

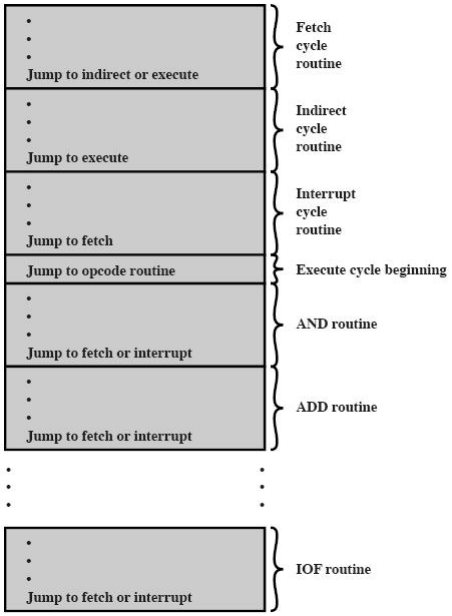
Microprogrammed control (*Mikro-ohjelmoitu ohjaus*)

- Idea 1951: Wilkes Microprogrammed Control
- Execution Engine
  - Execution of one machine instruction (or micro-operation) is done by executing a sequence of microinstructions
  - Executes each microinstruction by generating the control signals indicated by the instruction
- Micro-operations stored in control memory as microinstructions
  - Firmware *(laiteohjelmisto)*
- Each microinstruction has two parts
  - What will be done during the next cycle?
    - Microinstruction indicates the control signals
    - Deliver the control signals to circuits
  - What is the next microinstruction?
    - Assumption: next microinstruction from next location
    - Microinstruction can contain the address location of next instruction!

Sta09 Table 15.1 (slide 11)

Microinstructions

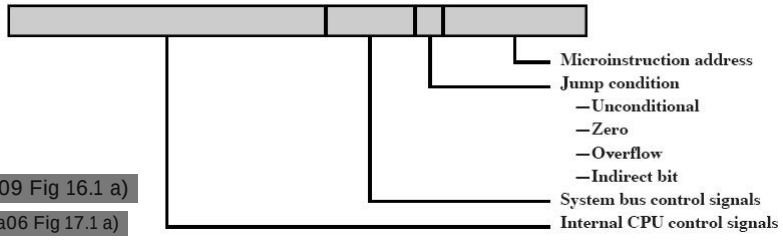
- Each stage in instruction execution cycle is represented by a sequence of microinstructions that are executed during the cycle in that stage
- E.g. In ROM memory
  - **Microprogram or firmware**



(Sta09 Fig 16.2)
(Sta06 Fig 17.2)

Horizontal microinstruction

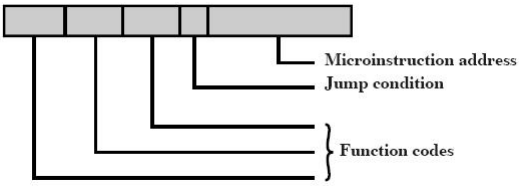
- All possible control signals are represented in a bit vector of each microinstruction
  - One bit for each signal (1=generate, 0=do not generate)
  - Long instructions if plenty of signals used
- Each microinstruction is a conditional branch
  - What status bit(s) checked
  - Address of the next microinstruction



(Sta09 Fig 16.1 a)
(Sta06 Fig 17.1 a)

Vertical microinstruction

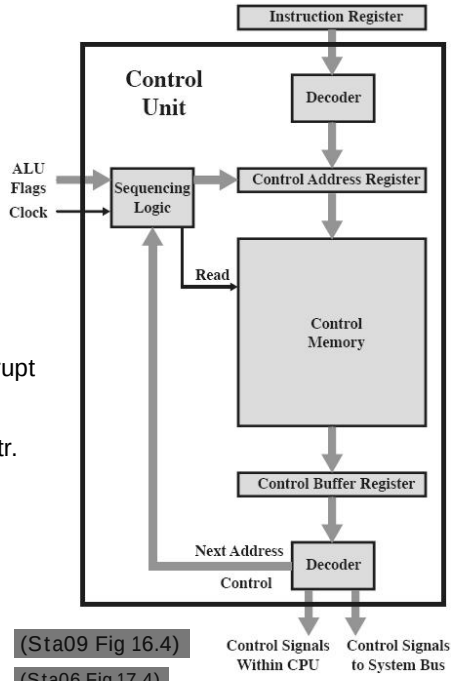
- Control signals coded to number
- Decode back to control signals during execution
- Shorter instructions, but decoding takes time
- Each microinstruction is conditional branch (as with horizontal instructions)



(Sta09 Fig 16.1 b)
(Sta06 Fig 17.1 b)

Execution Engine (*Ohjausyksikkö*)

- Control Address Register, CAR
  - Which microinstruction next?
  - ~ instr. pointer, "MiPC"
- Control memory
  - Microinstructions
    - fetch, indirect,execute,interrupt
- Control Buffer Register, CBR
  - Register for executing microinstr.
  - ~ instr. register, "MiIR"
  - Generate the signals to circuits
    - Verticals through decoder
- Sequencing Logic
  - Next address to CAR

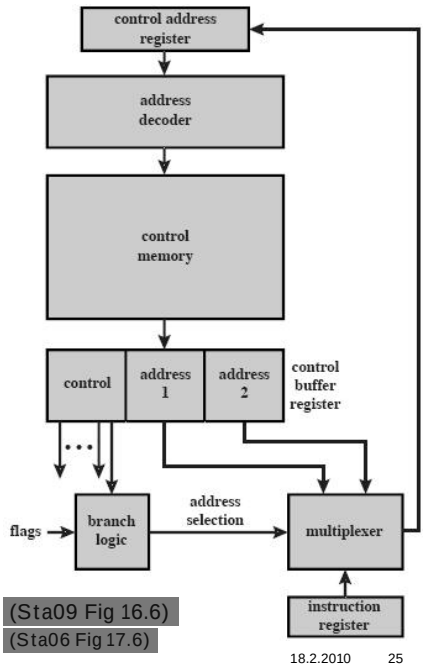


(Sta09 Fig 16.4)
(Sta06 Fig 17.4)

What microinstruction next?

a) Explicit

- Each instruction has 2 addresses
  - with the conditions flags that are checked for branching
  - Next instruction from either address (select using the flags)
  - Often just the next location in control memory
    - Why store the address?
    - No time for addition!

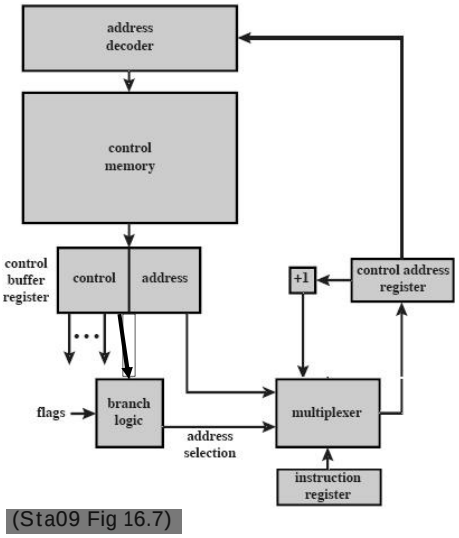


(Sta09 Fig 16.6)
(Sta06 Fig 17.6)

What microinstruction next?

b) Implicit

- Assumption: next microinstruction from next location in control memory
  - Must be calculated
- instruction has 1 address
  - Still need the condition flags
  - If condition=1, use the address
- Address part not always used
  - Wasted space

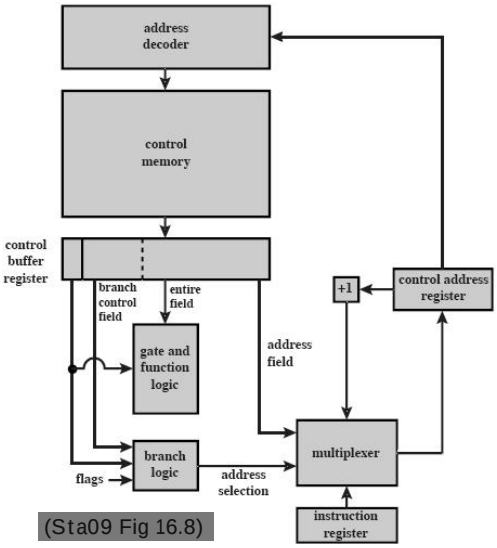


(Sta09 Fig 16.7)
(Sta06 Fig 17.7)

What microinstruction next?

c) Variable format

- Some bits interpreted in two ways
  - 1 b: Address or not
  - Only branch instructions have address
  - Branch instructions do not have control signals
  - If jump, need to execute two microinstructions instead of just one
    - Wasted time?
    - Saved space?



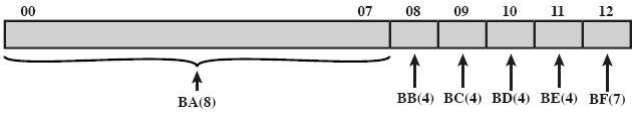
(Sta09 Fig 16.8)

(Sta06 Fig 17.8)

What microinstruction next?

d) Address generation during execution

- How to locate the correct microinstruction routine?
  - Control signals depend on the current machine instruction
- Generate first microinstruction address from op-code (mapping + combining/adding)
  - Most-significant bits of address directly from op-code
  - Least-significant bits based on the current situation (0 or 1)
  - Example: IBM 3033 CAR, 13 bit address
    - Op-code gives 8 bits -> each sequence 32 micro-instr.
    - rest 5 bits based on the certain status bits



(Sta09 Fig 16.9)

(Sta06 Fig 17.9)

What microinstruction next?

e) Subroutines and residual control

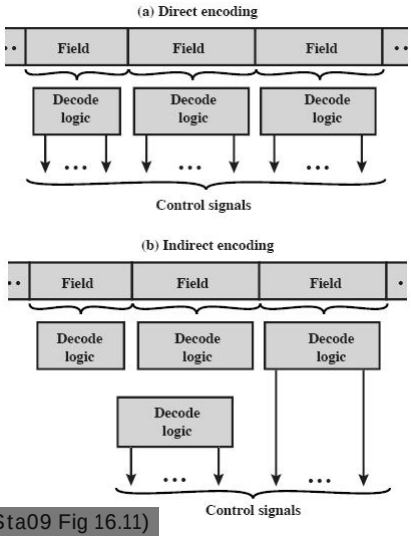
- Microinstruction can set a special return register with 'return address'
  - No context, just one return allowed (one-level only)
  - No nested structure
  - Example: LSI-11, 22 bit microinstruction
    - Control memory 2048 instructions, 11 bit address
    - OP-code determines the first microinstruction address
    - Assumption, next is CAR ← CAR+1
    - Each instruction has a bit: subroutine call or not
    - Call:
      - Store return address (only the latest one available)
      - Jump to the routine (address in the instruction)
    - Return: jump to address in return register

Microinstruction coding

- Horizontal? Vertical?
  - Horizontal: fast interpretation
  - Vertical: less bits, smaller space
- Often a compromize, using mixed model
  - Microinstruction split to fields, each field is used for certain control signals
  - Excluding signal combinations can be coded in the same field
    - NOT: Reg source and destination, two sources – one dest
  - Coding decoded to control signals during execution
    - One field can control decoding of other fields!
- Several shorter coded fields easier for implementation than one long field
  - Several simple decoders

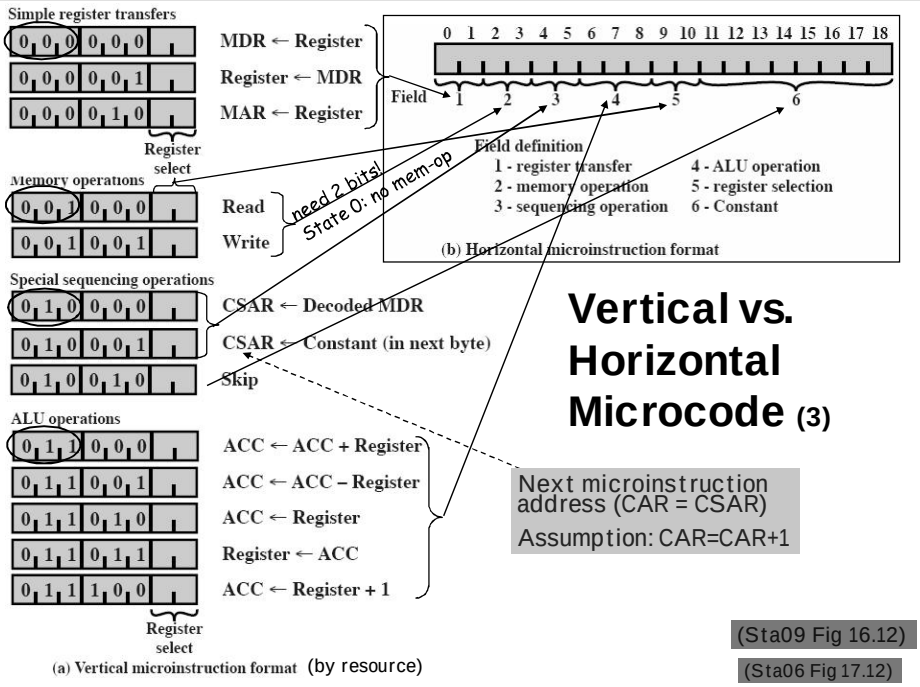
Microinstruction coding

- Functional encoding (*toiminnoittain*)
  - Each field controls one specific action
    - Load from accumulator
    - Load from memory
    - Load from ...
- Resource encoding (*resursseittain*)
  - Each field controls specific resource
    - Load from accumulator
    - Store to accumulator
    - Add to accumulator
    - … accumulator



(Sta09 Fig 16.11)

(Sta06 Fig 17.11)



Vertical vs. Horizontal Microcode (3)

Next microinstruction address (CAR = CSAR)

Assumption: CAR=CAR+1

(Sta09 Fig 16.12)

(Sta06 Fig 17.12)

Why microprogrammed control?

- ..even when its slower than hardwired control
- Design is simple and flexible
  - Modifications (e.g. expansion of instruction set) can be added very late in the design phase
  - Old hardware can be updated by just changing control memory
    - Whole control unit chip in older machines
  - There exist development environments for microprograms
- Backward compatibility
  - Old instruction set can be used easily
  - Just add new microprograms for new machine instructions
- Generality
  - One hardware, several different instruction sets
  - One instruction set, several different organizations

Review Questions / Kertauskysymyksiä

- Hardwired vs. Microprogrammed control?
- How to determine the address of microinstruction?
- What is the purpose of control memory?
- Horizontal vs. vertical microinstruction?
- Why not to use microprogrammed control?
- Microprogrammed vs. hardwired?

- Langoitettu vs. mikro-ohjelmoitu toteutus?
- Kuinka mikrokäskyn osoite määräytyy?
- Mihin tarvitaan kontrollimuistia?
- Horisontaalinen vs. vertikaalinen mikrokäsky?
- Miksi ei mikro-ohjelmointia?
- Mikro-ohjelmointi vs. langoitettu kontrolli?