Vector operations, tiled operations, distributed execution, task graphs, ... What next?

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Vector operations, tiled operations, distributed execution, task graphs, ...

What next?

Samuel Thibault, University of Bordeaux
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High-Performance Computing

- Frontier supercomputer
- #1 on top500.org LINPACK benchmark
- 1.102 EFlop/s
- 9472 nodes
  - 1 AMD Epyc CPU
  - 4 AMD Instinct 250X GPUs
  - 4TB flash memory
  - Infinity Fabric interconnect
- Slingshot 100GB/s network
- 21.1 MW
- Also #1 Green 500
High-Performance Computing

Classical parallel programming

- threads
High-Performance Computing

Classical parallel programming

• threads
• MPI+threads
High-Performance Computing

Classical parallel programming

• threads
• MPI+threads
• MPI+threads+GPU
High-Performance Computing

Classical parallel programming

• threads
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• Data transfers
High-Performance Computing

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Classical parallel programming

• threads
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• MPI+threads+GPU
• Data transfers
• Disk storage
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Classical parallel programming
- threads
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- MPI+threads+GPU
- Data transfers
- Disk storage
Manage it all by hand?!

https://starpu.gitlabpages.inria.fr/
High-Performance Computing

Classical parallel programming
- threads
- MPI+threads
- MPI+threads+GPU
- Data transfers
- Disk storage

Manage it all by hand?!

Need high-level abstractions
Cholesky ($\mathbf{A} = \mathbf{L}\mathbf{L}^\mathrm{T}$)
Cholesky (A = L.L^T)
Cholesky ($A = L.L^T$)
Cholesky ($A = L.L^T$)
Cholesky ($A = L.L^T$)
Cholesky (A = L.Lᵀ)
Cholesky \( (A = L.L^T) \)
Cholesky, LINPACK

Vector computers (end ‘70s, ‘80s)
Cholesky, LINPACK

Vector computers (end ‘70s, ‘80s)
Cholesky, LINPACK

Vector computers (end ‘70s, ‘80s)
Cholesky, LINPACK

Vector computers (end ‘70s, ‘80s)
Cholesky, LAPACK

Computers with cache (early ‘90s-today), blocked operations : BLAS
Cholesky, LAPACK

Computers with cache (early ‘90s-today), blocked operations : BLAS
Cholesky, LAPACK

Computers with cache (early ‘90s-today), blocked operations : BLAS
Cholesky, LAPACK

Computers with cache (early ‘90s-today), blocked operations : BLAS
Cholesky, ScaLAPACK

Distributed Computers (late ‘90s-today), 2D-block-cyclic distribution
Cholesky, ScaLAPACK

Distributed Computers (late ‘90s-today), 2D-block-cyclic distribution
Cholesky, ScaLAPACK

Distributed Computers (late ‘90s-today), 2D-block-cyclic distribution
Cholesky, ScaLAPACK

Distributed Computers (late ‘90s-today), 2D-block-cyclic distribution
Cholesky, PLASMA

Task graph (~’08-today)
Cholesky, PLASMA

Task graph (~’08-today)
Cholesky, PLASMA

Task graph (~’08-today)
Cholesky, PLASMA

Task graph (~’08-today)
Cholesky, PLASMA

Task graph (~’08-today)
Cholesky, PLASMA

Task graph (~’08-today)
Cholesky, PLASMA

Task graph (~’08-today)
Cholesky, PLASMA

Task graph (~’08-today)
Cholesky, PLASMA

Task graph (~’08-today), **priorities**
Cholesky, PLASMA

Task graph (~’08-today), \textit{priorities}
Cholesky, PLASMA

Task graph (~’08-today), priorities
Task graphs in HPC

Runtime systems
• OmpSs, PARSEC, StarPU, SuperGlue/DuctTeip, XKaapi...

Standards
• OpenMP4.0 introduced task dependencies

Applications
• Chameleon, DPLASMA, SLATE for dense linear algebra
• qr_mumps, PaStiX for sparse linear algebra
• ScalFMM for FMM
• …
Task-based support

- Task/data scheduling
  - Load balancing
  - Data prefetching
  - Pipelining
  - GPU memory limitation management
- Distributed execution through MPI
- Out-of-core: optimized swapping to disk
- High-level performance analysis
- Performance bounds
- Debugging sequential execution
- Reproducible performance simulation

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How big should a task be?

- Small enough to get parallelism to **feed** all processing units
- Large enough to **efficiently** use the processing units
How big should a task be?

From PARSEC: « Hierarchical DAG Scheduling for Hybrid Distributed Systems », Wu, Bouteiller, Bosilca, Faverge, Dongarra
How big should a task be?

GPUs
• Efficient only with large tile sizes

CPUs
• Need many tasks

→ **Hybrid** task size

More generally, **hierarchical** task graphs
• Seen in CEA, OmpSs, PaRSEC, StarPU
Outline

• How big should a task be?
• Hierarchical task graphs
• Opportunities
How big should a task be?
How big should a task be?

- Lower bound due to runtime overhead
  - Proposed by Martin Tillenius for DuctTeip (U. Uppsala)
How big should a task be?

From PARSEC: « Hierarchical DAG Scheduling for Hybrid Distributed Systems », Wu, Bouteiller, Bosilca, Faverge, Dongarra
How big should a task be?

GPUs

• Have **thousands** for cores to feed
• Newer generations require yet larger sizes
• Can run several kernels at the same time
  • Still limited
How big should a task be?

From PARSEC: « Hierarchical DAG Scheduling for Hybrid Distributed Systems », Wu, Bouteiller, Bosilca, Faverge, Dongarra

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How big should a task be?

CPUs

• Have many independent cores
  → Need many tasks

• Can use parallel implementations (e.g. from MKL)
  • But better have subtasks to interleave them
How big should a task be?

How size does not fit all

Gwenolé Lucas experimented with Chameleon

- Cholesky inversion
- 2 NVIDIA V100
- 2 Xeon Gold 6142
- Different matrix tile sizes: 2880 / 960 / 320
Hybrid tile sizes

Version: Tile sizes

- **Non-Hierarchical**: 2880, 960, 320
- **Hierarchical**: 2880 / 960 / 320
How big should a task be?

Tuning the tile size?

- **B** = “big” tile size, for GPUs
  - Large enough for GPUs
  - Not too large for parallelism

- **b** = “small” tile size, for CPUs
  - Large enough for CPUs
  - Not too large for parallelism

With Parsec, Wu, Bouteiller, Bosilca, Faverge and Dongarra experimented tuning
How big should a task be?

From PARSEC : « Hierarchical DAG Scheduling for Hybrid Distributed Systems », Wu, Bouteiller, Bosilca, Faverge, Dongarra

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How big should a task be?

![Graph showing performance of hybrid DOTRF on Bunsen](https://starpu.gitlabpages.inria.fr/)

From PARSEC: « Hierarchical DAG Scheduling for Hybrid Distributed Systems », Wu, Bouteiller, Bosilca, Faverge, Dongarra

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How big should a task be?

From CEA: « A hierarchical fast direct solver for distributed memory machines with manycore nodes », Augonnet, Goudin, Kuhn, Lacoste, Namyst, Ramet

From CEA: « A hierarchical fast direct solver for distributed memory machines with manycore nodes », Augonnet, Goudin, Kuhn, Lacoste, Namyst, Ramet

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How big should a task be?

Multiple answers

• Depends on available platform parallelism
• Depends on available application parallelism
• Depends on application phases

Automatically adapt?
Hierarchical task graphs
Hierarchical task graphs

Applications themselves are recursive
• e.g. h-matrices

From Airbus Group
Hierarchical task graphs

Applications themselves are recursive

- e.g. h-matrices

From Airbus Group
Hierarchical task graphs

Applications themselves are recursive
  • e.g. h-matrices

From Airbus Group
Hierarchical task graphs

Ideally, should just start with one huge task, and split
Hierarchical task graphs

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Ideally, should just start with one huge task, and split
Hierarchical task graphs

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Hierarchical task graphs

Ideally, should just start with one huge task, and split
Hierarchical task graphs

- In OpenMP?

TRSM(A, B) {
    #pragma omp task depend(in:A, inout:B) wait
    {
        #pragma omp task \ 
        depend(in:A[0][0], inout:B[0][0])
        TRSM(A[0][0], B[0][0])
        #pragma omp task \ 
        depend(in:A[0][0], inout:B[1][0])
        TRSM(A[0][0], B[1][0])
        #pragma omp task \ 
        depend(in:A[1][0], in:B[0][0], inout:B[0][1])
        GEMM(A[1][0], B[0][0], B[0][1])
    ...
}
Hierarchical task graphs

Synchronization concerns

- Fork-join parallelism
- Hindered by synchronization induced by task graph
Hierarchical task graphs

- OmpSs introduced weak dependencies

```c
TRSM(A, B) {
  #pragma omp task depend(weakin:A, weakinout:B) \ 
    weakwait

  {
    #pragma omp task \ 
      depend(in:A[0][0], inout:B[0][0])
    TRSM(A[0][0], B[0][0])

    #pragma omp task \ 
      depend(in:A[0][0], inout:B[1][0])
    TRSM(A[0][0], B[1][0])

    #pragma omp task \ 
      depend(in:A[1][0], in:B[0][0], inout:B[0][1])
    GEMM(A[1][0], B[0][0], B[0][1])

    ...
  }
```

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Hierarchical task graphs

In StarPU

• Explicit data registration
• Recursive partitioning
Hierarchical task graphs

In StarPU

• Explicit data registration
• Recursive partitioning
Hierarchical task graphs

In StarPU

• Explicit data registration
• Recursive partitioning
Hierarchical task graphs

In StarPU

- Explicit data registration
- Recursive partitioning
Hierarchical task graphs

In StarPU

• Explicit data registration
• Recursive partitioning
Hierarchical task graphs

In StarPU

- Multi-level data coherency, among CPUs-GPUs-disk
- Enables seamless recursive tasks
- More details in Gwenolé Lucas’ talk Thursday 14:40
Hierarchical task graphs

Multi-level data coherency

• Synchronization pseudo-tasks
  • Only when needed

• Result is exactly as appropriate
→ Just split at will!
Hierarchical task graphs

Multi-level data coherency

- Synchronization pseudo-tasks
  - Only when needed
- Result is exactly as appropriate

→ Just split at will!
Dividing tasks

No extra synchronization

→ Can consider task graph subdivision as a tree
Dividing tasks

No extra synchronization

→ Can consider task graph subdivision as a tree
Dividing tasks

No extra synchronization

→ Can consider task graph subdivision as a tree
Dividing tasks

No extra synchronization

→ Can consider task graph subdivision as a tree
→ Decide at will where and when to stop recursing
Opportunities
Opportunities

GPU / CPU efficiency management

- Stop recursing at desired tile size
- Care for latency of the task graph critical path
Opportunities

Parallel submission
- Unroll the graph in parallel
- While one PU is computing the first task
Opportunities

Delay unrolling

- Observe behavior before unrolling the rest accordingly
- Decorrelate submission and execution
Opportunities

Delay unrolling

• Observe behavior before unrolling the rest accordingly
• Decorrelate submission and execution
Opportunities

Scaling at large

- Master unrolls higher recursion levels, schedules result
- Slaves unroll the rest
- Master still contention point
Opportunities

Scaling at large

• All nodes unroll higher recursion levels, determine task mapping
• Nodes unroll their own remaining recursion
• Network communication quite coarse
  → Spurious synchronizations
Opportunities

Scaling at large

- All nodes unroll higher recursion levels, determine task mapping
- Nodes unroll their own remaining recursion
- Network communication at finer grain
- Fine-grain enough vs overhead?
Opportunities

Scheduling at large

- High-level global task graph scheduling, e.g. mapping, critical path
- High-level local task graph scheduling, e.g. memory-based ordering
- $O(N^2)$ or even $O(N^3)$ not that costly
Opportunities

• Computation efficiency
• Scaling at large
• Scheduling at large

NumPEx PEPR project
NumPEx project

Building a national ecosystem for the future exaflops machine hosted in France

- Facilitate conception, deployment, and monitoring of composite applications at large scale
- Efficiently exploit a heterogeneous architecture with many accelerators
- Control the energy envelope

80 teams in France
NumPEx project

PC1-ExaMA
Methods/Algorithms for the Exascale

PC2-ExaSoft
HPC softwares/tools for the Exascale

PC3-ExaDost
Data-oriented softwares/tools for the Exascale

PC4-ExaAToW
Architectures/tools for large-scale workflows

PC5-ExaDIP
Application co-design Integration and productivity

A Software Forge
Integration and productivity

https://starpu.gitlabpages.inria.fr/
NumPEx project

PC2-ExaSoft
- Holistic approach
  - Contribute to a sound, consistent software stack
  - Most components should fit together!
  - Bridge the gap between existing languages/software/tools
  - Integrate state-of-the-art research results
  - Demonstrate relevance on representative applications

- WP3 : Runtime Systems at Exascale
Conclusion

• Programming large systems requires abstraction
• Recursive applications are there
• Hierarchical task graphs seems an opportunity for
  • Controlling task size
  • Controlling task submission
  • High-level task graph scheduling
The StarPU runtime system
Development context

• History
  • Started in 2008
    – PhD Thesis of Cédric Augonnet
  • StarPU main core ≈ 70k lines of code
  • Written in C

• Open Source
  • Released under LGPL
  • Sources freely available
    – git repository and nightly tarballs
    – See https://starpu.gitlabpages.inria.fr/
  • Open to external contributors

• [HPPC'08]

• [Europar'09] – [CCPE'11],... >1500 citations
Features

- C, OpenMP, OpenCL APIs
- CPUs, GPUs, Phi
- Advanced task mapping & scheduling
- Optimized data transfers
- Cluster Support through MPI
- Out-Of-Core support
- Simulation support
- Performance analysis tools
The StarPU runtime system

Success stories

Task-based programming actually makes things easier!

• QR-Mumps (sparse linear algebra)
  • Non-task version: only 1D decomposition
  • Task version: 2D decomposition, flurry of parallelism
    – With seamless memory control

• H-Matrices (compressed linear algebra, AirBus)
  • Out-of-core support
    – Could run cases unachievable before
      – e.g. 1600 GB matrix with 256 GB memory
  • Shipped to AirBus customers

• Implemented CFD, FMM, CG, stencils, …
The StarPU runtime system

Supported platforms

• Supported architectures
  • Multicore CPUs (x86, PPC, ...)
  • NVIDIA GPUs
  • OpenCL devices (eg. AMD cards)
  • HIP
  • FPGA (ongoing)
  • Old Intel Xeon Phi (MIC), SCC, Kalray MPPA, Cell (decommissioned)

• Supported Operating Systems
  • Linux
  • Mac OS
  • Windows
Applications on top of StarPU

Using CPUs, GPUs, distributed, out of core, ...

• Dense linear algebra
  • Cholesky, QR, LU, ... : Chameleon (based on Plasma/Magma)

• Sparse linear algebra
  • QR_MUMPS
  • PaStiX

• Compressed linear algebra
  • BLR, h-matrices

• Fast Multipole Method
  • ScalFMM

• Conjugate Gradient

• Other programming models : Data flow, skeletons
  • SignalPU, SkePU

• ...