

Lab 4: Binarized Convolutional Neural Networks

Team work: in groups of 2

Due Friday, October 28, 2022, 11:59pm

Late submission: 3% penalty per day; cannot be late by more than 6 days

1 Introduction¹

A convolutional neural network (CNN) is a machine learning algorithm that takes in an image and produces predictions on the classification of the image. A CNN consists of a series of connected **layers**. Each layer takes as input a set of **feature maps (fmaps)** (for short), performs some computation on them, and produces a new set of fmaps to be fed into the next layer. The input fmaps of the first layer come from the input images. Layers may require configuration values known as **parameters**, which must first be determined by *training* the CNN offline on pre-classified data. Once the parameters are finalized, the CNN can be deployed for *inference* — the classification of new data points. For most practical machine learning applications, the first-order concerns are the accuracy and execution time of online classification. Figure 1 shows a typical structure of a CNN. In this lab, we focus on the inference process. Especially, we want to perform hardware acceleration on the convolutional layers.

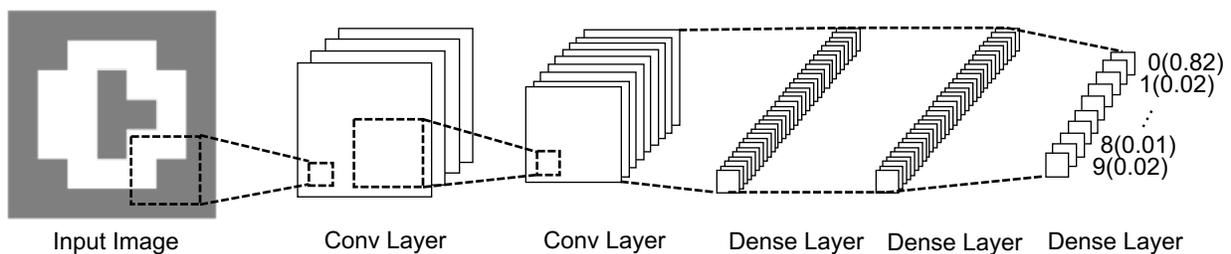


Figure 1: The typical structure of a CNN.

Networks with parameters and/or feature maps quantized to $+1/-1$ using polar encoding are called binarized neural networks (BNNs). Such networks have demonstrated high compute throughput and low on-chip memory footprint on FPGAs while maintaining accuracy comparable to full precision networks in certain cases. Moreover, we can reduce the number of multipliers by replacing multiplications with bit operations. In this lab, we represent $+1$

¹Part of this section is adapted from R. Zhao, et al. [1]

as 1 in memory. In addition, -1 is represented as 0. Hence, we only need one bit to store a binarized value. Figure 2 shows how we replace a multiplication with an XNOR operation after encoding. We use \hat{x} to denote the encoded value of x .

x	y	$x \times y$
-1	-1	+1
-1	+1	-1
+1	-1	-1
+1	+1	+1

\hat{x}	\hat{y}	$\hat{x} \odot \hat{y}$
0	0	1
0	1	0
1	0	0
1	1	1

(a) Normal multiplication between binarized variables x and y

(b) Multiplication using XNOR with encoded variables \hat{x} and \hat{y}

Figure 2: The encoding and multiplication for binarized variables.

In the following, we show how to perform a dot product between two binarized vectors.

$$\mathbf{A} \cdot \mathbf{B} = \sum_{i=0}^L A_i \times B_i \tag{1.1}$$

$$= 2 \times \sum_{i=0}^L (\hat{A}_i \odot \hat{B}_i) - L \tag{1.2}$$

Here \mathbf{A} and \mathbf{B} are two vectors with the same length L (i.e., $|\mathbf{A}| = |\mathbf{B}| = L$); A_i and B_i are the binarized elements that are either $+1$ or -1 in polar encoding; \hat{A}_i and \hat{B}_i are the actual binary values stored as 0/1 for A_i and B_i according to Figure 2. Below is a concrete example.

$$(+1, -1, -1, +1) \cdot (-1, -1, +1, +1) = 1 \times -1 + -1 \times -1 + -1 \times 1 + 1 \times 1 = 0 \quad \text{Eq. (1.1)}$$

$$= 2 \times (1 \odot 0 + 0 \odot 0 + 0 \odot 1 + 1 \odot 1) - 4 = 0 \quad \text{Eq. (1.2)}$$

We can see that now we only need logic operations (i.e., XNOR) and additions to perform the dot product. The multiplication of two can be replaced with a simple shift operation.

There are two common layer types in most BNNs — convolutional and fully connected layers.

A **convolutional (conv)** layer takes in M input fmaps of size $I \times I$ pixels, convolves them with *filters* of size $K \times K$ pixels, and produces N output fmaps of size $O \times O$ pixels. The convolution operation can be demonstrated using an example, which is shown in Figure 3. In this example, we have three input fmaps of size 5×5 (i_0 , i_1 , and i_2) and two output fmaps of size 3×3 (o_0 and o_1). To begin with, each input fmap is convolved² with a 3×3 filter, which generates a partial sum for the corresponding output pixel. In Figure 3, input fmap i_0 convolves with filter $w_{0,0}$ and generates $p_{0,0}$. The rest partial sums $p_{0,1}, \dots, p_{2,1}$ are produced in a similar manner. These partial sums are accumulated to produce the pixels of the output fmaps. In Figure 3, we sum up $p_{0,0}$, $p_{1,0}$, and $p_{2,0}$ to produce o_0 . Similarly, we can produce o_1 by accumulating $p_{0,1}$, $p_{1,1}$, and $p_{2,1}$.

²Please refer to Lecture 13 slides, p.36.

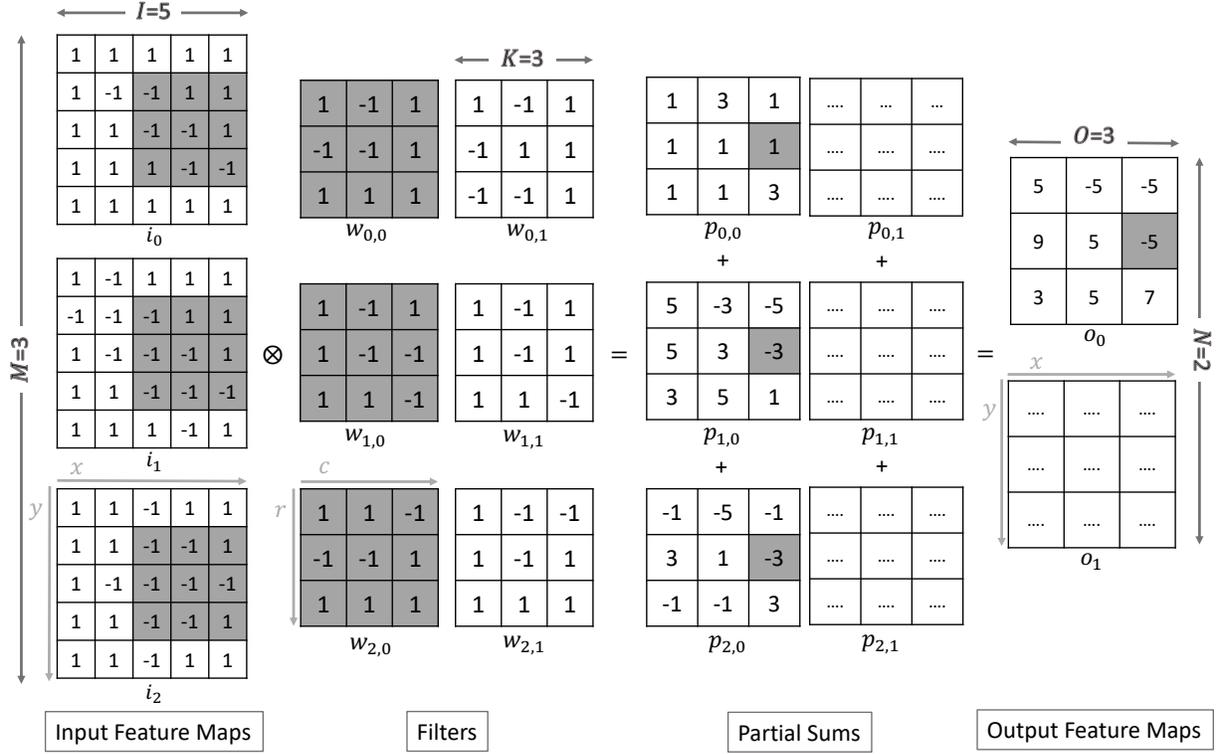


Figure 3: An example of convolution operation, where $M = 3$, $N = 2$, $I = 5$, $O = 3$, and $K = 3$.

From the above example, we can observe that for each output fmap, we need M filters. Thus, to produce N output feature maps, we need $M \times N$ filters. The above procedure can be formalized in Equation (1.3).

$$o_n(x, y) = \sum_{m=0}^{M-1} \sum_{r=0}^{K-1} \sum_{c=0}^{K-1} i_m(x + c, y + r) \times w_{m,n}(c, r) \quad (1.3)$$

Here $o_n(x, y)$ is the value of pixel (x, y) of the n^{th} output feature map, i_m is the m^{th} input feature map, and $w_{m,n}$ is the filter that convolves with input i_m and produces a partial sum of output o_n . Note that we can apply Equation (1.2) to transform the multiplications into XNOR operations. For example, if we want to calculate the pixel $(2, 1)$ of the first output fmap in Figure 3, we can have the following equation.

$$\begin{aligned}
o_0(2, 1) &= \sum_{m=0}^2 \sum_{r=0}^2 \sum_{c=0}^2 i_m(2+c, 1+r) \times w_{m,0}(c, r) \\
&= 2 \times \sum_{m=0}^2 \sum_{r=0}^2 \sum_{c=0}^2 (i_m(2+c, 1+r) \odot w_{m,0}(c, r)) - 3 \times 3 \times 3 \\
&= 2 \times \{(0 \odot 1 + 1 \odot 0 + 1 \odot 1 + \dots + 0 \odot 1) \\
&\quad + (0 \odot 1 + 1 \odot 0 + 1 \odot 1 + \dots + 0 \odot 0) \\
&\quad + (0 \odot 1 + 0 \odot 1 + 1 \odot 0 + \dots + 1 \odot 1)\} - 27 = -5
\end{aligned}$$

The number of **multiplication-accumulation operations (MACs)** needed during the above process is $M \times N \times O \times O \times K \times K$. After we derive the output fmaps, we binarize the outputs by comparing each value with a pre-trained threshold t , which is shown in Equation (1.4).

$$\text{binarize}(x) = \begin{cases} +1, & x \geq t \\ -1, & x < t \end{cases} \quad (1.4)$$

The parameters of a conv layer are $M \times N \times K \times K$ bits. Finally, we perform a 2D maximum pooling to halve the size of an output fmap, where we pick the maximum value in a 2×2 window with a stride of two. An example is shown in Figure 4.

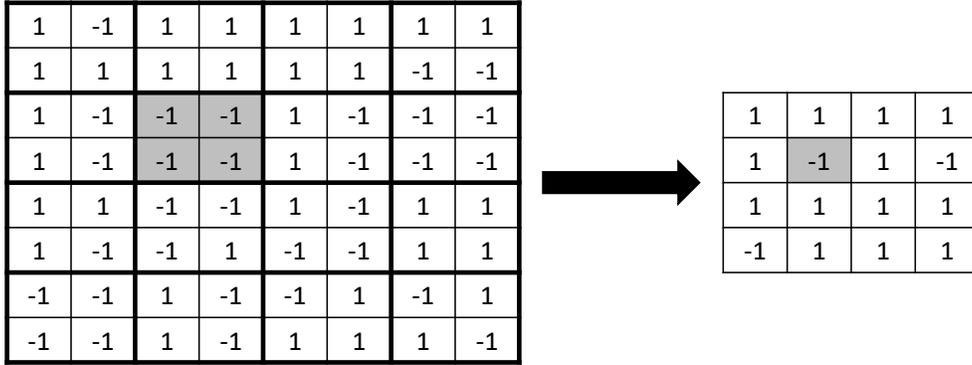


Figure 4: An example of performing 2D maximum pooling on a 8×8 fmap, which results in a fmap of size 4×4 .

A **fully-connected (or dense)** layer takes in M input feature maps of size 1×1 (i.e., a pixel) and produces N output feature maps of size 1×1 . The output feature maps are derived from the product between M input fmaps and $M \times N$ weight matrix. Equation (1.5) shows the operation of a dense layer with M input pixels i_0, \dots, i_{M-1} , N output pixels o_0, \dots, o_{N-1} , and $M \times N$ weights $w_{0,0}, \dots, w_{M-1,N-1}$.

$$o_n = \sum_{m=0}^{M-1} i_m \times w_{m,n} \quad (1.5)$$

The number of MAC operations is $M \times N$. Similar to conv layers, we can apply Equation (1.2) to replace all multiplications. After we have the output fmaps, we quantize the output values according to their signs. The parameters of a dense layer are $M \times N$ bits, which are produced by the training process.

2 Objective

In this lab, you will be building a BNN inference accelerator on ZedBoard. Specifically, you are given a pre-trained BNN that performs digit recognition.

From Table 1, we can observe from Columns 7-8 that conv layers are more compute intensive while dense layers are more memory intensive. In practice, a larger and deeper BNN has more conv layers, where the difference is more pronounced. Thus, although we offload all layers to FPGA in this lab, you should first focus on optimizing the conv layers.

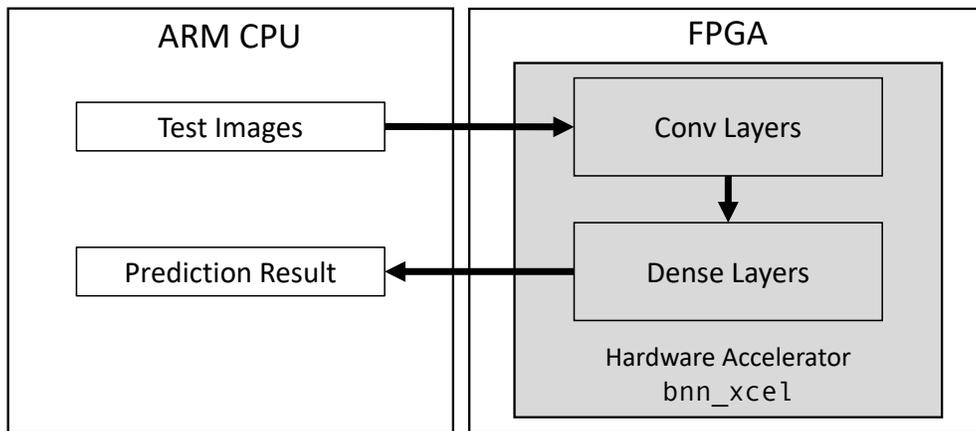


Figure 5: The software-hardware partition.

The software-hardware system is shown in Figure 5. The whole flow works as follows. First, the test images stored in CPU are sent to the hardware accelerator `bnn_xcel` one at a time. The test image will become the input fmaps of the first layer in `bnn_xcel`. The fmaps will be processed by the two conv layers inside `bnn_xcel` sequentially. The output fmaps of the last conv layer will become the input fmaps of the first dense layer in `bnn_xcel`. Finally, the prediction result is computed by the second dense layer and sent back to CPU. Your task is to **optimize the performance of the accelerator** with limited hardware resources.

3 Materials

You are given a zip file named `lab4.zip` on `ecelinux` under `/classes/ece5775/labs`, which contains the following directories:

- **ecelinux**: contains a C++ project for you to build the `bnn` HLS design and synthesize it to a hardware module. This code should be completed on `ecelinux`.
- **zedboard**: contains *symbolic links* to the files in the `ecelinux` directory required for software execution of `bnn` on CPU. This time the host program is given.

Both *ecelinux* and *zedboard* folders contain the following files:

- *bnn.cpp*: a source file which contains the program (dut) to be synthesized on FPGA.
- *bnn.h*: a header file that defines the prototype of functions in *bnn.cpp*.
- *layer.cpp*: a source file where conv layers, dense layers, and maximum pooling operations are defined.
- *layer.h*: a header file that defines the prototype of functions in *layer.cpp*. It also contains the network configuration.
- *bnn.test.cpp*: a test bench file that runs and tests the BNN model.
- *model.h*: a header file that contains the weights for all layers.
- *typedefs.h*: a header file that defines the data types used in the design.
- *data*: a folder that contains the weights and testing data.
- *run.tcl*: a Tcl script that helps you run the HLS flow.
- *Makefile*: a makefile similar to Lab 3 that helps you compile the design and generate the bitstream.

4 Design Overview

The configuration of our network is shown in Table 1.

Layers ³	#Input fmaps	#Output fmaps	Size of Input fmaps	Size of Output fmaps	Filter Size	#MACs	#Params
conv1	1	16	16×16	8×8	3×3	36864	144
conv2	16	32	8×8	4×4	3×3	294912	4608
dense1	512	256	1×1	1×1	-	131072	131072
dense2	256	10	1×1	1×1	-	2560	2560

Table 1: The network configuration of our BNN.

Following we describe the details of each hardware component.

CPU/FPGA Interface: Similar to Lab 3, an input FIFO and an output FIFO are used to transfer data between software and hardware. Each pixel of a 16×16 input image is represented by a Bool variable, which stores the encoded value of the original pixel. The output is a number ranging from 0 to 9 that represents the classification result. The C/C++ code for this interface is provided in file *zedboard/host.cpp*.

On-chip Memories: The on-chip memories can be classified as two parts: feature maps and parameters. From Table 1, we can see that the parameters used by both conv and dense layers only require 138384 bits (17k bytes). Thus, we can store all parameters on-chip to minimize software-hardware communication. The stored weights and thresholds are in file *model.h*. All weights are already encoded for XNOR operations. Similarly, the maximum size of fmaps we need is $16 \times 16 \times 16 = 4096$ bits. Therefore, the fmaps for conv layers are also stored on-chip. The stored fmaps are in file *bnn.cpp*. The value of each pixel in the fmaps is also encoded.

³Convolutional layers are followed by maxpooling layers, which downsample feature map sizes by 2.

Both fmaps and parameters are stored as 1D arrays. The reason why we use 1D arrays is that we can reuse the same 1D arrays to represent matrices with different shapes. The main issue of using 1D arrays is how we translate between the original matrix and the 1D array. Figures 6 and 7 show the mappings of 3D fmaps ($M \times I \times I$ or $N \times O \times O$) and 4D weights ($M \times N \times K \times K$) into 1D arrays, respectively.

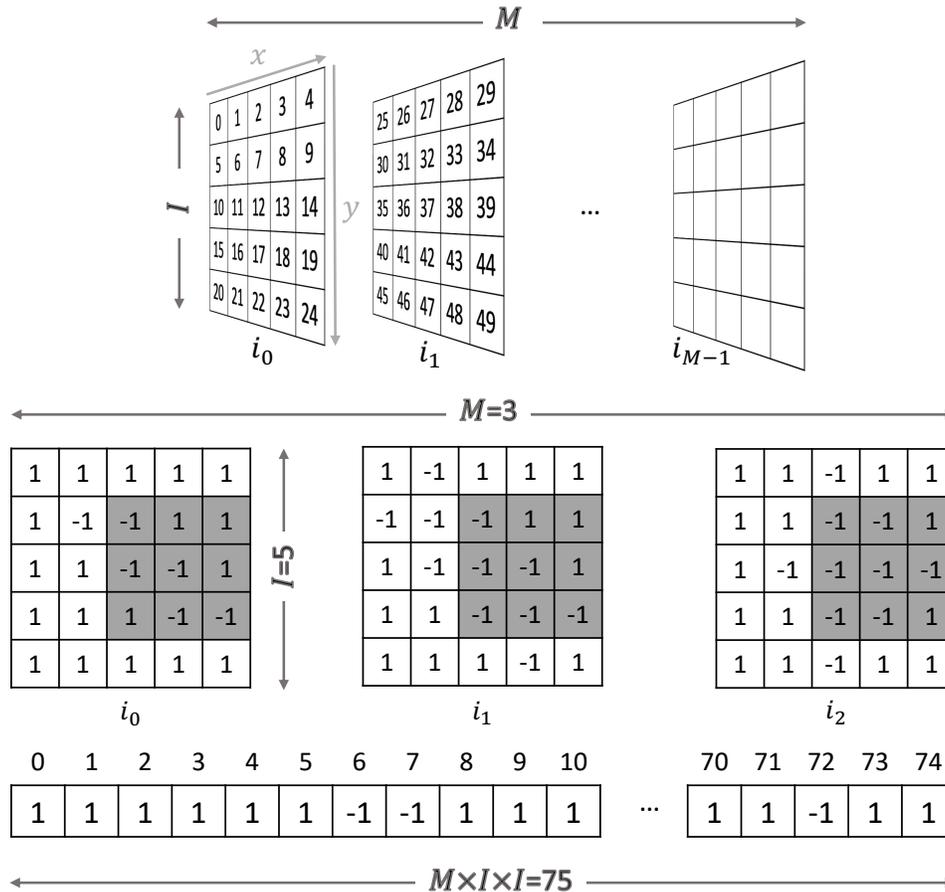


Figure 6: The indexing of pixels in fmaps for examples in Figure 3.

The mappings are provided in file `layer.cpp` as well.

5 Guidelines and Hints

5.1 Coding and Debugging

Your first task is to run the code on **ecelinux** by using **make** to make sure you have a functional design. The accuracy should be 0.82 (82%). In this lab, you only need to optimize the FPGA implementation on a ZedBoard. The process of generating the bitstream, logging onto a ZedBoard, and programming the ZedBoard using the bitstream is identical to Lab 3. Be aware that **it may take 15-20 minutes to generate the bitstream**. Since the

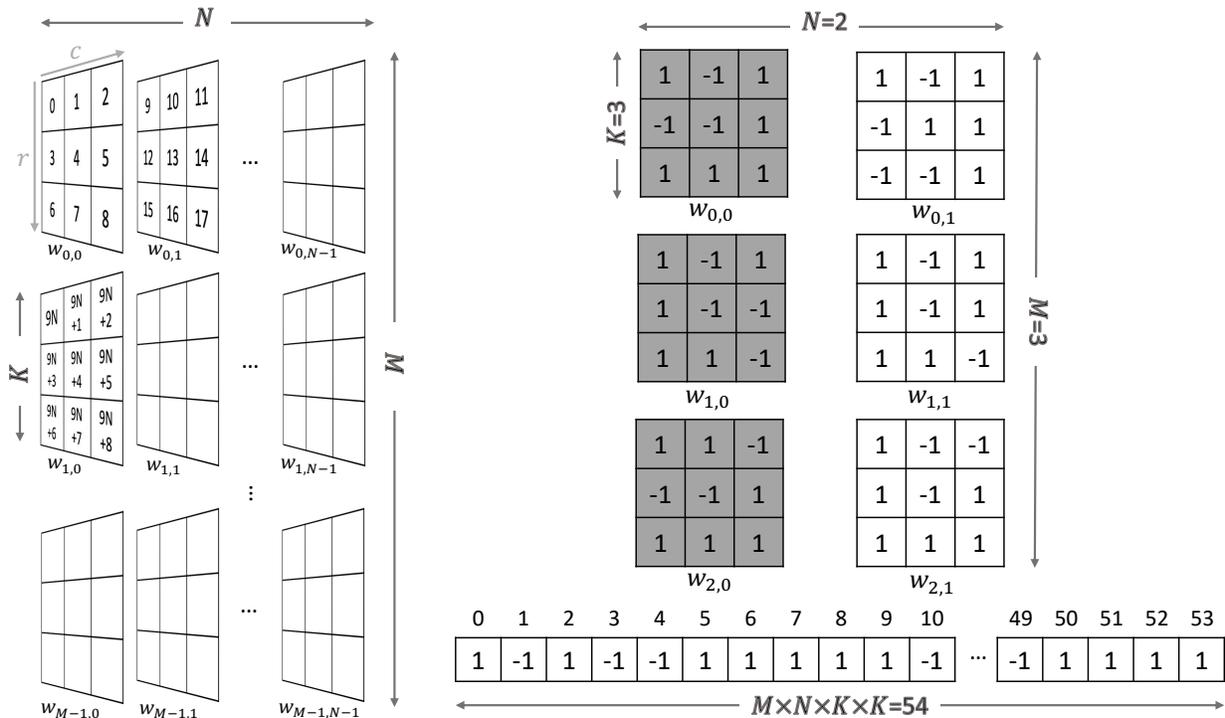


Figure 7: The indexing of pixels in filter weights for examples in Figure 3.

bitstream generation may be slower with a more complex design after optimization, we strongly recommend you to use the information from the Vivado HLS synthesis report to estimate the performance of your hardware design before generating the bitstream. Similar to Lab 3, use `make sw` to run the entire design on ARM CPU and use `make fpga` to run the program with the generated bitstream. Timers identical to those from Lab 3 will be used. After you complete the code, the execution times you get from `make sw` and `make fpga` will be the CPU baseline and FPGA baseline, respectively. The FPGA baseline should be around **3500 msec** for **100** test images.

5.2 Design Optimizations and Constraints

In the first three labs, you have explored various design optimization techniques related to customized data types (e.g. fixed point) and customized compute engines that exploit parallel processing and pipelining. In this lab, you will further learn to build customized on-chip memory architectures to maximize the efficiency of your accelerator. It is still necessary to add HLS pragmas/directives, such as `unroll`, `pipeline`, and `array_partition`, in appropriate places to reduce the overall cycle count. You will also need to modify the given source code to reorganize the on-chip data storage. Specifically, there are several optimizations you can try to implement.⁴

- Reorganizing the arrays that store the binary parameters and fmaps by packing multiple 1-bit values into integers with a higher bitwidth (say 32 or 64 bits). This would allow

⁴You don't have to implement all of them to achieve a good performance.

each access to the array to read or write many bits in one slot and naturally enable many (bitwise) XNOR operations to be performed in parallel.

- Exploring different loop orders ⁵ if it exposes more parallelism and makes the bit packing easier. **Hint:** it is more beneficial to pack the bits along the channels instead of doing it along the rows or columns of the fmaps.
- Exploiting data reuse in 2D convolution by introducing reuse buffers, which is discussed in Lectures 2 and 13. It is not a trivial task to properly implement line buffers and register windows in HLS. To understand the key concepts, you can refer to Chapter 9 “Video Systems” of this book [4]. There are also helpful tutorials on YouTube [5] that give detailed explanation and guidelines of using the `LineBuffer` and `Window` provided by Vivado HLS.

You are allowed to change any parts of the program to improve performance. However, the only restriction is that the utilization ratio for each type of hardware resources (i.e., BRAMs, LUTs, FFs, and DSPs) should be **at most 75%**.⁶ You can verify this by checking your HLS synthesis report. In addition, the test error should be **no greater than 20%**.

5.3 Grading Scheme

This time we will do a competition among 20+ teams (with 2 students per team) to see who could achieve the best performance (i.e., the lowest execution time measured on ZedBoard) while meeting the resource constraint. The report accounts for 4 points (out of 10) of the overall grade. Below is the grading scheme of the 6 points allocated for the design itself.

- +3pt : At least 3X speedup over the unoptimized baseline in terms of the worst-case latency estimate in the HLS report
- +1pt : At least 5X speedup over the baseline in worst-case latency estimate by HLS
- +1pt : Top 40% (i.e., top 8-9 teams) in performance on ZedBoard
- +1pt : Top 15% (i.e., top 3-4 teams) in performance on ZedBoard

5.4 Report

- Please write your report in a **single-column and single-space format with a 10pt font size. Page limit is 2.** Please include the names and NetIDs of your team members on the report.
- The report should start with an overview of the document. This should inform the reader what the report is about, and highlight the major results. In other words, this is similar to an abstract in a technical document.
- There should be a section describing how you optimize the design. If you use more than one optimization methods, please compare their impacts regarding different aspect (e.g., performance, resource usage, accuracy). This section should contain a table which reports the measured execution time and resource usage under different optimization methods, including the CPU baseline and the FPGA baseline.

⁵Please refer to Lecture 15 and check out the paper by Zhang, et al [2].

⁶Using more resources may cause routing congestion that increases the compile time to generate bitstream.

- There should be paragraph at the end that concisely describe the division of work between the team members.
- All of the figures and tables should have captions. These captions should do their best to explain the figure (explain axis, units, etc.). Ideally you can understand the report just by looking at the figures and captions. But please avoid just putting some results and never saying anything about them.
- The report should only show screenshots from the tool when they demonstrate some significant idea. If you do use screenshots, make sure they are readable (e.g., not blurry). In general, you are expected to create your own figures. While more time consuming, it allows you to show the exact results, figures, and ideas you wish to present.

6 Deliverables

Please submit your lab on CMS. You are expected to submit your report and your code and scripts (and only these files, not the project files generated by the tool) in a zipped file named **bnn.zip** that contains the following contents:

- **report.pdf**: the project report in pdf format.
- The folders **ecelinux** and **zedboard**. These should contain the completed source files for the software-only and optimized FPGA implementations of the **bnn** design. Make sure the design can be built using the Makefile and scripts in the folders. Please run `make clean` to remove all the generated output files.

7 Acknowledgement

The baseline FPGA+Linux setup used in the lab is based on the Xilinx distribution provided by Xillybus Ltd. (<http://xillybus.com/xilinx>)

References

- [1] R. Zhao, W. Song, W. Zhang, T. Xing, J.-H. Lin, M. Srivastava, R. Gupta, and Z. Zhang, *Accelerating Binarized Convolutional Neural Networks with Software-Programmable FPGAs*, International Symposium on Field-Programmable Gate Arrays (FPGA), Feb. 2017.
- [2] C. Zhang, P. Li, G. Sun, Y. Guan, B. Xiao, and J. Cong, *Optimizing FPGA-based Accelerator Design for Deep Convolutional Neural Networks*, International Symposium on Field-Programmable Gate Arrays (FPGA), Feb. 2015.
- [3] Xilinx Inc., *Vivado Design Suite User Guide: High-Level Synthesis UG902 (v2019.1)*, Available at https://www.xilinx.com/support/documentation/sw_manuals/xilinx_2019_1/ug902-vivado-high-level-synthesis.pdf
- [4] R. Kastner, J. Matai, and S. Neuendorffer, *Parallel Programming for FPGAs*, 2018. Available at <https://arxiv.org/pdf/1805.03648.pdf>
- [5] YouTube Tutorials, *Vivado HLS 2D Convolution on Hardware*. [Part1] [Part2] [Part3]