





CoCoSys Center Overview : Year 2 Annual SAB Meeting

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AI Challenges

a-x-dx-

- Narrow (specific to task or input modality)
- Lack of explainability and transparency
- Lack of robustness

2+4+4+8+12=30 2x+2y=20

- Scaling depends on larger models and datasets
- Algorithms driven by today's hardware (GPUs and digital accelerators)

COS(B)



Why CoCoSys?

Future Collaborative Al Systems

Current AI Systems

- Black-box (not explainable or interpretable)
- Reliant on large datasets, networks and compute
- Mostly monolithic CMOStechnology

GRAND CHALLENGES

- Can we stem the unsustainable trends in compute requirements for AI?
- Can a fusion of neural, symbolic and probabilistic methods lead to more scalable, robust and explainable AI?
- Can cognitive algorithms perform the entire gamut of tasks involved in collaborative AI systems (perception, reasoning and decision making)?
- Can cross-layer design of cognitive algorithms and hardware improve energy efficiency by over 100X?

- Seamless human-AI and AI-AI collaboration
- Explainable, robust and secure
- Hardware and algorithms co-designed to optimize energy efficiency, latency and throughput
- Leverage future logic, memory and integration technologies



Center Overview and Themes



Neural + Vector Symbolic Architectures



The Theory of Robustness and Beyond



Improving Vision Systems through Foveation and Saccades

Computational Models

Foveation (variable resolution)



Saccade (quick eye movement)





Theory

• Advantage 1: more accurate bounding boxes:







• Advantage 2: more resilient localization pipeline,



Algorithms

 Advantage 3: Can define Image grammer (semantics & syntax)
Correct image Patches





Needs of Future Neuro-Symbolic-Probabilistic Workloads



Algorithm-Hardware Co-design



- Open-source tools and tool-chains for system exploration within CoCoSys
- Industry collaborations (joint papers, joint conference sessions)
- Hardware artifacts to quantify system benefits





- Innovation: First effort towards algorithms-to-hardware co-design of Neuro-symbolic-probabilistic AI systems
- Key Result: 2-3 orders of magnitude faster & more energy efficient than CPUs and GPUs

System Design with Advanced and Emerging Technologies



Heterogeneous Integration Smulator with Interconnect Modeling (HISIM)

- 2.5D/3D interconnection, inmemory computing chiplets, network-on-packaging, thermal
- <u>Analytical performance models that</u> are 10⁴x-10⁶x faster than NeuroSim and other SOTAs







Reducing Data-movement through In-X Computing

SRAM





- FP-IMC: TSMC 28nm digital floatingpoint IMC macro chip (ESSCIRC'23)
- SP-IMC: TSMC 28nm digital sparsity-integrated IMC macro w/ compressed computing (CICC'24)
- IMC w/ delta-sigma modulator for variable input precision (CICC'23, SSCL'23) Multi-step cap.-coupling IMC SRAM Macro in 28nm (JSSC'24)
- Accurate/ Approximate CAM (TBP)

NVM

Sensor



FD Processing & Event Detection COLPE/PO [k] + +1 FVT[k] [323,n+1 324 x 252 Pixel [322,n] Pixels Image Patch [107.k] 108 x 84 Patches Patch [0.k FD Processing & EV Pixe [0,n+1] Colur Parallel A Coleix (n+ Col_{Pix} [n 324 x 252 Pixels Col_{PIX} [n-1] 108 x 84 Patches PATCH Col. Parallel ADCs MUX & Output Buff

- 65nm RRAM for genome sequencing
- 180nm IMC macro chip for NVM ferroelectric capacitor array with PoT ADC (SSCL'23)
- 40nm RRAM VLIW processor for edge inference and robot manipulation
- Time-memory-based CMOS vision sensor w/ in-pixel temporal derivative comp. (ESSCIRC'23)
- Multi-mode: image sensor, event, temporal deriv.

Tool-chain for DTCO in the Context of AI Workloads

Cross-layer Modeling and Design of 7nm PDK for DTCO

- Circuit parasitics extracted from SOT, SRAM, and FeFET-CAM layouts based on ASAP7 PDK using state of the art EDA tools
- Parasitics used in SPICE simulations to extract ML discharge delays
- Interconnect parasitics IR drop and RC delay degrade similarity search performance for larger array sizes
- Two solutions explored using wider search lines

(S2x) and matching clk delay (Clk match)





(a) SOT (b) SRAM and (c) FeFET CAM cell layout

Human-AI Interactions: Conversational Agents



AI-AI Interactions: Autonomous UAV Swarms



- 18.9% reduction in UAV flight energy
- 22.1% increase in number of successful missions
- 4.07x reduction in processing energy
- Generalize across chips, voltages, UAV numbers, and autonomy policies



- First benchmark suite for evaluating robotic computing system performance.
- Usage across academia (Harvard, GT, CMU, Boston Univ, Columbia Univ, etc) and industry (Intel, Ford, AMD, etc). 123 GitHub stars.

CoCoSys at a Glance



CoCoSys Hardware Gallery













40nm Transformer PI: Priyanka Raina



28nm NeRF acc. PI: Celine Lin

28nm MRAM IMC PI: N. Shanbhag w/ Raytheon

M IMC 16nm adaptive GNN w/ Raytheon PI: Yu Cao



CoCoSys Software Artifact Gallery



CoCoSys Software Artifact Gallery

Offline Learning

Multi-

Agent

Robust

Policy

Learn with

injected random

bit-flips

(1)Payload

Optimization

(2)Collaborative

Sprint-or-Slack





Rapid DSE for LLM PI: Tushar Krishna

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Virtual Environment	-•	Frame-based Processing	->	Multi-modal Fusion
Video Interpolation	-	Frame-to-event conversion	┝	Event-based Processing

Event-based drone simulation PI: Arijit Raychowdhury (Frontiers in NeuroSci'24)

LLM KV Cache compression PI: Tushar Krishna (w/ Intel)

On-Device Robust Learning

Learn with actual low-voltage bit-flips

Swarm drone optimization

PI: Arijit Raychowdhury (w/ IBM)

(DAC'23, ASPLOS'24)

V/F

(4) Dynamic

Serve

(3)Dynamic

ommuni cation

Adjustment

Server Para.

Automated and customized CNN/ViT compression and model conversion





conv.weight (INT) scaler.scale (INT)

scaler.bias (INT



Automated CNN/ViT compression PI: Jae-sun Seo

Float32

Improvements

Robustness

Success Rate

Effic iency

Processing |

Energy

Quality-of-Flight

Flight Energy

#Missions

Host Sim **Companion Computer** AirSim Perception Plannin Sensors Camera (IMU) Point Cloud Point Cloud Publish IM Actuator Trajector Mission Planner Flight Package Delivery ROSFI Unreal Attach + Sync **QoF Metric** Control Engine Flight time Fault Injection Path Tracking/ Success rate Continue Mission energ +Topic +--+ Service ++ Fault injection ROS node Error propagation e.g.

AutoSys reliability analysis PI: Arijit Raychowdhury (TCAD'23, Comm of ACM'24)





Robotic benchmarking PI: Arijit Raychowdhury (ICRA'24)



Software and Hardware Artifacts



https://drive.google.com/file/d/1uivIeDm1CIUjA2O4rZL mcW0YuYvqwgfK/view?usp=sharing

Software Artifacts



https://drive.google.com/file/d/17wh_sf_Jf72Kc91GJcLMA6dir4REkhR/view?usp=share_link

Hardware Artifacts







