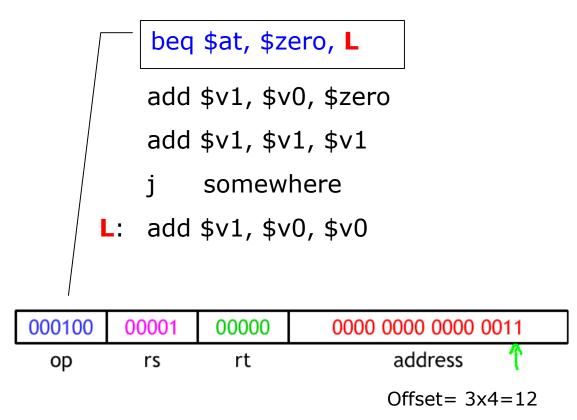
### **Design of the MIPS Processor (contd)**

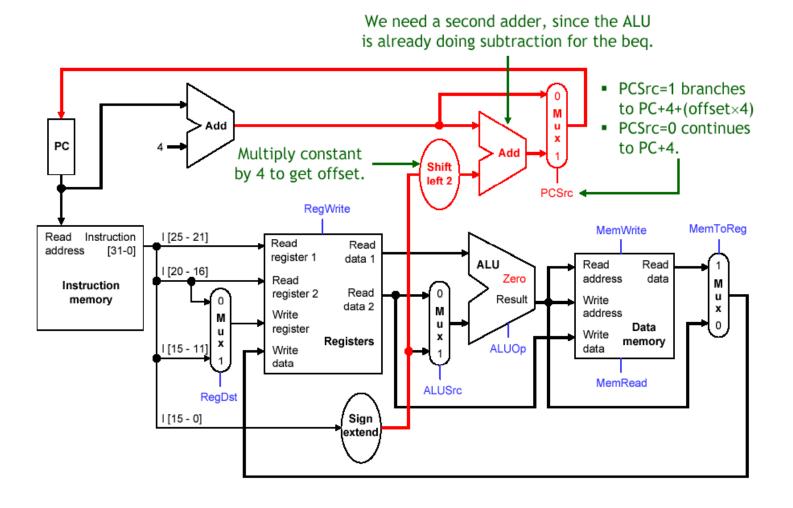
First, revisit the datapath for add, sub, lw, sw. We will augment it to accommodate the beq and j instructions.

#### **Execution of branch instructions**



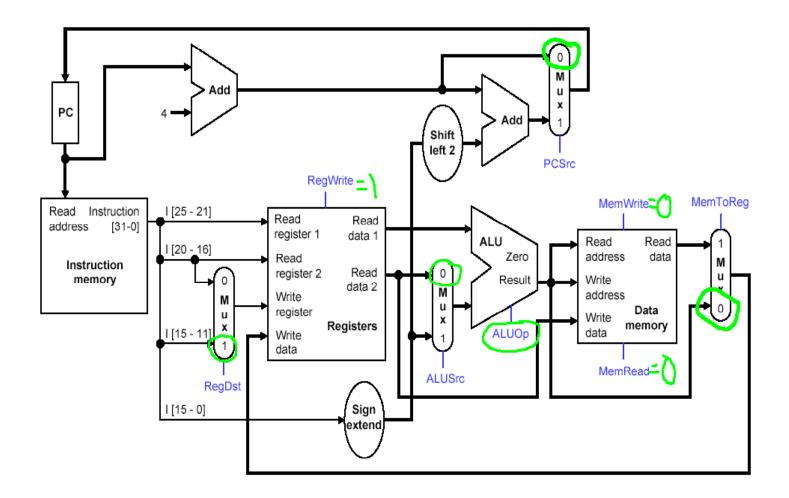
The offset must be added to the next PC to generate the target address for branch.

# The modified version of MIPS



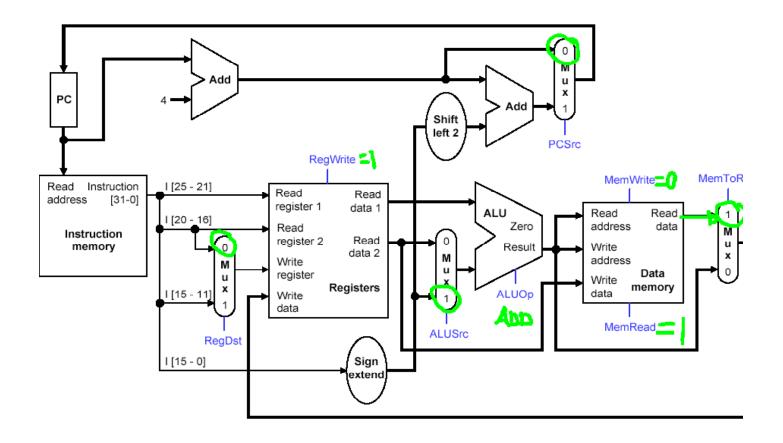
The final datapath for single cycle MIPS. Find out which paths the signal follow for lw, sw, add and beq instructions

# **Executing R-type instructions**

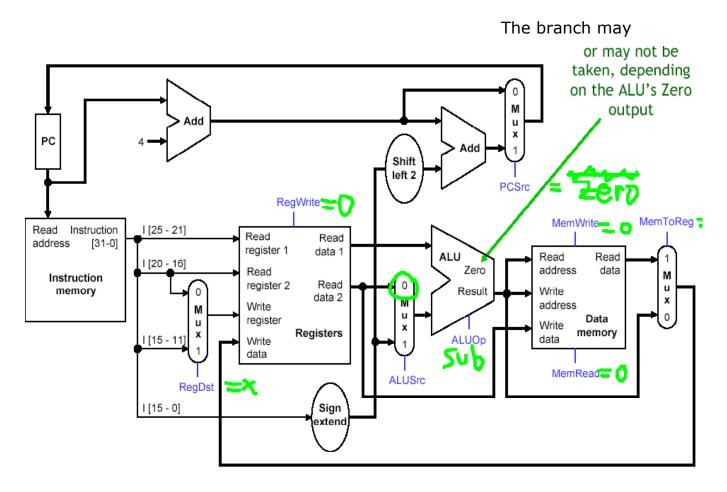


The ALUop will be determined by the value of the opcode field and the function field of the instruction word

## **Executing LW instruction**



## **Executing beq instruction**



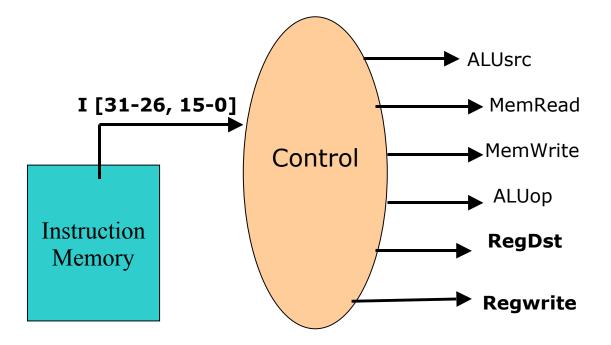
# Control signal table

This table summarizes what control signals are needed to execute an instruction. The set of control signals vary from one instruction to another.

Operation	RegDst	RegWrite	ALUSrc	ALUOp	MemWrite	MemRead	MemToReg
add	1	1	0	010	0	0	0
sub	1	1	0	110	0	0	0
and	1	1	0	000	0	0	0
or	1	1	0	001	0	0	0
slt	1	1	0	111	0	0	0
lw	0	1	1	010	0	1	1
SW	Х	0	1	010	1	0	X
beq	Х	0	0	110	0	0	Х

How to implement the control unit?

# **The Control Unit**



#### All control signals are not shown here

#### 1-cycle implementation is not used

Why? Because the length of the clock cycle will always be determined by the slowest operation (lw, sw) even when the data memory is not used. Practical implementations use multiple cycles per instruction, which fixes some shortcomings of the 1-cycle implementation.

Faster instructions are not held back by the slower instructions

The clock cycle time can be decreased.

Eventually simplifies the implementation of

pipelining, the universal speed-up technique

This requires some changes in the datapath