



Tools in action

An example with Pytorch

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LUMI Comprehensive Training
Oct. 31st 2024

AMD 
together we advance_

slides on LUMI in `/project/project_465001362/Slides/AMD/`

hands-on exercises: <https://hackmd.io/@sfantao/lumi-training-ams-2024#Pytorch-example>

hands-on source code: `/project/project_465001362/Exercises/AMD/Pytorch`

Agenda

-
1. Intro to Pytorch and its dependencies
 2. Controlling affinity
 3. Profiling – rocprof and omnitools.
 4. Debugging

All suggestions presented here are transversal to any AI or HPC application!

Python applications can leverage the same tooling as non-python applications!

Scripting examples are suggestions and can always be adapted!

Pytorch highlight

- Official page: <https://pytorch.org/>
- Code: <https://github.com/pytorch/pytorch>
- Python™-based framework for machine learning
 - Auto-differentiation on tensor types
- GPU-enabled
 - ROCm support for MI250x (and others)
 - Hipification as part of the build system
 - C/C++ libraries with proper bindings for Python
 - Python code does **NOT** need changing – using the same CUDA conventions
- Other related packages:
 - Torch vision/audio, many others
 - APEX – multiprecision library
 - <https://github.com/ROCmSoftwarePlatform/apex>



Pytorch install – our base environment

```
module purge
```


```
module load CrayEnv
```

```
module load PrgEnv-cray/8.5.0
```


```
module load craype-accel-amd-gfx90a
```

```
module load cray-python
```

Setup the GPU environment
and the Cray
Python environment



Recent Pytorch builds need
recent user-level ROCm
versions.




```
# This path provides more recent ROCm modules.
```

```
module use /appl/local/containers/test-modules
```

```
module load rocm/6.1.3.lua
```

We will be using 6.1.3 as it the oldest version
for Pytorch 2.4.1 official releases



Pytorch install – running the examples

- For simplicity and improve the demonstration we leverage interactive runs on existing node allocation
- We run beforehand:

```
N=1 ; salloc -p standard-g \
  --threads-per-core 1 \
  --exclusive \
  -N $N \
  --gpus $((N*8)) \
  -t 4:00:00 --mem 0
```

We are reserving **N nodes**, in this case only one node, using **one of the two available hardware threads** per core. We we'll be using the **8 GCDs** available in each node.



- This is a good way to experiment and converge to the correct job description.
- Don't forget to release your allocations once you are done!
- Once you consolidate your job description you can leverage batch jobs.
 - Salloc options translate directly to sbatch options.

Pytorch install – system python

- Native install from Pytorch python wheels

Where do we want to install things - don't use your home folder!

Package install version can mix the Pytorch version as well as the ROCm it was build against.

This is where Pytorch project posts the wheel files - browse it to see what versions and ROCm combinations are available.

```
pip3 install -t $PWD/pip-installs --pre torch==2.4.1+rocm6.1 --index-url https://download.pytorch.org/whl/
```

```
Collecting torch==2.4.1+rocm6.1
  Downloading https://download.pytorch.org/whl/rocm6.1/torch-2.4.1%2Brocm6.1-cp311-cp311-linux_x86_64.whl (2662.0 MB)
  0.9/2.7 GB 74.9 MB/s eta 0:00:24
```

```
PYTHONPATH=$PWD/pip-installs \
```

Make the frershly install Pytorch available to your Python runs

```
srun --jobid=$jobid -n1 --gpus 8 \
```

```
python -c 'import torch; print("I have this many devices:", torch.cuda.device_count())'
```

```
> I have this many devices: 8
```

Should yield the number of GCDs in the node.



Pytorch install – virtual environments

- Virtual environments are convenient to manage python package installation in ones user-space

Leverage the venv module to create the virtual environment

We are happy to leverage system's already installed packages

The folder where the virtual environment will be installed

```
python -m venv --system-site-packages cray-python-virtualenv
```

```
source cray-python-virtualenv/bin/activate
```

Activate the environment. It will be leveraged by the install and run.

Install and run as before. No need to specify install location – the environment is doing it for you.

```
pip3 install --pre torch==2.4.1+rocm6.1 --index-url https://download.pytorch.org/whl/  
srun --jobid=$jobid -n1 --gpus 8 \
```

```
python -c 'import torch; print("I have this many devices:", torch.cuda.device_count())'
```


Pytorch install – conda environment

- Conda environment adds the package-manager functionality to a virtual environment
- One can tune the Python version to use as we won't be leveraging the system one anymore.
 - No `module load cray-python` needed!

```
curl -LO https://repo.anaconda.com/miniconda/Miniconda3-latest-Linux-x86_64.sh
```

```
bash ./Miniconda3-* -b -p miniconda3 -s
```

Download and install a minimal conda (miniconda).

```
source $PWD/miniconda3/bin/activate base
```

Activate the conda environment

```
conda create -y -n pytorch python=3.11
```

```
source $PWD/miniconda3/bin/activate pytorch
```

Create and activate a conda environment to install Pytorch based on Python 3.11

Install and run as before - Conda package manager doesn't have ROCm enabled Pytorch installs

```
pip3 install --pre torch==2.4.1+rocm6.1 --index-url https://download.pytorch.org/whl/
srun --jobid=$jobid -n1 --gpus 8 \
```

```
python -c 'import torch; print("I have this many devices:", torch.cuda.device_count())'
```

Pytorch install – conda environment install from source

- Installing Pytorch from source is not recommended on LUMI
 - Too old default ROCm to build against.
- It might be useful in some cases: builds with symbols for debugging.

```
# We need a recent enough compiler – we'll use gcc
```

```
module load PrgEnv-gnu/8.5.0 gcc/10.3.0
```

```
# Clone a given version of Pytorch and all its third_party components
```

```
git clone -b v2.4.1 --recursive \
  https://github.com/pytorch/pytorch pytorch-source
```

```
# Create and activate conda environment to manage the install
```

```
conda create -y -n pytorch-from-source python=3.11
```

```
source $wd/miniconda3/bin/activate pytorch-from-source
```

```
# Install requirements for Pytorch and some build tools.
```

```
pip install -r $wd/pytorch-source/requirements.txt
```

```
conda install -y cmake ninja
```

```
# Sometimes we need to solve some library clashes between conda and the system. We force the removal of the conda libstdc++ so that we use the system one.
```

```
rm -rf $wd/miniconda3/envs/pytorch-from-source/lib/libstdc++.so
```

```
# Point to our ROCM installation that is not in a default path.
```

```
grep -rl /opt/rocm | \
```

```
xargs sed -i "s#/opt/rocm#$ROCM_PATH#g"
```

```
# Hipify source
```

```
nice python3 tools/amd_build/build_amd.py
```

```
# Build with debug symbols
```

```
CC=$(which gcc) \
```

```
CXX=$(which g++) \
```

```
CMAKE_PREFIX_PATH=$CONDA_PREFIX:$CMAKE_PREFIX_PATH \
```

```
LDFLAGS="-L$ROCM_PATH/deps -lstdc++ -l'info" \
```

```
USE_KINETO=0 BUILD_TEST=0 \
```

```
PYTORCH_ROCM_ARCH=gfx90a \
```

```
REL_WITH_DEB_INFO=1 \
```

```
nice python3 setup.py bdist_wheel
```

```
pip install $wd/pytorch-source/dist/torch-*.whl
```

Enable/disable the packages you care about.

Build with debug symbols

Pytorch install – Singularity containers

- Control better the Pytorch environment
- Less strain on the filesystem
 - All application installation is loaded as a single file
- Enable more recent ROCm versions
- Transferable and arguably more portable
- Some containers available under:
 - </appl/local/containers/sif-images/>



• Any cons?

- Updating the environment and installing more packages may require rebuild the container
- Containers can't currently be build on LUMI:
 - Needs containers to be built elsewhere and copied to the system
- Submitting jobs has to be done more carefully.

SIF=<myimage.sif>

```
srun --jobid=$jobid -n1 \
singularity exec \
  [-B /var/spool/slurmd \
  -B /opt/cray \
  -B /usr/lib64/libcxi.so.1 \
  -B $wd:/workdir \
  $SIF /workdir/run-me.sh
```

Make relevant pieces of native environment visible inside the container

Make my work directory visible inside the container

The container image

Use helper script to spin the application

Pytorch install – Singularity containers

Example 04

```
SIF=/apl/local/containers/sif-images/lumi-pytorch-rocm-6.1.3-python-3.12-pytorch-v2.4.1.sif
```

```
rm -rf $wd/run-me.sh
```

```
cat > $wd/run-me.sh << EOF
```

```
#!/bin/bash -e
```

```
# Start conda environment inside the container
```

```
\$WITH_CONDA
```

```
# Run application
```

```
python -c 'import torch; print("I have this many devices:", torch.cuda.device_count())'
```

```
EOF
```

```
chmod +x $wd/run-me.sh
```

```
srun --jobid=$jobid -n1 --gpus 8 \
```

```
singularity exec \
```

```
-B /var/spool/slurmd \
```

```
-B /opt/cray \
```

```
-B /usr/lib64/libcxi.so.1 \
```

```
-B $wd:/workdir \
```

```
$SIF /workdir/run-me.sh
```

The container image to use:
Pytorch 2.4.1 on top of ROCm 6.1.3

One could leverage a script to describe what is going to be executed inside the container.

This script has to load the container Conda environment. A special variable is set in the container to facilitate that.

Run as before.

Invoke singularity to start the container and execute the script created above.

Controlling device visibility

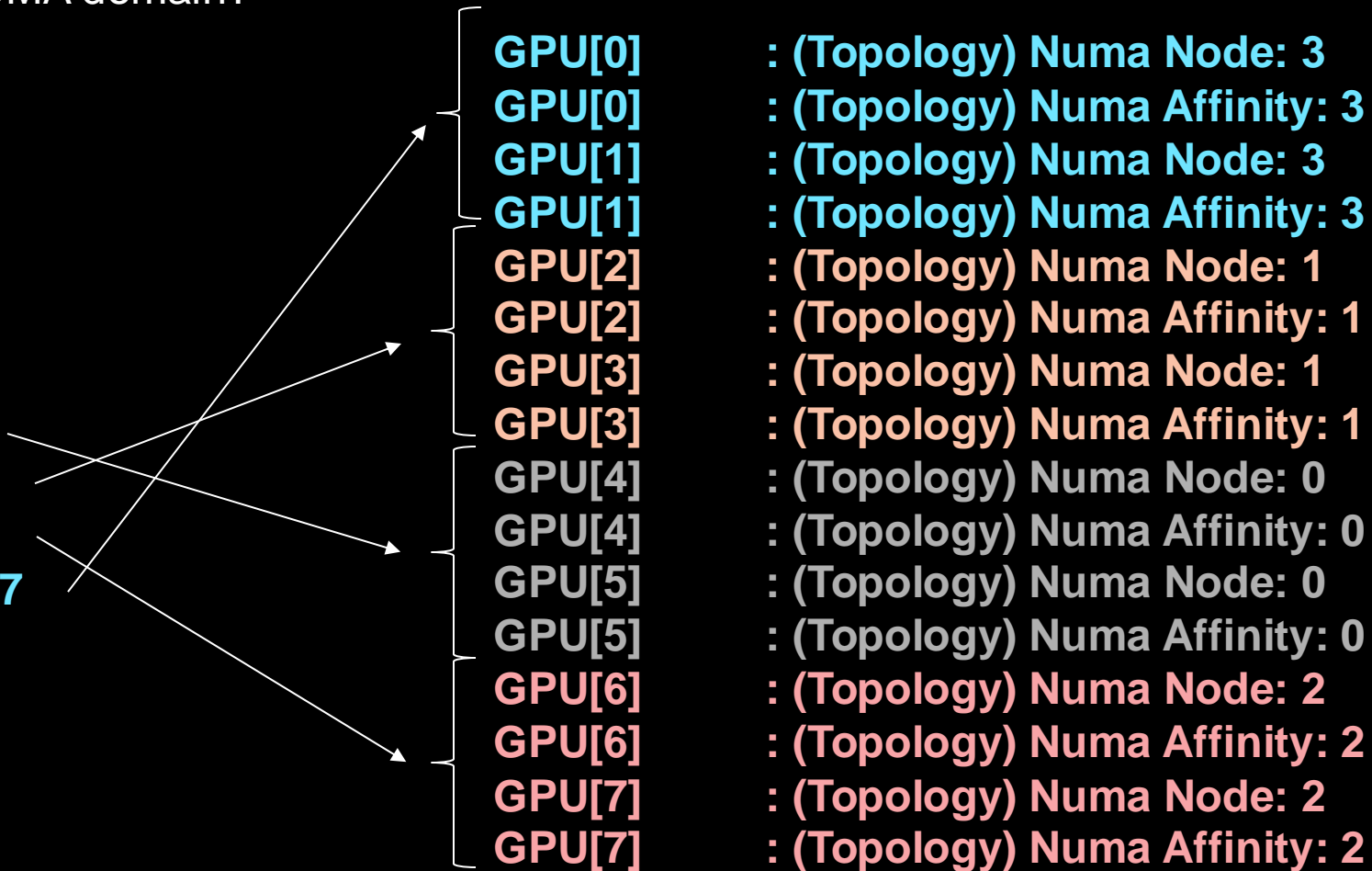
- Controlling visibility
 - `HIP_VISIBLE_DEVICES=0,1,2,3 python -c 'import torch; print(torch.cuda.device_count())'`
 - `ROCR_VISIBLE_DEVICES=0,1,2,3 python -c 'import torch; print(torch.cuda.device_count())'`
 - SLURM sets `ROCR_VISIBLE_DEVICES`
 - Implications of both ways of setting visibility – blit kernels and/or DMA
- Considerations:
 - Does my app expects GPU visibility to be set in the environment?
 - Does my app expects arguments to define target GPUs
 - Does my app make any assumption on the device based on other information:
 - MPI rank
 - CPU-range
 - Auto-determined
 - How many processes using the same GPU:
 - Contention vs occupancy
 - Runtime scheduling limits
 - Increased scheduling complexity
 - Imbalance

Most Pytorch applications and driver scripts assume the GPU to be used corresponds to the local rank!!!

Testing affinity

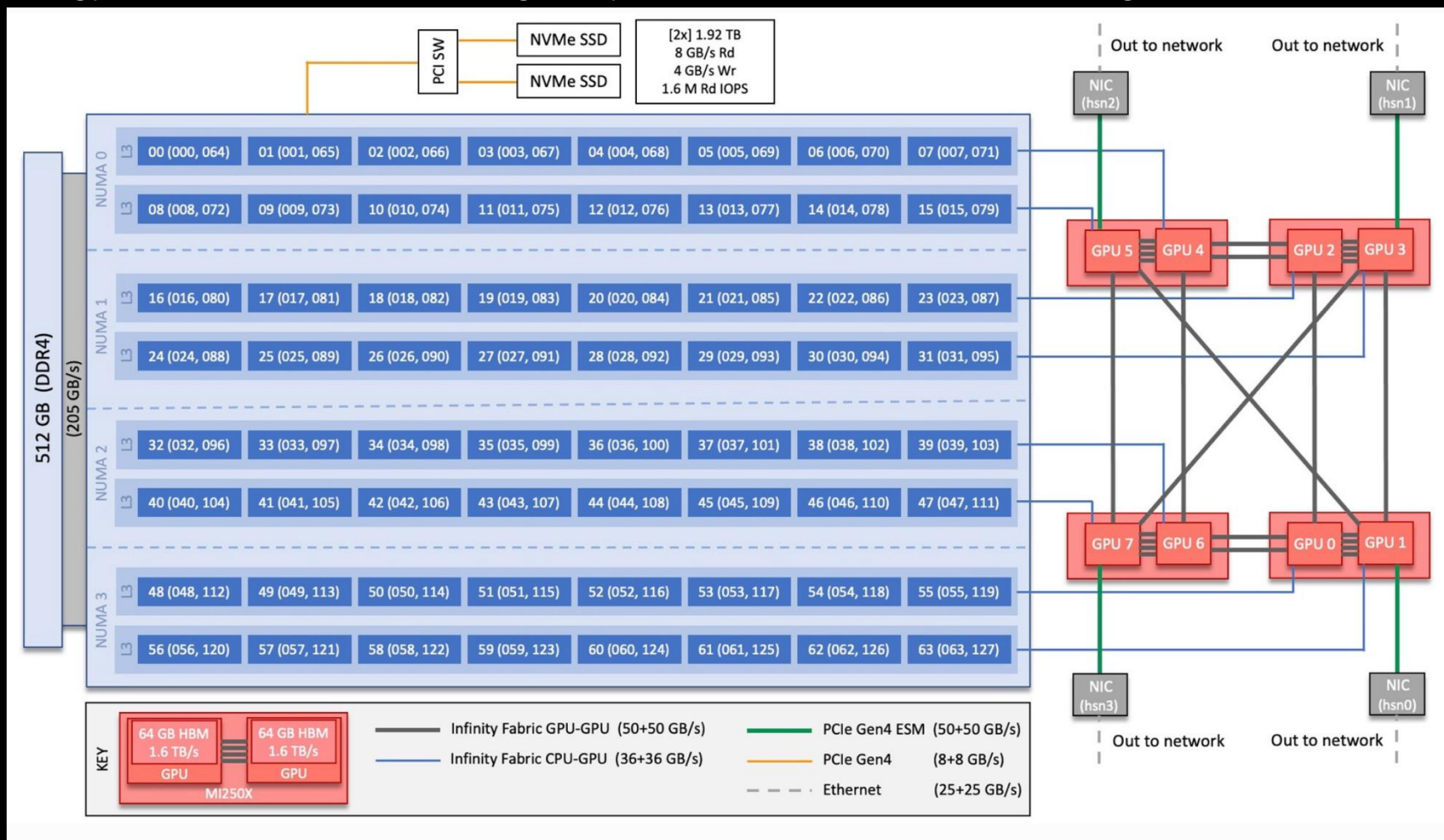
- What CPUs I have available and their NUMA domain?
 - lscpu
- What GPUs I have
 - rocm-smi -showtopo

NUMA node0 CPU(s): 0-15,64-79
NUMA node1 CPU(s): 16-31,80-95
NUMA node2 CPU(s): 32-47,96-111
NUMA node3 CPU(s): 48-63,112-127



Testing affinity

- ORNL topology - https://docs.olcf.ornl.gov/systems/crusher_quick_start_guide.html



Testing affinity

- Check what SLURM is giving us:

```
srun -c 7 -N 2 -n 16 --gpus 16 \
```

```
bash -c 'echo "$SLURM_PROCID -- GPUS $ROCR_VISIBLE_DEVICES -- $(taskset -p $$)' \
```

```
| sort -n -k1
```

```
0 -- GPUS 0,1,2,3,4,5,6,7 -- pid 54249's current affinity mask: fe
1 -- GPUS 0,1,2,3,4,5,6,7 -- pid 54250's current affinity mask: fe00
2 -- GPUS 0,1,2,3,4,5,6,7 -- pid 54251's current affinity mask: fe0000
3 -- GPUS 0,1,2,3,4,5,6,7 -- pid 54252's current affinity mask: fe000000
4 -- GPUS 0,1,2,3,4,5,6,7 -- pid 54253's current affinity mask: fe00000000
5 -- GPUS 0,1,2,3,4,5,6,7 -- pid 54254's current affinity mask: fe0000000000
6 -- GPUS 0,1,2,3,4,5,6,7 -- pid 54255's current affinity mask: fe000000000000
7 -- GPUS 0,1,2,3,4,5,6,7 -- pid 54256's current affinity mask: fe00000000000000
8 -- GPUS 0,1,2,3,4,5,6,7 -- pid 110083's current affinity mask: fe
9 -- GPUS 0,1,2,3,4,5,6,7 -- pid 110084's current affinity mask: fe00
10 -- GPUS 0,1,2,3,4,5,6,7 -- pid 110085's current affinity mask: fe0000
11 -- GPUS 0,1,2,3,4,5,6,7 -- pid 110086's current affinity mask: fe000000
12 -- GPUS 0,1,2,3,4,5,6,7 -- pid 110087's current affinity mask: fe00000000
13 -- GPUS 0,1,2,3,4,5,6,7 -- pid 110088's current affinity mask: fe0000000000
14 -- GPUS 0,1,2,3,4,5,6,7 -- pid 110089's current affinity mask: fe000000000000
15 -- GPUS 0,1,2,3,4,5,6,7 -- pid 110090's current affinity mask: fe00000000000000
```



Example 05

Careful! Allocations do not follow GPU ranking!!

Testing affinity

- Check what SLURM is giving us:

```
srun -N 2 -n 16 --gpus 16 \
--cpu-bind=mask_cpu:0xfe000000000000,0xfe000000000000,0xfe0000,0xfe000000,0xfe,0xfe00,0xfe00000000,0xfe0000000000 \
bash -c 'echo "$SLURM_PROCID -- GPUS $ROCR_VISIBLE_DEVICES -- $(taskset -p $$)'" \
| sort -n -k1
```

```
0 -- GPUS 0,1,2,3,4,5,6,7 -- pid 13819's current affinity mask: fe000000000000
1 -- GPUS 0,1,2,3,4,5,6,7 -- pid 13820's current affinity mask: fe00000000000000
2 -- GPUS 0,1,2,3,4,5,6,7 -- pid 13821's current affinity mask: fe0000
3 -- GPUS 0,1,2,3,4,5,6,7 -- pid 13822's current affinity mask: fe000000
4 -- GPUS 0,1,2,3,4,5,6,7 -- pid 13823's current affinity mask: fe
5 -- GPUS 0,1,2,3,4,5,6,7 -- pid 13824's current affinity mask: fe00
6 -- GPUS 0,1,2,3,4,5,6,7 -- pid 13825's current affinity mask: fe00000000
7 -- GPUS 0,1,2,3,4,5,6,7 -- pid 13826's current affinity mask: fe0000000000
8 -- GPUS 0,1,2,3,4,5,6,7 -- pid 94670's current affinity mask: fe000000000000
9 -- GPUS 0,1,2,3,4,5,6,7 -- pid 94671's current affinity mask: fe00000000000000
10 -- GPUS 0,1,2,3,4,5,6,7 -- pid 94672's current affinity mask: fe0000
11 -- GPUS 0,1,2,3,4,5,6,7 -- pid 94673's current affinity mask: fe000000
12 -- GPUS 0,1,2,3,4,5,6,7 -- pid 94674's current affinity mask: fe
13 -- GPUS 0,1,2,3,4,5,6,7 -- pid 94675's current affinity mask: fe00
14 -- GPUS 0,1,2,3,4,5,6,7 -- pid 94676's current affinity mask: fe00000000
15 -- GPUS 0,1,2,3,4,5,6,7 -- pid 94677's current affinity mask: fe0000000000
```

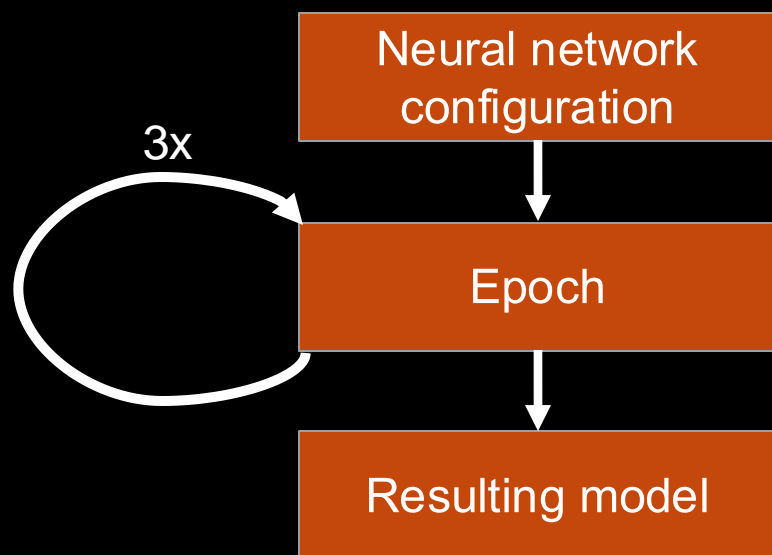


Great! CPUs are properly bound to the GPUs!

Example 05

Pytorch example app – MNIST distributed learning

- Popular computer vision training dataset
- AI training iterate over epochs and a given sample batch is considered in each epoch
- Provided example runs over 3 epochs (properly trained models need much more than than!)
- MNIST training considers number images with different formats.



Pytorch example app – MNIST distributed learning

- What provides distributed capability:
 - Pytorch Distribute Data Parallel (DDP) – Batches of different data run concurrently
 - Other more sophisticated methods available
 - Frameworks like Deepspeed and Horovod can also enable distributed training.

```
import torch.distributed as dist
```

```
...
```

```
dist.init_process_group(
```

```
    backend='nccl',
```

```
    init_method='env://',
```

```
    world_size=int(os.environ['WORLD_SIZE']),
```

```
    rank=int(os.environ['RANK']))
```

Let's use RCCL collectives library.

We'll be learning about the distributed setting from the environment

Capture some env vars to adjust my distributed training

- ... Epoch 0 Loss 0.148397 Global batch size 2048 on 16 ranks
- ... Epoch 1 Loss 0.147906 Global batch size 2048 on 16 ranks
- ... Epoch 2 Loss 0.147717 Global batch size 2048 on 16 ranks

Pytorch example app – MNIST distributed learning – RCCL

- RCCL should be set to use only high-speed-interfaces - Slingshot

- The problem one might see on startup:

```
NCCL error in: /workdir/pytorch-
example/pytorch/torch/csrc/distributed/c10d/ProcessGroupNCCL.cpp:1269, unhandled
system error, NCCL version 2.12.12
```

- Check error origin by setting RCCL specific debug environment variables:

```
export NCCL_DEBUG=INFO
```

```
NCCL INFO NET/Socket : Using [0]nmn0:10.120.116.65<0> [1]hsn0:10.253.6.67<0>
[2]hsn1:10.253.6.68<0> [3]hsn2:10.253.2.12<0> [4]hsn3:10.253.2.11<0>
NCCL INFO /long_pathname_so_that_rpms_can_package_the_debug_info/data/driver/rccl/src/init.cc:1292
```

Node has interfaces other than Slingshot

These are the correct ones.

- The fix:

```
export NCCL_SOCKET_IFNAME=hsn0,hsn1,hsn2,hsn3
```

Point RCCL to use all 4 high-speed interfaces. It will know how to bind them based on the node topology.

Pytorch example app – MNIST distributed learning - script



Example 06

- What can/should I include in my start script:

Smoke test to confirm GPUs are available

```
if [ \${SLURM_LOCALID} -eq 0 ]; then
```

```
rocm-smi
```

```
fi
```

```
export MIOOPEN_USER_DB_PATH="/tmp/${whoami}-miopen-cache-${SLURM_NODEID}"
```

```
export MIOOPEN_CUSTOM_CACHE_DIR=${MIOOPEN_USER_DB_PATH}
```

```
# Report affinity
```

```
echo "Rank \${SLURM_PROCID} --> \${taskset -p \${SLURM_PROCID}}"
```

```
# Start conda environment inside the container
```

```
\${WITH_CONDA}
```

```
# Set interfaces to be used by RCCL.
```

```
export NCCL_SOCKET_IFNAME=hsn0,hsn1,hsn2,hsn3
```

```
# Set environment for the app
```

```
export MASTER_ADDR=$(python /workdir/get-master.py "\${SLURM_NODELIST}")
```

```
export MASTER_PORT=29500
```

```
export WORLD_SIZE=${SLURM_NPROCS}
```

```
export RANK=${SLURM_PROCID}
```

```
export ROCR_VISIBLE_DEVICES=${SLURM_LOCALID}
```

```
# Run app
```

```
cd /workdir/mnist
```

```
python -u mnist_DDP.py --gpu --modelpath /workdir/mnist/model
```

Just-in-time compiles are a common technique in these applications. MIOpen leverages this functionality. Let's cache those builds in node-local storage instead of the default home folder. ROCm 6.2 may not need this.

Activate the container Conda environment that provides Pytorch

Point RCCL to use the high-speed network interfaces

Translate SLURM environment into something that Pytorch DDP understands

Run my model training

Pytorch example app – MNIST distributed learning - rocprof



Example 07

- Rocprof profiler client is the easiest way to get started with GPU profiling.
- It is available as part of the ROCm stack and, therefore, available in the containers
- It is seldomly useful to profile every single process/rank of your app:
 - Profiling more than needed = more potential profiling overhead
 - Misleading conclusions



Command to prepend to my application instantiation

```
pcmd=""
if [ $RANK -eq 2 ] ; then
pcmd='rocprof --hip-trace'
fi
```

We want to profile only for one rank – in this case rank #2

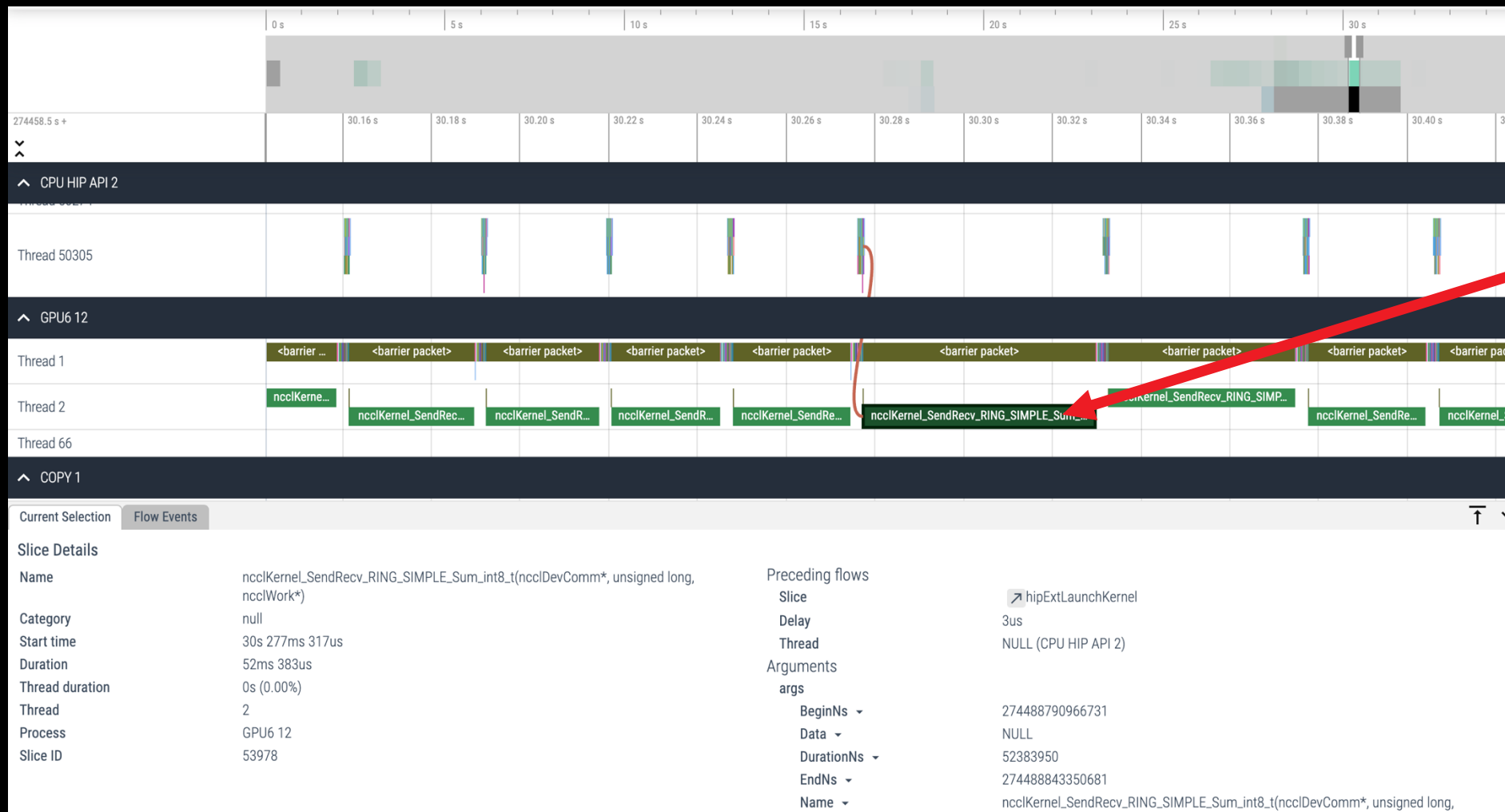
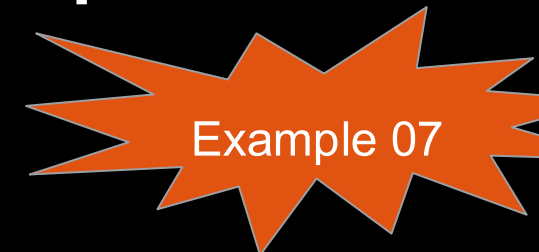
Run command as before except to the prepended profiling command

```
$pcmd python -u mnist_DDP.py --gpu --modelpath /workdir/mnist/model
```

More than one rank to be profiled? Use, `-o myresults.$RANK.csv`, to make sure there are no races generating the profile files

Pytorch example app – MNIST distributed learning - rocprof

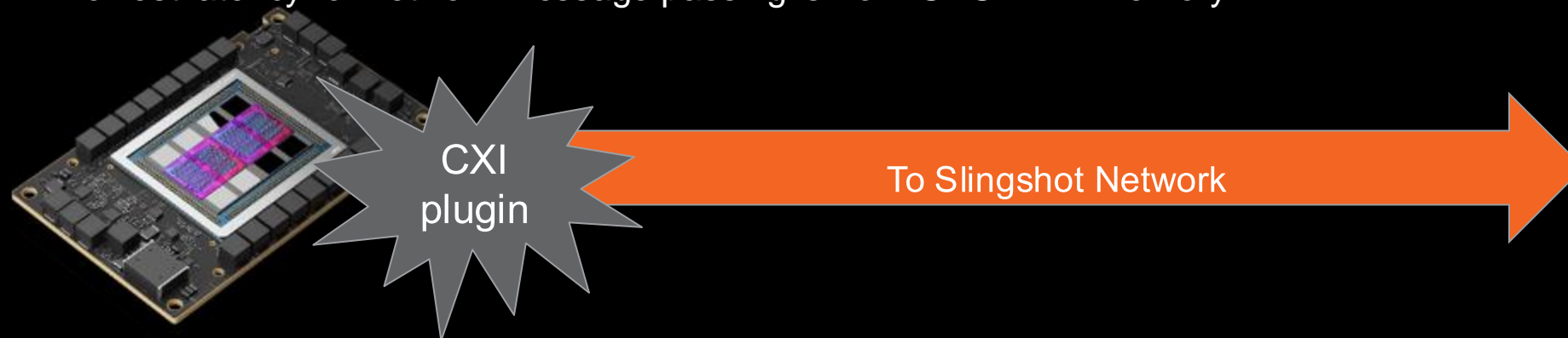
- Bound by RCCL communication!



Collectives kernels dominate profile

Comms are important! - RCCL AWS-CXI plugin

- LUMI, Frontier (and others) directly attaches AMD Instinct™ MI250x Accelerator to the Slingshot Network
 - Enable collectives computation on devices
 - Minimize the role of the CPU in the control path – expose more asynchronous computation opportunities
 - Lowest latency for network message passing is from GPU HBM memory



- CXI plugin is a runtime dependency. Requires: HPE Cray libfabric implementation
 - <https://github.com/rocm/aws-ofi-rccl>
 - 3-4x faster collectives
- **Included in the LUMI provided containers! If not using the LUMI containers make sure you have that in your environment:**

```
export NCCL_DEBUG=INFO
```

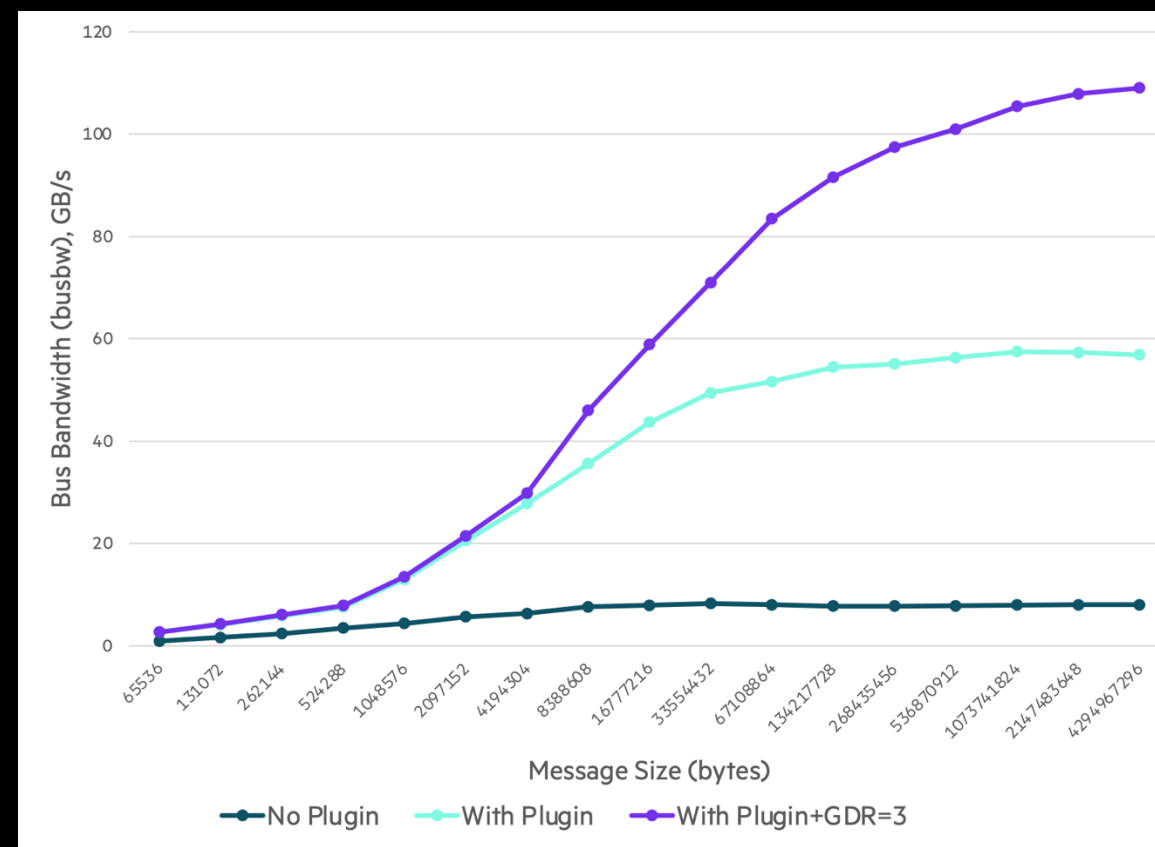
```
export NCCL_DEBUG_SUBSYS=INIT
```

```
# and search the logs for:
```

```
[0] NCCL INFO NET/OFI Using aws-ofi-rccl 1.4.0
```


Configuring RCCL environment (cont.)

- RCCL should be set configured to use GPU RDMA:
 - `export NCCL_NET_GDR_LEVEL=PHB`
- On upcoming ROCm versions (6.2) this won't be needed – it is default.
- Why should I spend time with all this?
 - 3-4x better bandwidth utilization with plugin
 - 2x better bandwidth utilization with RDMA
 - Can scale further!
- **Careful using external containers! You may need to be setting plugin yourself!**



Pytorch example app – MNIST distributed learning – Omnitrace

- Obtain more thorough trace information and visualization
 - <https://github.com/AMDRResearch/omnitrace>
- Omnitrace install outside the container can be used
 - The host/container ROCm levels should match

```
module use module use /appl/local/containers/test-modules
```

```
module load rocm/6.1.3.lua omnitrace/1.12.0-rocm6.1.x
```

```
SIF=/appl/local/containers/sif-images/lumi-pytorch-rocm-6.1.3-python-3.12-pytorch-v2.4.1.sif
```

- Configuration file:
 - `omnitrace-avail -G omnitrace.cfg --all`
 - `export OMNITRACE_CONFIG_FILE=/workdir/omnitrace-config.cfg`
 - Override environment with command line arguments if needed



Example 08-09

Pytorch example app – MNIST distributed learning – Omnitrace



Example 08

- Sample – learn about the native stack trace along side GPU activity
- GPU activity is **never** sampled even in sampling mode
- Adjust configuration file according to the needs:

```
OMNITRACE_USE_SAMPLING = true
OMNITRACE_USE_ROCM_SMI = false
OMNITRACE_SAMPLING_CPUS = none
OMNITRACE_SAMPLING_GPUS = 2
```

Let's do sampling!

Not interested in sampling GPU hardware metrics (frequency, temperature...)

Not interested in sampling CPU hardware metrics

Targeting GPU #2 only used by Rank #2

- Execution similar to rocprof:

```
pcmd=""
if [ $RANK -eq 2 ] ; then
pcmd='omnitrace-sample --'
fi
$pcmd python -u mnist_DDP.py --gpu --modelpath /workdir/mnist/model
```

Prepend omnitrace sampling driver for rank #2

- We need to add a few more bindings to singularity:

```
srun --jobid=$jobid -N $((Nodes)) -n $((Nodes*8)) --gpus $((Nodes*8)) --cpu-bind=mask_cpu:$MYMASKS \
singularity exec \
... \
-B $wd:/workdir \
-B $OMNITRACE_dir/omnitools \
-B /usr/lib64/libpciaccess.so.0 \
$SIF /workdir/run-me.sh
```

Make omnitrace available in the container

Omnitrace does PCIe info loading – so we need to enable that

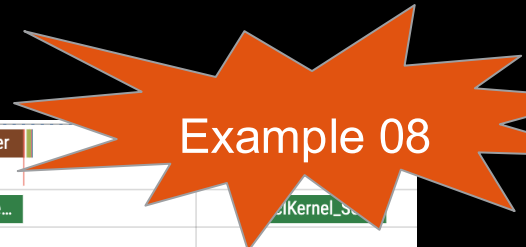
- ...and make sure the environment inside the container is set accordingly:

```
export PATH=$OMNITRACE_dir/bin:$PATH
export LD_LIBRARY_PATH=$OMNITRACE_dir/lib:$LD_LIBRARY_PATH
export PYTHONPATH=$OMNITRACE_dir/lib/python/site-packages:$LD_LIBRARY_PATH
```

Makes sure all Omnitrace bits are available in my environment.

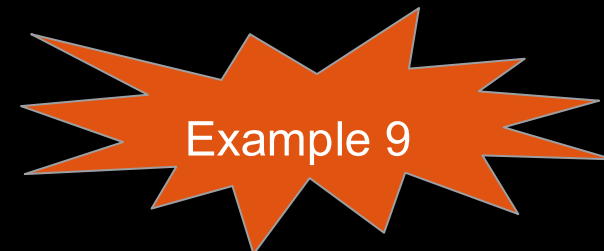
Pytorch example app – MNIST distributed learning – Omnitrace

- Native stack frame graph:

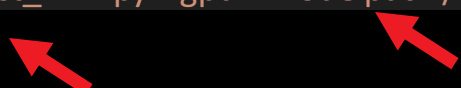


Pytorch example app – MNIST distributed learning – Omnitrace

- Sampling the Python and C/C++ parts of the code – omnitrace-python

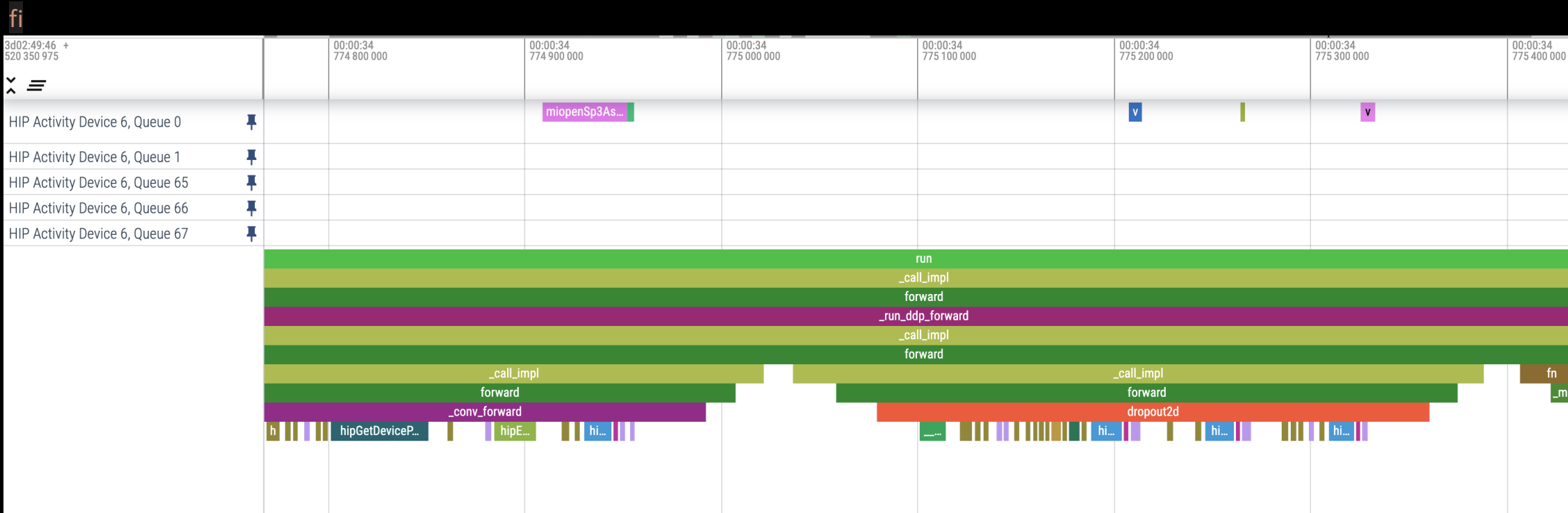


```
if [ \${RANK} -eq 2 ]; then
  omnitrace-python-3.10 -- mnist_DDP.py --gpu --modelpath /workdir/mnist/model
else
```



Omnitrace expects the Python script as opposed to the Python executable

```
python -u mnist_DDP.py --gpu --modelpath /workdir/mnist/model
```



Pytorch example app – MNIST distributed learning – Omniperf



Example 10

- Obtain detailed kernel performance counters
 - <https://github.com/AMDRResearch/omniperf>

```
module use module use /appl/local/containers/test-modules
module load rocm/6.1.3.lua omniperf/2.1.0
```

- Virtual environment is used to extend the existing Python environment inside the container.
- Omniperf needs replaying the application many times
 - Could be challenging to profile individual ranks as all need replaying.

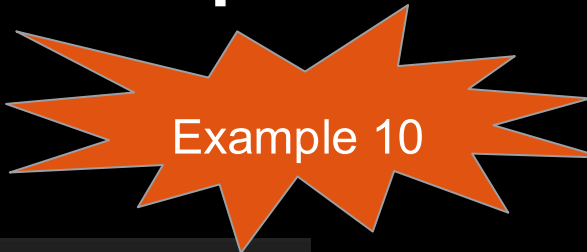
```
if [ $RANK -eq 0 ] ; then
  omniperf profile -n myprof --device 0 --roof-only -- $(which python) -u mnist_DDP.py ...
else
  for i in {1..4} ; do
    sleep 10
    python -u mnist_DDP.py --gpu --modelpath /workdir/mnist/model
  done
fi
```

Collect roofline profile for rank #0 that uses device #0

Replay the app on the other ranks as many times as needed (5 times for roofline)

Pytorch example app – MNIST distributed learning – Omnipperf

- Analyze in or outside the container):
 - omnipperf analyze -p workloads/pytorch/MI200/ --gui



Menu ▾ NORMALIZATION: per_wave ▾ GCD: ALL ▾ DISPATCH FILTER: ALL ▾ TOP N: 10 ▾

KERNELS: × ▾ [Report Bug](#)

Empirical Roofline Analysis (FP32/FP64)

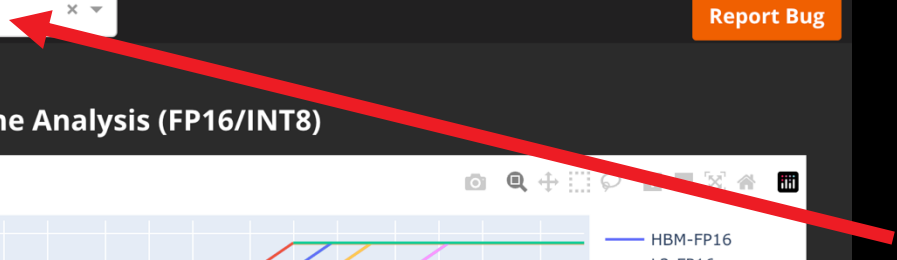
Legend:

- HBM-FP32
- L2-FP32
- L1-FP32
- LDS-FP32
- Peak VALU-FP32
- Peak MFMA-FP32
- ai_l1
- ai_l2
- ai_hbm

Empirical Roofline Analysis (FP16/INT8)

Legend:

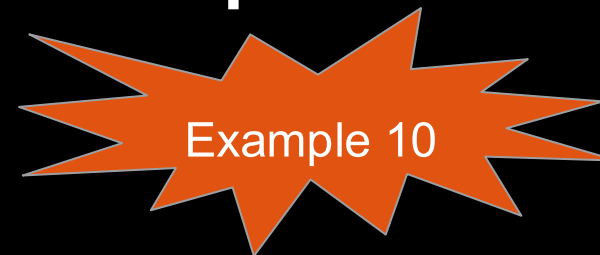
- HBM-FP16
- L2-FP16
- L1-FP16
- LDS-FP16
- Peak MFMA-FP16
- ai_l1
- ai_l2
- ai_hbm
- HBM-I8
- L2-I8
- L1-I8
- LDS-I8
- Peak MFMA-I8



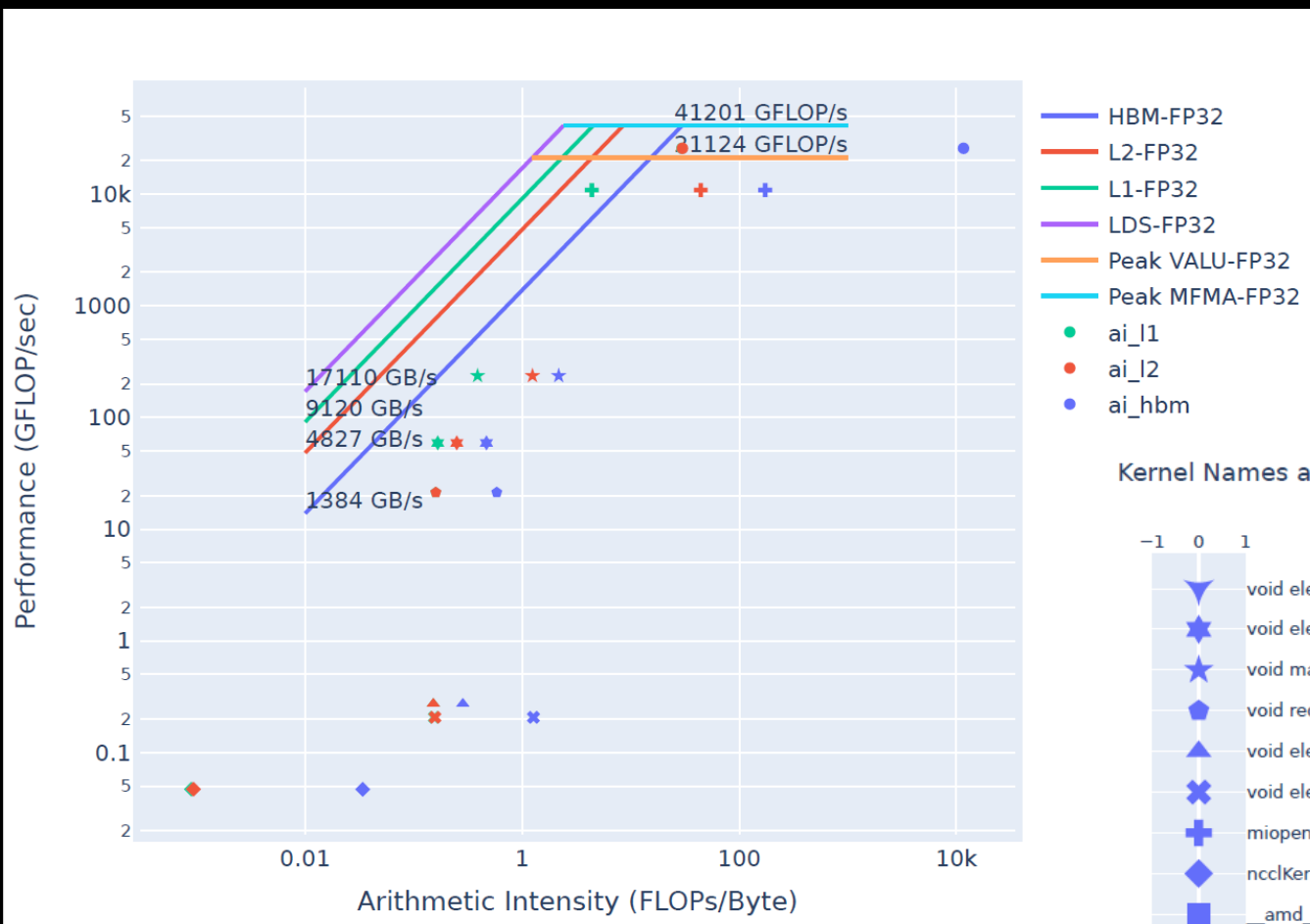
Select kernel of interest

Pytorch example app – MNIST distributed learning – Omniperf

- Analyze in or outside the container):
 - Roofline PDFs



Kernel names



Kernel Names and Markers

Marker	Kernel Name
-1	void elementwise_kernel<launch_clamp_scalar(Scalar, Scalar, lambda(operator)) lambda(operator)) lambda(float)Array >(int, launch_clamp)
0	void elementwise_kernel<128, 4, gpu_kernel_impl(CUDAFunctor_add lambda(int)(int, gpu_kernel_impl(CUDAFunctor_add lambda(int))
1	void max_pool_backward_nchw<float, float>(float const*, long const*, int, long, long, long, int, int, int, int, int, int, int, float*)
▽	void reduce_kernel<512, 1, ReduceOp
★	void elementwise_kernel<BUnaryFunctor, Array >(int, BUnaryFunctor<float, float, float, MulFunctor >, Array<char*, 2>)
☆	void elementwise_kernel<AUnaryFunctor, Array >(int, AUnaryFunctor<float, float, float, MulFunctor >, Array<char*, 2>)
+	miopenSp3AsmConv_v21_1_3_gfx9_fp32_stride1.kd
◆	ncclKernel_SendRecv_RING_SIMPLE_Sum_int8_t(ncclDevComm*, unsigned long, ncclWork*)
■	__amd_roclr_fillBufferAligned.kd
●	miopenSp3AsmConv_v21_1_3_gfx9_fp32_stride1_group.kd

Leveraging framework profiler infrastructure

Example 11

- AI frameworks typically provide hooks for developers to gather profiling information
- An example with Pytorch:

```
from torch.profiler import profile, record_function, ProfilerActivity
```

```
for epoch in range(args.epochs):
```

```
    prof = None
    if epoch == 3:
        print("Starting profile...")
        prof = profile(activities=[ProfilerActivity.CPU, ProfilerActivity.CUDA])
        prof.start()
```

```
    for imgs, labels in dataloader:
        with torch.amp.autocast('cuda', enabled=args.amp):
            imgs, labels = imgs.cuda(), labels.cuda()
            outputs = model(imgs)
            loss = criterion(outputs, labels)
            loss = scaler.scale(loss)
            loss.backward()
            scaler.step(optimizer)
            scaler.update()
```

```
    if prof:
        prof.stop()
        prof.export_chrome_trace("trace.json")
```

Invoke the profiler

Enable profiling for epoch number 3

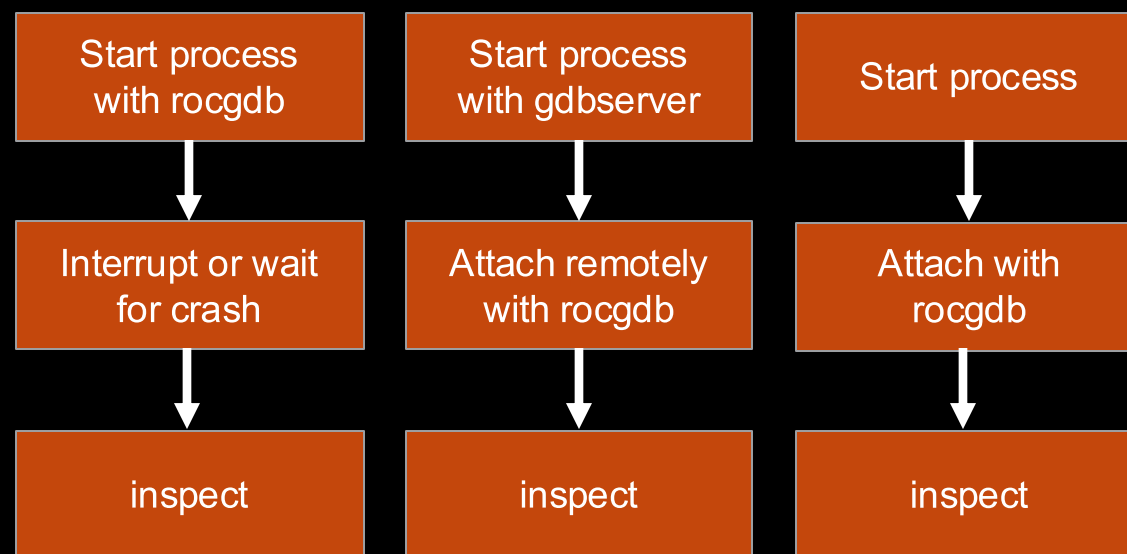
Training for an epoch

Finish profiling and generate trace

Trace file can be viewed in Perfetto UI tool

Pytorch example app – MNIST distributed learning – Rocgdb

- Debugging requires proper driver support
 - Can't run debugger effectively from incompatible containers
 - Use system ROCm for rocgdb
- Two main use cases to use
 - Connecting into a hanging process
 - Progress up to breakpoint or segfault
- ROCm provides rocgdb – you may need your own gdbserver.
- Using gdbserver is possible
 - gdbserver can be issued conveniently as a profile tool
 - Launch with:
 - `gdbserver --once $(hostname):12345 ./my_command`
 - Attach with
 - `rocgdb -x gdb.commands ./my_command`
 - Leverage gdb commands file to automate startup
 - `target remote target_host:12345`



3 different workflows to choose from!

If interested in stepping into GPU code you should avoid gdbserver

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