

INSTALLATIONGUIDE

DSP/BIOS™ LINK

DRA44x/DRX416

LNK 138 USR

Version 1.65.00.03

JUL 12, 2010

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A. INTRODUCTION

1 Purpose

DSP/BIOS™ LINK is foundation software for the inter-processor communication across the GPP-DSP boundary. It provides a generic API that abstracts the characteristics of the physical link connecting GPP and DSP from the applications. It eliminates the need for customers to develop such link from scratch and allows them to focus more on application development.

This document provides the users necessary information to install DSP/BIOS™ LINK on the development host.

This document corresponds to the product release Version 1.65.00.03 dated JUL 12, 2010.

2 TextConventions

| | |
|---|--|
|  | This bullet indicates important information. Please read such text carefully. |
|  | This bullet indicates additional information. |
| [arg1 arg2] | In context of the commands, contents enclosed in square brackets are the optional arguments to the command. Different values of these arguments are separated by " ". |

3 Terms&Abbreviations

| | |
|---------|---|
| CCS | Code Composer Studio |
| IPC | Inter Processor Communication |
| GPP | General Purpose e.g. ARM |
| DSP | Digital Signal Processor e.g. TMS320C5510 |
| CGTools | Code Gen Tools, e.g. Compiler, Linker, Archiver |

4 References

| | | |
|----|--|--|
| 1. | pre-drx40x_psp_user_guid e.doc | DRA44x PrOS PSP user guide - pre-drx40x- rel0.1.0 |
| 2. | drx40x_psp_user_guid e.pdf | REL_DRX40X_PSP_0.6.0 |
| 3. | ReleaseNotes_BS_TI_J ACINTO_EVM(RVCT)(Pr KERNELv4)-en.html | J1_BSP_v1.6.0beta - PrKERNELv4 ver3.1 rev3 |

B. INSTALLATION

5 BasicInstallation

The DSP/BIOS™ LINK is made available as a tar.gz file. To install the product follow the steps below:

1. Unzip and untar the file dsplink_Version 1.65.00.03.tar.gz.

 *This document assumes the install path to be L:\dsplink while working on a Windows PC. This path will be used in remainder of this document.*

 *If the installation was done at different location, make appropriate changes to the commands listed in the document.*

It is advisable to archive the released sources in a configuration management system. This will help in merging:

- The updates delivered in the newer releases of DSP/BIOS™ LINK.
- The changes to the product, if any, done by the users.

5.1 Installing Standalone DSP/BIOS™ 5.32.04 and CG Tools

For compilation of DSP-side sources and applications, the CGTools version 6.0.18 can be used. This release has been validated with DSP/BIOS™ version 5.32.04.

This release will not work with BIOS version earlier than 5.32.01.

Refer to the URL mentioned below for getting the distribution of DSP/BIOS™ and the associated installation instructions.

https://www-a.ti.com/downloads/sds_support/targetcontent/bios/index.html

The directory structure specified in Figure 1 is expected by the build system of DSP/BIOS™ LINK. If you install the tools to a different directory, you will also need to modify the make system and the scripts contained in the release package. You may need to copy the directories to create the structure expected for compiling sources. Refer to section on "Understanding the MAKE System" in the User Guide for details.

5.2 Installing GNU make 3.81

For compilation of DSPLINK sources the GNU make 3.81 can be used. Download the make 3.81 from the URL

<http://ftp.gnu.org/pub/gnu/make/make-3.81.tar.gz>.

The following are the installation steps required to install make on the development host machine.

1. Copy and untar make-3.81.tar.gz to your home directory.
2. cd to make-3.81 directory
3. Type './configure' and press enter to configure the package for your system. Running 'configure' takes awhile. By default, make package's files will be installed in '/usr/local/bin', '/usr/local/man', etc.

You can specify an installation prefix other than ``/usr/local'` by giving ``configure'` the option ``-- prefix=PREFIX'`.

For example,

To install make at `/usr/local/bin`
run the configure command like below.
`./configure --prefix=/usr/local.`

To install make at `/usr/bin`
run the configure command like below.
`./configure --prefix=/usr`

4. Type ``make'` and press enter to compile the package.
5. Optionally, type ``.make check'` and press enter to run any self-tests that come with the package.
6. Type ``make install'` and press enter to install the programs and any data files and documentation.
7. *For additional details refer to `INSTALL` file located under `make-3.81` directory.*

6 Creating development workspace

This document and the scripts included in the release assume the following directory structure on your development host:

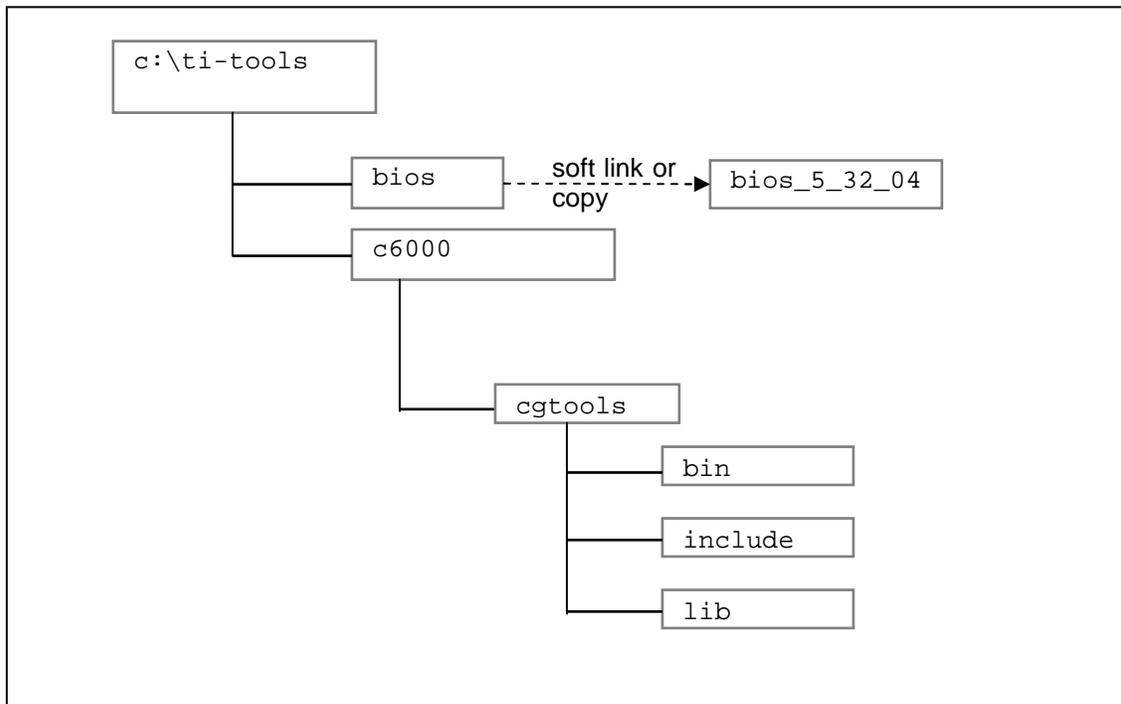


Figure1. Expected directory structure on development host

- For the Windows development host, the build system shipped with DSP/BIOS™ LINK assumes that the standalone DSP/BIOS™ is installed in the 'ti-tools\' directory on the <ROOT-DRIVE> and CGTools is installed in the 'ti-tools\c6000\' directory on the <ROOT-DRIVE>.
- To support multiple installations of DSP/BIOS with a single DSP/BIOS™ LINK DSP-side distribution file, a c:\ti-tools\bios directory is used for the BIOS installation. This can be a soft link or copy to the actual DSP/BIOS installation directory.

7 Configuring CCS

CCS needs to be configured to use the JTAGJet emulator.

8 Configuring eBinder

8.1 Configuring eBinder for DRA40x

eBinder version ver 1.7 needs to be configured to use JTAGJet emulator.

JTAGJet emulator driver available from Signum Systems needs to be installed.

This release has been tested on driver release dated 4/17/2006.

8.2 Configuring eBinder for DRX41x

eBinder version ver 1.7 needs to be configured to use JTAGJet emulator.

JTAGJet emulator driver available from Signum Systems needs to be installed.

C. WORKING ON TARGET PLATFORM

8.1 PrOS

We have to use eBinder IDE for loading and running DSP/BIOS Link through the sample project released in the DRA44x PSP package. Follow the steps given in the PSP release notes on loading and running the sample application.

8.2 Runningthesampleapplications

Sample applications are provided with DSPLINK for the DRA44x platform. All the sample applications are described in detail in the user guide. This section describes the way to execute the sample applications.

The specific instructions shown below refer to the message sample. However, similar instructions can be used for the other applications also.

The steps for execution of the samples are given below for execution with PrOS running on the GPP.

8.3 PrOS

For executing the applications on PrOS, the ARM-side executable must be built to include the sample library. The *DSPLINK* library is included into the sample library. In addition, the sample application must be invoked from within the `pspSysInit.c` file in the PrOS asp-ppsp installation. The `pspSysInit.c` file must be modified to add a task which calls the DSP/BIOS Link sample applications.

8.3.1 Integratingtheapplications

Based on the DSP executable loader to be used, the procedure for usage of the target GPP file system differs.

The COFF loader is used in the default configuration provided with the release. This release has been verified with the `pseudofs` utility.

This release has not been verified with the binary or the static loader. The binary and static loader have been retained for reference.

When the static loader is used, no target file system is required for running the message sample when the DSP static loader is used. In this configuration, the DSP executable gets loaded automatically when the ARM executable is loaded. However, there is a constraint of including only a single DSP executable in the build of the GPP executable.

When the binary loader is used, the DSP binary executable 'file' is required while loading it on the target.

When the COFF or binary loader is used, the DSP file needs to be placed into the target file system. To provide for easy application integration and to satisfy the need of a file system, the release package contains the `pseudofs` utility.

The `pseudofs` utility, as the name suggests, creates a pseudo filesystem by reading from a file and creating a corresponding C array. This utility is present under directory `dsplink\etc\host\tools\generic\pseudofs`. It expects a text file as its input and the text file is expected to contain:

1. The list of files to be included in the `filesystem`.
2. The name of the file generated as the pseudo file-system.

The generated pseudo file-system file can be built with the required files. A sample input file `pseudofs.cfg` containing the list of files to be added in the file-system is included with the release package under directory `dsplink\etc\host\tools\generic\pseudofs\PrOS\Jacinto`. This file includes all the DSP executables, data files and scripts for running the samples or test-suite. It can be modified to comment out the files that are not required to be included into the file system. It can also be modified to include any additional files, or to modify the input paths for the existing files.

After the list of files has been modified, the file system can be built using the following command:

```
L:\> cd dsplink\etc\host\tools\generic\pseudofs
L:\> gmake -s filesystem [debug | release]
```

This command generates the file-system and compiles it. The `FILESYS.LIB` file generated must be included within the build of the PrOS executable.

8.3.2 Building the PrOS executable

The procedure to build the final PrOS executable to be loaded onto the DRA44x EVM is:

1. Ensure that you have the installations for
 - DRA44x :
 - eBinder version ver 1.7 rev with valid licenses.
 - JTAGJet emulator driver available from Signum Systems
 - J1_BSP_v1.6.0beta.zip : Board Support Package(BSP)
 - pre-drx40x-psp-rel0.1.0: TI PSP release.
 - PrF2_ver1.3rev1.zip : PrFILE2 (including RAM disk driver) : "Board Support Package" and consists of board dependent modules.
 - BGX_95V_100_000.zip : Patch for PrFILE2.
 - DRX416 :
 - eBinder version ver 1.7 with valid licenses.
 - JTAGJet emulator driver available from Signum Systems
 - eSOL Board Support Package(BSP)
 - DSP/BIOS patch for J2 (TI internal).
 - TI PSP release REL_DRX40X_PSP_0.6.0.zip (TI internal) supporting eSOL release for DRX41x.
 - TI EDMA release EDMA3_LLD_setupwin32_1_05_00_01.exe
 - PrF2_ver1.3rev1.zip: PrFILE2 (including RAM disk driver): "Board Support Package" and consists of board dependent modules.
 - BGX_95V_100_000.zip: Patch for PrFILE2.
 - BGX_963_100_000.zip.
2. Configure the DSP/BIOS LINK for DRA44x and DRX416

The build configuration command must be executed to configure DSPLink for the various parameters such as platform, GPP OS, build configuration etc.

 - DRA44X for Seudofs

```
perl dsplinkcfg.pl --platform=JACINTO1 --nodsp=1 --
dspcfg_0=DRA44XGEMSHMEM --dspos_0=DSPBIOS5XX --gppos=PROS --
comps=ponslrm --fs=PSEUDOFS
```

- DRA44X for Prfile


```
perl dsplinkcfg.pl --platform=JACINTO1 --nodsp=1 --
dspcfg_0=DRA44XGEMSHMEM --dspos_0=DSPBIOS5XX --gppos=PROS --
comps= ponslrm --fs=PRFILEFS
```

- DRX416 for Pseudofs


```
perl dsplinkcfg.pl --platform=JACINTO2 --nodsp=1 --
dspcfg_0=DRX416GEMSHMEM --dspos_0=DSPBIOS5XX --gppos=PROS --
comps=ponslrm --fs=PSEUDOFS
```

- DRX416 for Prfile


```
perl dsplinkcfg.pl --platform=JACINTO2 --nodsp=1 --
dspcfg_0=DRX416GEMSHMEM --dspos_0=DSPBIOS5XX --gppos=PROS --
comps=ponslrm --fs=PRFILEFS
```

For details please refer user guide

2. Set Environment Variables in Windows :
 - set EB_RDI_DLL=<eBinder_install_folder>:\Signum\RDI\SigJdsRDI.dll
 - set EB_RDI_CFG=<eBinder_install_folder>:\Signum\RDI\SigJdsRDI.cnf
3. Follow the steps given in TI PSP release user guide to create a eBinder project that consumes the PSP sample project. We will be using this Sample Project as a base to run Link samples. DSPLink uses the UART driver for kprintf implementation and MMC/SD driver for PrFile support. Link specific project settings while creating the eBinder project are as follows: Select Custom Configuration in the Project wizard. Accept default configuration for all settings except:
 - Configurations about TMS320DRA446 for DRA44x
OR
 - Configurations about TMS320DRX416 for DRX416
 Remaining settings are similar to those given in the PSP user guide.
4. Update bios_jacintoevm_pagetable_rvct.inc at %eSOL%\eBinder\projects\<<your-project>\build\parts\config\bios_ep\board\jacintoevm\bios for any memory map changes in the project folder to ensure that EMIF where DSP data resides is non cacheable. Below is an indicative entry for DRX416.

```
; EMIFA DATA CS(1:0) SDRAM (0x40000000 - 0x477FFFFFF) 120MB
L1SectionEntry 0x40000000, 0x477FFFFFF, WRITE_BACK

; EMIFA DATA CS(1:0) SDRAM (0x47800000 - 0x5FFFFFFF) 390MB
L1SectionEntry 0x47800000, 0x5FFFFFFF, UNCACHE_UNBUFF
```

5. Modify the pspSysInit.c file within the psp package to call MESSAGE_Main () with the appropriate arguments. The code to call the different samples with different sets of parameters is also shown below. The addresses to be passed for the readwrite example are platform dependant.

Third argument is processor identifier (optional), if it not provided assumed as default processor (zero).

```
MESSAGE_Main ("/opt/message.out", "10000", "0") ;
RING_IO_Main ("/opt/ringio.out", "1024", "10240", "0") ;
```

```

MP_LIST_Main ("/opt/mplist.out", "100", "10", "0") ;
MPCSXFER_Main ("/opt/mpcsxfer.out", "128", "1000", "0") ;
RDWR_Main ("/opt/readwrite.out", "1741664256", 1741664256, "1024",
1024, "10000", 10000, "0") ;
MPCSXFER_Main ("/opt/mpcsxfer.out", "128", "1000", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "1", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "2", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "3", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "4", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "5", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "6", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "7", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "8", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "9", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "10", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "11", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "12", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "13", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "14", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "15", "0") ;
MESSAGEMULTI_Main ("/opt/messagemulti.out", "10000", "16", "0") ;

```

6. Modify the DRA44x PSP project file available with the psp package to link the dsplink libraries. Right click on the project in the Build tab. Select Add Files to project and add the dsplink libraries i.e. DSPLINK.LIB, MESSAGEGPP.LIB etc to the project.

Debug libraries can be added to the Debug Build whereas Release libraries can be added to the Release build.

The libraries need to be associated with File Type ARM Static Library while adding to the project.

7. Follow steps given in PSP user guide to build the sample project file, register the resident unit, setup the target board and load and run the samples.
8. Note the release supports PrFile system as well. To use the MMC/SD driver PSP driver specific initialization needs to be done. The initialization steps are as follows:

DRA44x :

```

#define PINMUX1          *(volatile Uint32 *) (0x01C48104)

PAL_sysModuleClkCtrl(PAL_SYS_CLK_MODULE_MMCSDB, PAL_SYS_MODULE_CLK_ENABLE);

PINMUX1 &= (~((1 << 3) | (1 << 2)));

result = DDA_MMCSDB_DrvInit((92u * 1000u * 1000u), 0, hEdma);

```

```
PAL_osWaitMsecs(2000u);
```

```
DRX416 :
```

```
#define PINMUX0    (*(volatile Uint32 *) (0x01C48100))

PAL_sysModuleClkCtrl(PAL_SYS_CLK_MODULE_MMCSDB, PAL_SYS_MODULE_CLK_ENABLE);

PINMUX0 &= (~((1 << 15) | (1 << 28)));
PINMUX0 |= (1 << 19);

result = DDA_MMCSDB_DrvInit((130u * 1000u * 1000u), 0, hEdma, 0);
```

9. The output from the samples can be seen on the UART terminal. Connect Target COM (UART) to your Local Machine through RS232 Cable. Configure the Hyper-Terminal or TeraTerm (or any Local Windows UART Application) at –
- 115200 BAUD Rate,
 - 8 bit Data, No Parity, No Flow Control & Stop Bit equal to 1
- The above instructions assume that the psp package for DRA44x is used for building and running the applications on PrOS. For a different system, please modify these instructions accordingly.*
- Based on the user requirement, different loaders for the DSP executable can be used. Some loaders require additional changes to the build procedure for the PrOS executable. Instructions for these are available within README.TXT files at:*
- L:\dsplink\etc\host\scripts\msdos\loaderutils\binary*
- L:\dsplink\etc\host\scripts\msdos\loaderutils\static*
- DSPLINK uses DRx40x PSP's kprintf implementation. DSPLINK libraries call kprintf only when PSP "pspUartConsoleOut" function is defined. So system integrators need to update the PRINT_Printf () API in gpp\src\osal\PrOS\print.c, if they don't want to use DRx40x PSP's kprintf and pspUartConsoleOut implementations.*

D. ADDITIONAL INFORMATION

9 Tools and utilities

9.1 binloaderscript

When PrOS is used as the ARM-side Operating System, *DSPLINK* supports different types of DSP executable loaders for loading the DSP executable onto the target.

The `binloader` script is provided to generate the source and header files with information about the DSP executable to be loaded by the binary loader. It also converts the DSP executable from COFF into binary format, which can be loaded by the binary loader.

The files generated are:

1. 'C' file containing an instance of the `BinLoaderImageInfo` structure required by the binary loader. This generated file can be built with the ARM-side example to generate information used by the binary loader.
2. 'H' file containing declaration of the instance of the `BinLoaderImageInfo` structure in the 'C' file. This file can be included by the ARM-side application using the binary loader.
3. 'BIN' file generated through COFF to binary conversion of the DSP executable.
4. 'DAT' file, which is an intermediate file generated by the script and used for conversion of the DSP executable from COFF to binary format. This file is available to the user for reference about the memory map used for generation of the binary file. to load and unload the DSP/BIOS™ LINK device driver on the target platform.

This script is present at the following location within the *DSPLINK* installation:

```
L:\dsplink\etc\host\scripts\msdos\loaderutils\binary
```

Additional information about the script and its usage is provided within the `README.TXT` file present at the same location.

9.2 staticloaderscript

The DRA44x platform has a unified GPP-DSP memory map. When PrOS is used as the ARM-side Operating System, the DSP executable can be built into the ARM-side executable. This optimizes the loading time of the DSP executable on the target, since the DSP executable gets automatically loaded when the ARM executable is loaded onto the target.

The `staticloader` script is provided to generate source and command files corresponding to the DSP executable image specified. These generated files can be statically linked into the ARM-side executable to get a pre-loaded DSP image.

The files generated are:

1. 'C' file containing arrays of DSP sections. This file is generated in the asp-psp source directory for DRA44x, and included in the build.
2. 'H' file containing declarations of the DSP section arrays. This file is generated in `$(DSPLINK)\gpp\inc\PrOS\Jacinto` directory.

3. 'CMD' file containing linker placement of the DSP section arrays. This file is generated in the asp-psp build directory for DRA44x and included in the linker command file for the GPP executable.

This script is present at the following location within the *DSPLINK* installation:

```
L:\dsplink\etc\host\scripts\msdos\loaderutils\static
```

Additional information about the script and its usage is provided within the `README.TXT` file present at the same location.