
INSTALLATIONGUIDE

DSP/BIOS™ LINK**DRA44x + DM6437****LNK 138 USR****1.65.00.03****JUL 12, 2010**

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TABLE OF CONTENTS

A.	INTRODUCTION	7
1	Purpose	7
2	Text Conventions	7
3	Terms & Abbreviations	7
4	References	7
B.	INSTALLATION	8
5	Basic Installation	8
5.1	Installing Standalone DSP/BIOS™ 5.32.04 and CGTools	8
5.2	Installing GNU make 3.81	8
6	Creating development workspace	9
6.1	Tools Directory Structure Layout (User-Defined)	11
7	Configuring CCS	11
8	Configuring eBinder	11
8.1	Configuring eBinder for DRA40x	11
C.	FLASHING DM6437	13
D.	WORKING ON TARGET PLATFORM	14
8.1	PrOS	14
8.2	Running the sample applications	14
8.3	PrOS	14
E.	ADDITIONAL INFORMATION	19
9	Tools and utilities	19
9.1	binloader script	19
9.2	staticloader script	19

TABLE OF FIGURES

Figure 1.	Expected directory structure on development host.....	10
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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 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	Jacinto 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_sla_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:

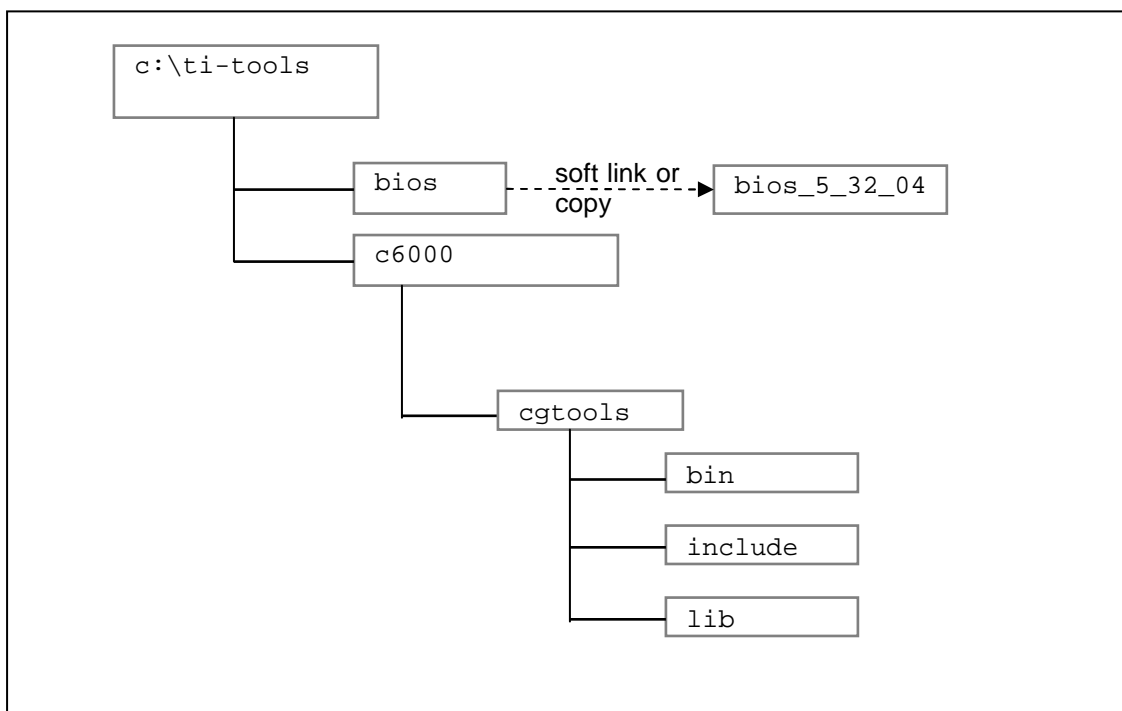


Figure1. Expected directory structure on development host

- 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.

6.1 ToolsDirectoryStructureLayout(User-Defined)

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 can define the following environment variables on your desktop (My Computer -> Right Click -> Properties -> Advanced -> Environment Variables -> System Variables):

ENV variable name	Purpose	Example	Default
TI_TOOLS_BASE_DIR	Defines the base directory for the TI Tools. This should be defined only when your TI Tools are not under C:\ti_tools as the scripts and makefile expect. Refer to Figure 1 for more information.	c:\my_tools\ti_tools	C:\ti-tools
BIOS_INSTALL_DIR	Defines the base directory where the bios is located. This should be defined only when bios is not located under C:\ti-tools\bios or \$(TI_TOOLS_BASE_DIR)\bios	c:\my_tools\bios_5_32_04	C:\ti-tools\bios
XDCROOT	Defines the base directory of XDC tools. This should be defined only when the XDC tools are not located in xdctools directory under your bios installation (i.e. \$(BIOS_INSTALL_DIR)\xdctools).	C:\xdctools	C:\titools\bios\xdctools
CGTOOLS_INSTALL_DIR	Defines the base directory (not the bin the directory) for your CGTools installation. This should be defined only when the CGTools are not located under C:\titools\c6000\cgtools or \$(TI_TOOLS_BASE_DIR)\C6000\cgtools	C:\C6000_v3_10_05	C:\titools\C6000\cgtools
BASE_PERL	Defines the base directory (not the bin directory) for your Perl installation	C:\my_tools\Perl	C:\Perl

Alternatively, you can also 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.

7 ConfiguringCCS

CCS needs to be configured to use the JTAGJet emulator.

8 ConfiguringeBinder

8.1 ConfiguringeBinderforDRA40x

eBinder version ver 1.7 rev0 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 02/23/2009.

C. FLASHING DM6437

Refer to platform guide on VLYNQ related setup details.

D. 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 Jacinto 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-psp 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 filesys [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 rev0 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.
2. Configure the DSP/BIOS LINK for DRA44x.
The build configuration command must be executed to configure DSPLink for the various parameters such as platform, GPP OS, build configuration etc.

- DRA44X for Pseudofs


```
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=DM6437VLYNQ
--dspos_0=DSPBIOS5XX --gppos=PROS --comps=mrl --fs=PSEUDOFS
```
- DRA44X and DM6437 over VLYNQ for Pseudofs


```
perl dsplinkcfg.pl --platform=JACINTO1 --nodsp=2 --
dspcfg_0=DRA44XGEMSHMEM --dspos_0=DSPBIOS5XX --
dspcfg_1=DM6437VLYNQ --dspos_1=DSPBIOS5XX --gppos=PROS --
comps=ponslrm --fs=PSEUDOFS
```
- DRA44X and DM6437 over VLYNQ for Prfile


```
perl dsplinkcfg.pl --platform=JACINTO1 --nodsp=2 --
dspcfg_0=DRA44XGEMSHMEM --dspos_0=DSPBIOS5XX --
dspcfg_1=DM6437VLYNQ --dspos_1=DSPBIOS5XX --gppos=PROS --
comps=ponslrm --fs=PSEUDOFS
```

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.
 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 DRA44x.

```
; EMIFB DATA CS(1:0) SDRAM (0x67A00000 - 0x7FFFFFFF) 400MB
    L1SectionEntry 0x67A00000, 0x7FFFFFFF, UNCACHE_UNBUFF
    ELSE
; Reserved (0x60000000 - 0x7FFFFFFF) 512MB
    L1SectionEntry 0x60000000, 0x7FFFFFFF, ACCESS_DISABLE
    ENDIF
```

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);
```

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 kprnitf and pspUartConsoleOut implementations.*

E. 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.