

# ***TMS320C55x DSP/BIOS 5.x Application Programming Interface (API) Reference Guide***

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## Read This First

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### ***About This Manual***

DSP/BIOS gives developers of mainstream applications on Texas Instruments TMS320C5000™ DSP devices the ability to develop embedded real-time software. DSP/BIOS provides a small firmware real-time library and easy-to-use tools for real-time tracing and analysis.

You should read and become familiar with the *TMS320 DSP/BIOS User's Guide*, a companion volume to this API reference guide.

Before you read this manual, you may use the *Code Composer Studio* online tutorial and the DSP/BIOS section of the online help to get an overview of DSP/BIOS. This manual discusses various aspects of DSP/BIOS in depth and assumes that you have at least a basic understanding of DSP/BIOS.

### ***Notational Conventions***

This document uses the following conventions:

- Program listings, program examples, and interactive displays are shown in a special typeface. Examples use a **bold version** of the special typeface for emphasis; interactive displays use a **bold version** of the special typeface to distinguish commands that you enter from items that the system displays (such as prompts, command output, error messages, etc.).

Here is a sample program listing:

```
Void copy(HST_Obj *input, HST_Obj *output)
{
    PIP_Obj      *in, *out;
    Uns          *src, *dst;
    Uns          size;
}
```

- ❑ Square brackets ( [ and ] ) identify an optional parameter. If you use an optional parameter, you specify the information within the brackets. Unless the square brackets are in a **bold** typeface, do not enter the brackets themselves.

## **Related Documentation From Texas Instruments**

The following books describe TMS320 devices and related support tools. To obtain a copy of any of these TI documents, call the Texas Instruments Literature Response Center at (800) 477-8924. When ordering, please identify the book by its title and literature number.

**TMS320 DSP/BIOS User's Guide** (literature number SPRU423) provides an overview and description of the DSP/BIOS real-time operating system.

**TMS320C55x Optimizing C Compiler User's Guide** (literature number SPRU281) describes the C55x C compiler. This C compiler accepts ANSI standard C source code and produces TMS320 assembly language source code for the C55x generation of devices.

**TMS320C55x Programmer's Guide** (literature number SPRU376) describes ways to optimize C and assembly code for the TMS320C55x DSPs and includes application program examples.

**TMS320C55x Code Composer Studio Tutorial Online Help** (literature number SPRH097) introduces the Code Composer Studio integrated development environment and software tools. Of special interest to DSP/BIOS users are the *Using DSP/BIOS* lessons.

## **Related Documentation**

You can use the following books to supplement this reference guide:

**The C Programming Language** (second edition), by Brian W. Kernighan and Dennis M. Ritchie, published by Prentice-Hall, Englewood Cliffs, New Jersey, 1988

**Programming in C**, Kochan, Steve G., Hayden Book Company

**Programming Embedded Systems in C and C++**, by Michael Barr, Andy Oram (Editor), published by O'Reilly & Associates; ISBN: 1565923545, February 1999

**Real-Time Systems**, by Jane W. S. Liu, published by Prentice Hall; ISBN: 013099651, June 2000

***Principles of Concurrent and Distributed Programming*** (Prentice Hall International Series in Computer Science), by M. Ben-Ari, published by Prentice Hall; ISBN: 013711821X, May 1990

***American National Standard for Information Systems-Programming Language C*** X3.159-1989, American National Standards Institute (ANSI standard for C); (out of print)

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February 26, 2009



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# API Functional Overview

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This chapter provides an overview to the TMS320C55x DSP/BIOS API functions.

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## 1.1 DSP/BIOS Modules

Table 1-1. DSP/BIOS Modules

Module	Description
ATM Module	Atomic functions written in assembly language
BUF Module	Maintains buffer pools of fixed size buffers
C55 Module	Target-specific functions
CLK Module	System clock manager
DEV Module	Device driver interface
GBL Module	Global setting manager
GIO Module	I/O module used with IOM mini-drivers
HOOK Module	Hook function manager
HST Module	Host channel manager
HWI Module	Hardware interrupt manager
IDL Module	Idle function and processing loop manager
LCK Module	Resource lock manager
LOG Module	Event Log manager
MBX Module	Mailboxes manager
MEM Module	Memory manager
MSGQ Module	Variable-length message manager
PIP Module	Buffered pipe manager
POOL Module	Allocator interface module
PRD Module	Periodic function manager
PWRM Module	Reduce application's power consumption
QUE Module	Queue manager
RTDX Module	Real-time data exchange manager
SEM Module	Semaphores manager
SIO Module	Stream I/O manager
STS Module	Statistics object manager
SWI Module	Software interrupt manager
SYS Module	System services manager
TRC Module	Trace manager
TSK Module	Multitasking manager
std.h and stdlib.h functions	Standard C library I/O functions

## 1.2 Naming Conventions

The format for a DSP/BIOS operation name is a 3- or 4-letter prefix for the module that contains the operation, an underscore, and the action.

## 1.3 Assembly Language Interface Overview

The assembly interface that was provided for some of the DSP/BIOS APIs has been deprecated. They are no longer documented.

Assembly functions can call C functions. Remember that the C compiler adds an underscore prefix to function names, so when calling a C function from assembly, add an underscore to the beginning of the C function name. For example, call `_myfunction` instead of `myfunction`. See the *TMS320C55x Optimizing Compiler User's Guide* for more details.

When you are using the DSP/BIOS Configuration Tool, use a leading underscore before the name of any C function you configure. (The DSP/BIOS Configuration Tool generates assembly code, but does not add the underscore automatically.) If you are using `Tconf`, do not add an underscore before the function name; `Tconf` internally adds the underscore needed to call a C function from assembly.

All DSP/BIOS APIs follow standard C calling conventions as documented in the C programmer's guide for the device you are using.

DSP/BIOS APIs save and restore context for each thread during a context switch. Your code should simply follow standard C register usage conventions. Code written in assembly language should be written to conform to the register usage model specified in the C compiler manual for your device. When writing assembly language, take special care to make sure the C context is preserved. For example, if you change the AMR register on the 'C6000, you should be sure to change it back before returning from your assembly language routine. See the Register Usage appendix in this book to see how DSP/BIOS uses specific registers.

## 1.4 DSP/BIOS Tconf Overview

The section describing each module in this manual lists properties that can be configured in `Tconf` scripts, along with their types and default values. The sections on manager properties and instance properties also provide `Tconf` examples that set each property.

For details on `Tconf` scripts, see the *DSP/BIOS Tconf User's Guide* (SPRU007). The language used is JavaScript with an object model specific to the needs of DSP/BIOS configuration.

In general, property names of Module objects are in all uppercase letters. For example, "STACKSIZE". Property names of Instance objects begin with a lowercase word. Subsequent words have their first letter capitalized. For example, "stackSize".

Default values for many properties are dependent on the values of other properties. The defaults shown are those that apply if related property values have not been modified. Default values for many HWI properties are different for each instance.

The data types shown for the properties are not used as syntax in Tconf scripts. However, they do indicate the type of values that are valid for each property. The types used are as follows:

- ❑ **Arg.** Arg properties hold arguments to pass to program functions. They may be strings, integers, labels, or other types as needed by the program function.
- ❑ **Bool.** You may assign a value of either true or 1 to set a Boolean property to true. You may assign a value of either false or 0 (zero) to set a Boolean property to false. Do not set a Boolean property to the quoted string "true" or "false".
- ❑ **EnumInt.** Enumerated integer properties accept a set of valid integer values. These values are displayed in a drop-down list in the DSP/BIOS Configuration Tool.
- ❑ **EnumString.** Enumerated string properties accept certain string values. These values are displayed in a drop-down list in the DSP/BIOS Configuration Tool.
- ❑ **Extern.** Properties that hold function names use the Extern type. In order to specify a function Extern, use the prog.extern() method as shown in the examples to refer to objects defined as asm, C, or C++ language symbols. The default language is C.
- ❑ **Int16.** Integer properties hold 16-bit unsigned integer values. The value range accepted for a property may have additional limits.
- ❑ **Int32.** Long integer properties hold 32-bit unsigned integer values. The value range accepted for a property may have additional limits.
- ❑ **Numeric.** Numeric properties hold either 32-bit signed or unsigned values or decimal values, as appropriate for the property.
- ❑ **Reference.** Properties that reference other configures objects contain an object reference. Use the prog.get() method to specify a reference to another object.
- ❑ **String.** String properties hold text strings.

## 1.5 List of Operations

Table 1-2. DSP/BIOS Operations

### ATM module operations

Function	Operation
ATM_andi, ATM_andu	Atomically AND memory location with mask and return previous value
ATM_cleari, ATM_clearu	Atomically clear memory location and return previous value
ATM_deci, ATM_decu	Atomically decrement memory and return new value
ATM_inci, ATM_incu	Atomically increment memory and return new value
ATM_ori, ATM_oru	Atomically OR memory location with mask and return previous value
ATM_seti, ATM_setu	Atomically set memory and return previous value

### BUF module operations

Function	Operation
BUF_alloc	Allocate a fixed memory buffer out of the buffer pool
BUF_create	Dynamically create a buffer pool
BUF_delete	Delete a dynamically created buffer pool
BUF_free	Free a fixed memory buffer into the buffer pool
BUF_maxbuff	Check the maximum number of buffers used from the buffer pool
BUF_stat	Determine the status of a buffer pool (buffer size, number of free buffers, total number of buffers in the pool)

### C55 operations

Function	Operation
C55_disableIER0, C55_disableIER1, C55_disableInt	Disable certain maskable interrupts
C55_enableIER0, C55_enableIER1, C55_enableInt	Enable certain maskable interrupts
C55_l2AckInt	Acknowledge an L2 interrupt (OMAP 2320/2420 only)

<b>Function</b>	<b>Operation</b>
C55_I2DisableMIR, C55_I2DisableMIR1	Disable certain level 2 interrupts (OMAP 2320/2420 only)
C55_I2EnableMIR, C55_I2EnableMIR1	Enable certain level 2 interrupts (OMAP 2320/2420 only)
C55_I2SetIntPriority	Set the priority of an L2 interrupt (OMAP 2320/2420 only)
C55_plug	C function to plug an interrupt vector

---

### *CLK module operations*

<b>Function</b>	<b>Operation</b>
CLK_countspms	Number of hardware timer counts per millisecond
CLK_cpuCyclesPerHtime	Return multiplier for converting high-res time to CPU cycles
CLK_cpuCyclesPerLtime	Return multiplier for converting low-res time to CPU cycles
CLK_gethtime	Get high-resolution time
CLK_getltime	Get low-resolution time
CLK_getprd	Get period register value
CLK_reconfig	Reset timer period and registers
CLK_setTimerFunc	Assign function to a 'C5505 timer
CLK_start	Restart the low-resolution timer
CLK_stop	Halt the low-resolution timer

---

### *DEV module operations*

<b>Function</b>	<b>Operation</b>
DEV_createDevice	Dynamically creates device with user-defined parameters
DEV_deleteDevice	Deletes the dynamically created device
DEV_match	Match a device name with a driver
Dxx_close	Close device
Dxx_ctrl	Device control operation
Dxx_idle	Idle device

---



<b>Function</b>	<b>Operation</b>
Dxx_init	Initialize device
Dxx_issue	Send a buffer to the device
Dxx_open	Open device
Dxx_ready	Check if device is ready for I/O
Dxx_reclaim	Retrieve a buffer from a device
DGN Driver	Software generator driver
DGS Driver	Stackable gather/scatter driver
DHL Driver	Host link driver
DIO Driver	Class driver
DNL Driver	Null driver
DOV Driver	Stackable overlap driver
DPI Driver	Pipe driver
DST Driver	Stackable split driver
DTR Driver	Stackable streaming transformer driver

### *GBL module operations*

<b>Function</b>	<b>Operation</b>
GBL_getClkin	Get configured value of board input clock in KHz
GBL_getFrequency	Get current frequency of the CPU in KHz
GBL_getProclId	Get configured processor ID used by MSGQ
GBL_getVersion	Get DSP/BIOS version information
GBL_setFrequency	Set frequency of CPU in KHz for DSP/BIOS
GBL_setProclId	Set configured value of processor ID used by MSGQ

### *GIO module operations*

---

<b>Function</b>	<b>Operation</b>
GIO_abort	Abort all pending input and output
GIO_control	Device-specific control call
GIO_create	Allocate and initialize a GIO object
GIO_delete	Delete underlying IOM mini-drivers and free GIO object and its structure
GIO_flush	Drain output buffers and discard any pending input
GIO_new	Initialize a pre-allocated GIO object
GIO_read	Synchronous read command
GIO_submit	Submit a GIO packet to the mini-driver
GIO_write	Synchronous write command

---

### *HOOK module operations*

---

<b>Function</b>	<b>Operation</b>
HOOK_getenv	Get environment pointer for a given HOOK and TSK combination
HOOK_setenv	Set environment pointer for a given HOOK and TSK combination

---

### *HST module operations*

---

<b>Function</b>	<b>Operation</b>
HST_getpipe	Get corresponding pipe object

---

### *HWI module operations*

---

<b>Function</b>	<b>Operation</b>
HWI_disable	Globally disable hardware interrupts
HWI_dispatchPlug	Plug the HWI dispatcher
HWI_enable	Globally enable hardware interrupts
HWI_enter	Hardware interrupt service routine prolog

---

<b>Function</b>	<b>Operation</b>
HWI_exit	Hardware interrupt service routine epilog
HWI_isHWI	Check to see if called in the context of an HWI
HWI_restore	Restore global interrupt enable state

### *IDL module operations*

<b>Function</b>	<b>Operation</b>
IDL_run	Make one pass through idle functions

### *LCK module operations*

<b>Function</b>	<b>Operation</b>
LCK_create	Create a resource lock
LCK_delete	Delete a resource lock
LCK_pend	Acquire ownership of a resource lock
LCK_post	Relinquish ownership of a resource lock

### *LOG module operations*

<b>Function</b>	<b>Operation</b>
LOG_disable	Disable a log
LOG_enable	Enable a log
LOG_error/LOG_message	Write a message to the system log
LOG_event	Append an unformatted message to a log
LOG_printf	Append a formatted message to a message log
LOG_reset	Reset a log

*MBX module operations*

---

<b>Function</b>	<b>Operation</b>
MBX_create	Create a mailbox
MBX_delete	Delete a mailbox
MBX_pend	Wait for a message from mailbox
MBX_post	Post a message to mailbox

---

*MEM module operations*

---

<b>Function</b>	<b>Operation</b>
MEM_alloc, MEM_valloc, MEM_calloc	Allocate from a memory heap
MEM_define	Define a new memory heap
MEM_free	Free a block of memory
MEM_getBaseAddress	Get base address of a memory heap
MEM_increaseTableSize	Increase the internal MEM table size
MEM_redefine	Redefine an existing memory heap
MEM_stat	Return the status of a memory heap
MEM_undefine	Undefine an existing memory segment

---

*MSGQ module operations*

---

<b>Function</b>	<b>Operation</b>
MSGQ_alloc	Allocate a message. Performed by writer.
MSGQ_close	Closes a message queue. Performed by reader.
MSGQ_count	Return the number of messages in a message queue
MSGQ_free	Free a message. Performed by reader.
MSGQ_get	Receive a message from the message queue. Performed by reader.
MSGQ_getAttrs	Get attributes of a message queue.
MSGQ_getDstQueue	Get destination message queue field in a message.

---

<b>Function</b>	<b>Operation</b>
MSGQ_getMsgId	Return the message ID from a message.
MSGQ_getMsgSize	Return the message size from a message.
MSGQ_getSrcQueue	Extract the reply destination from a message.
MSGQ_isLocalQueue	Return whether queue is local.
MSGQ_locate	Synchronously find a message queue. Performed by writer.
MSGQ_locateAsync	Asynchronously find a message queue. Performed by writer.
MSGQ_open	Opens a message queue. Performed by reader.
MSGQ_put	Place a message on a message queue. Performed by writer.
MSGQ_release	Release a located message queue. Performed by writer.
MSGQ_setErrorHandler	Set up handling of internal MSGQ errors.
MSGQ_setMsgId	Sets the message ID in a message.
MSGQ_setSrcQueue	Sets the reply destination in a message.

### *PIP module operations*

<b>Function</b>	<b>Operation</b>
PIP_alloc	Get an empty frame from a pipe
PIP_free	Recycle a frame that has been read back into a pipe
PIP_get	Get a full frame from a pipe
PIP_getReaderAddr	Get the value of the readerAddr pointer of the pipe
PIP_getReaderNumFrames	Get the number of pipe frames available for reading
PIP_getReaderSize	Get the number of words of data in a pipe frame
PIP_getWriterAddr	Get the value of the writerAddr pointer of the pipe
PIP_getWriterNumFrames	Get the number of pipe frames available to be written to
PIP_getWriterSize	Get the number of words that can be written to a pipe frame
PIP_peek	Get the pipe frame size and address without actually claiming the pipe frame
PIP_put	Put a full frame into a pipe
PIP_reset	Reset all fields of a pipe object to their original values
PIP_setWriterSize	Set the number of valid words written to a pipe frame

*PRD module operations*

---

<b>Function</b>	<b>Operation</b>
PRD_getticks	Get the current tick counter
PRD_start	Arm a periodic function for one-time execution
PRD_stop	Stop a periodic function from execution
PRD_tick	Advance tick counter, dispatch periodic functions

---

*PWRM module operations*

---

<b>Function</b>	<b>Operation</b>
PWRM_changeSetpoint	Initiate a change to the V/F setpoint
PWRM_configure	Set new configuration parameters for PWRM
PWRM_getCapabilities	Get information on PWRM's capabilities on the current platform
PWRM_getCurrentSetpoint	Get the current setpoint in effect
PWRM_getDependencyCount	Get count of dependencies currently declared on a resource
PWRM_getNumSetpoints	Get the number of setpoints supported for the current platform
PWRM_getSetpointInfo	Get the corresponding frequency and CPU core voltage for a setpoint
PWRM_getTransitionLatency	Get the latency to scale between setpoints
PWRM_idleClocks	Immediately idle the clock domains
PWRM_registerNotify	Register a function to be called on a specific power event
PWRM_releaseDependency	Release a dependency that has been previously declared
PWRM_setDependency	Declare a dependency upon a resource
PWRM_sleepDSP	Transition the DSP to a new sleep state
PWRM_unregisterNotify	Unregister for an event notification from PWRM

---

*QUE module operations*

<b>Function</b>	<b>Operation</b>
QUE_create	Create an empty queue
QUE_delete	Delete an empty queue
QUE_dequeue	Remove from front of queue (non-atomically)
QUE_empty	Test for an empty queue
QUE_enqueue	Insert at end of queue (non-atomically)
QUE_get	Get element from front of queue (atomically)
QUE_head	Return element at front of queue
QUE_insert	Insert in middle of queue (non-atomically)
QUE_new	Set a queue to be empty
QUE_next	Return next element in queue (non-atomically)
QUE_prev	Return previous element in queue (non-atomically)
QUE_put	Put element at end of queue (atomically)
QUE_remove	Remove from middle of queue (non-atomically)

*RTDX module operations*

<b>Function</b>	<b>Operation</b>
RTDX_channelBusy	Return status indicating whether a channel is busy
RTDX_CreateInputChannel	Declare input channel structure
RTDX_CreateOutputChannel	Declare output channel structure
RTDX_disableInput	Disable an input channel
RTDX_disableOutput	Disable an output channel
RTDX_enableInput	Enable an input channel
RTDX_enableOutput	Enable an output channel
RTDX_isInputEnabled	Return status of the input data channel
RTDX_isOutputEnabled	Return status of the output data channel
RTDX_read	Read from an input channel

<b>Function</b>	<b>Operation</b>
RTDX_readNB	Read from an input channel without blocking
RTDX_sizeofInput	Return the number of bytes read from an input channel
RTDX_write	Write to an output channel

---

*SEM module operations*

<b>Function</b>	<b>Operation</b>
SEM_count	Get current semaphore count
SEM_create	Create a semaphore
SEM_delete	Delete a semaphore
SEM_new	Initialize a semaphore
SEM_pend	Wait for a counting semaphore
SEM_pendBinary	Wait for a binary semaphore
SEM_post	Signal a counting semaphore
SEM_postBinary	Signal a binary semaphore
SEM_reset	Reset semaphore

---

*SIO module operations*

<b>Function</b>	<b>Operation</b>
SIO_bufsize	Size of the buffers used by a stream
SIO_create	Create stream
SIO_ctrl	Perform a device-dependent control operation
SIO_delete	Delete stream
SIO_flush	Idle a stream by flushing buffers
SIO_get	Get buffer from stream
SIO_idle	Idle a stream
SIO_issue	Send a buffer to a stream
SIO_put	Put buffer to a stream

---



---

<b>Function</b>	<b>Operation</b>
SIO_ready	Determine if device for stream is ready
SIO_reclaim	Request a buffer back from a stream
SIO_reclaimx	Request a buffer and frame status back from a stream
SIO_segid	Memory section used by a stream
SIO_select	Select a ready device
SIO_staticbuf	Acquire static buffer from stream

---

### *STS module operations*

---

<b>Function</b>	<b>Operation</b>
STS_add	Add a value to a statistics object
STS_delta	Add computed value of an interval to object
STS_reset	Reset the values stored in an STS object
STS_set	Store initial value of an interval to object

---

### *SWI module operations*

---

<b>Function</b>	<b>Operation</b>
SWI_andn	Clear bits from SWI's mailbox and post if becomes 0
SWI_andnHook	Specialized version of SWI_andn
SWI_create	Create a software interrupt
SWI_dec	Decrement SWI's mailbox and post if becomes 0
SWI_delete	Delete a software interrupt
SWI_disable	Disable software interrupts
SWI_enable	Enable software interrupts
SWI_getattr	Get attributes of a software interrupt
SWI_getmbox	Return SWI's mailbox value
SWI_getpri	Return an SWI's priority mask
SWI_inc	Increment SWI's mailbox and post
SWI_isSWI	Check to see if called in the context of a SWI

---

## List of Operations

---

<b>Function</b>	<b>Operation</b>
SWI_or	Set or mask in an SWI's mailbox and post
SWI_orHook	Specialized version of SWI_or
SWI_post	Post a software interrupt
SWI_raisepri	Raise an SWI's priority
SWI_restorepri	Restore an SWI's priority
SWI_self	Return address of currently executing SWI object
SWI_setattr	Set attributes of a software interrupt

---

## *SYS module operations*

<b>Function</b>	<b>Operation</b>
SYS_abort	Abort program execution
SYS_atexit	Stack an exit handler
SYS_error	Flag error condition
SYS_exit	Terminate program execution
SYS_printf, SYS_sprintf, SYS_vprintf, SYS_vsprintf	Formatted output
SYS_putchar	Output a single character

---

## *TRC module operations*

<b>Function</b>	<b>Operation</b>
TRC_disable	Disable a set of trace controls
TRC_enable	Enable a set of trace controls
TRC_query	Test whether a set of trace controls is enabled

---

## *TSK module operations*

<b>Function</b>	<b>Operation</b>
TSK_checkstacks	Check for stack overflow
TSK_create	Create a task ready for execution
TSK_delete	Delete a task
TSK_deltatime	Update task STS with time difference

---

---

<b>Function</b>	<b>Operation</b>
TSK_disable	Disable DSP/BIOS task scheduler
TSK_enable	Enable DSP/BIOS task scheduler
TSK_exit	Terminate execution of the current task
TSK_getenv	Get task environment
TSK_geterr	Get task error number
TSK_getname	Get task name
TSK_getpri	Get task priority
TSK_getsts	Get task STS object
TSK_isTSK	Check to see if called in the context of a TSK
TSK_itick	Advance system alarm clock (interrupt only)
TSK_self	Returns a handle to the current task
TSK_setenv	Set task environment
TSK_seterr	Set task error number
TSK_setpri	Set a task execution priority
TSK_settime	Set task STS previous time
TSK_sleep	Delay execution of the current task
TSK_stat	Retrieve the status of a task
TSK_tick	Advance system alarm clock
TSK_time	Return current value of system clock
TSK_yield	Yield processor to equal priority task

---

### *C library stdlib.h*

---

<b>Function</b>	<b>Operation</b>
atexit	Registers one or more exit functions used by exit
calloc	Allocates memory block initialized with zeros
exit	Calls the exit functions registered in atexit
free	Frees memory block
getenv	Searches for a matching environment string
malloc	Allocates memory block
realloc	Resizes previously allocated memory block

---

*DSP/BIOS std.h special utility C macros*

---

<b>Function</b>	<b>Operation</b>
ArgToInt(arg)	Casting to treat Arg type parameter as integer (Int) type on the given target
ArgToPtr(arg)	Casting to treat Arg type parameter as pointer (Ptr) type on the given target

---

# Application Program Interface

This chapter describes the DSP/BIOS API modules and functions.

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## 2.1 ATM Module

The ATM module includes assembly language functions.

### Functions

- ❑ ATM\_andi, ATM\_andu. AND memory and return previous value
- ❑ ATM\_cleari, ATM\_clearu. Clear memory and return previous value
- ❑ ATM\_deci, ATM\_decu. Decrement memory and return new value
- ❑ ATM\_inci, ATM\_incu. Increment memory and return new value
- ❑ ATM\_ori, ATM\_oru. OR memory and return previous value
- ❑ ATM\_seti, ATM\_setu. Set memory and return previous value

### Description

ATM provides a set of assembly language functions that are used to manipulate variables with interrupts disabled. These functions can therefore be used on data shared between tasks, and on data shared between tasks and interrupt routines.

**ATM\_andi***Atomically AND Int memory location and return previous value***C Interface**

<b>Syntax</b>	<code>ival = ATM_andi(idst, isrc);</code>
<b>Parameters</b>	<code>volatile Int *idst; /* pointer to integer */</code> <code>Int isrc; /* integer mask */</code>
<b>Return Value</b>	<code>Int ival; /* previous value of *idst */</code>

**Description**

ATM\_andi atomically ANDs the mask contained in isrc with a destination memory location and overwrites the destination value \*idst with the result as follows:

```
`interrupt disable`  
ival = *idst;  
*idst = ival & isrc;  
`interrupt enable`  
return(ival);
```

ATM\_andi is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

ATM\_andu  
ATM\_ori

**ATM\_andu***Atomically AND Uns memory location and return previous value***C Interface**

**Syntax**                    uval = ATM\_andu(udst, usrc);

**Parameters**                volatile Uns \*udst;     /\* pointer to unsigned \*/  
                              Uns            usrc;                /\* unsigned mask \*/

**Return Value**              Uns            uval;                /\* previous value of \*udst \*/

**Description**

ATM\_andu atomically ANDs the mask contained in usrc with a destination memory location and overwrites the destination value \*udst with the result as follows:

```
`interrupt disable`  
uval = *udst;  
*udst = uval & usrc;  
`interrupt enable`  
return(uval);
```

ATM\_andu is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

ATM\_andi  
ATM\_oru



**ATM\_cleari***Atomically clear Int memory location and return previous value***C Interface**

<b>Syntax</b>	<code>ival = ATM_cleari(idst);</code>
<b>Parameters</b>	<code>volatile Int *dst; /* pointer to integer */</code>
<b>Return Value</b>	<code>Int ival; /* previous value of *dst */</code>

**Description**

ATM\_cleari atomically clears an Int memory location and returns its previous value as follows:

```
`interrupt disable`  
ival = *dst;  
*dst = 0;  
`interrupt enable`  
return (ival);
```

ATM\_cleari is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

ATM\_clearu  
ATM\_seti

**ATM\_clearu***Atomically clear Uns memory location and return previous value***C Interface**

**Syntax**                    uval = ATM\_clearu(udst);

**Parameters**                volatile Uns \*udst;     /\* pointer to unsigned \*/

**Return Value**              Uns                    uval;     /\* previous value of \*udst \*/

**Description**

ATM\_clearu atomically clears an Uns memory location and returns its previous value as follows:

```
`interrupt disable`  
uval = *udst;  
*udst = 0;  
`interrupt enable`  
return (uval);
```

ATM\_clearu is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

ATM\_cleari  
ATM\_setu

**ATM\_deci***Atomically decrement Int memory and return new value***C Interface**

**Syntax**                   ival = ATM\_deci(idst);

**Parameters**           volatile Int    \*idst;     /\* pointer to integer \*/

**Return Value**         Int            ival;     /\* new value after decrement \*/

**Description**

ATM\_deci atomically decrements an Int memory location and returns its new value as follows:

```
`interrupt disable`  
ival = *idst - 1;  
*idst = ival;  
`interrupt enable`  
return (ival);
```

ATM\_deci is written in assembly language, efficiently disabling interrupts on the target processor during the call.

Decrementing a value equal to the minimum signed integer results in a value equal to the maximum signed integer.

**See Also**

ATM\_decu  
ATM\_inci

**ATM\_decu***Atomically decrement Uns memory and return new value***C Interface****Syntax**`uval = ATM_decu(udst);`**Parameters**`volatile Uns *udst; /* pointer to unsigned */`**Return Value**`Uns uval; /* new value after decrement */`**Description**

ATM\_decu atomically decrements a Uns memory location and returns its new value as follows:

```
`interrupt disable`  
uval = *udst - 1;  
*udst = uval;  
`interrupt enable`  
return (uval);
```

ATM\_decu is written in assembly language, efficiently disabling interrupts on the target processor during the call.

Decrementing a value equal to the minimum unsigned integer results in a value equal to the maximum unsigned integer.

**See Also**

ATM\_deci  
ATM\_incu

**ATM\_inci***Atomically increment Int memory and return new value***C Interface****Syntax**`ival = ATM_inci(idst);`**Parameters**`volatile Int *idst; /* pointer to integer */`**Return Value**`Int ival; /* new value after increment */`**Description**

ATM\_inci atomically increments an Int memory location and returns its new value as follows:

```
`interrupt disable`  
ival = *idst + 1;  
*idst = ival;  
`interrupt enable`  
return (ival);
```

ATM\_inci is written in assembly language, efficiently disabling interrupts on the target processor during the call.

Incrementing a value equal to the maximum signed integer results in a value equal to the minimum signed integer.

**See Also**

ATM\_deci  
ATM\_incu

**ATM\_incu***Atomically increment Uns memory and return new value***C Interface****Syntax**`uval = ATM_incu(udst);`**Parameters**`volatile Uns *udst; /* pointer to unsigned */`**Return Value**`Uns uval; /* new value after increment */`**Description**

ATM\_incu atomically increments an Uns memory location and returns its new value as follows:

```
`interrupt disable`  
uval = *udst + 1;  
*udst = uval;  
`interrupt enable`  
return (uval);
```

ATM\_incu is written in assembly language, efficiently disabling interrupts on the target processor during the call.

Incrementing a value equal to the maximum unsigned integer results in a value equal to the minimum unsigned integer.

**See Also**

ATM\_decu  
ATM\_inci

**ATM\_ori***Atomically OR Int memory location and return previous value***C Interface**

<b>Syntax</b>	<code>ival = ATM_ori(idst, isrc);</code>
<b>Parameters</b>	<code>volatile Int *idst; /* pointer to integer */</code> <code>Int isrc; /* integer mask */</code>
<b>Return Value</b>	<code>Int ival; /* previous value of *idst */</code>

**Description**

ATM\_ori atomically ORs the mask contained in isrc with a destination memory location and overwrites the destination value \*idst with the result as follows:

```
`interrupt disable`  
ival = *idst;  
*idst = ival | isrc;  
`interrupt enable`  
return(ival);
```

ATM\_ori is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

ATM\_andi  
ATM\_oru

**ATM\_oru***Atomically OR Uns memory location and return previous value***C Interface**

**Syntax** `uval = ATM_oru(udst, usrc);`

**Parameters** `volatile Uns *udst; /* pointer to unsigned */`  
`Uns usrc; /* unsigned mask */`

**Return Value** `Uns uva; /* previous value of *udst */`

**Description**

ATM\_oru atomically ORs the mask contained in usrc with a destination memory location and overwrites the destination value \*udst with the result as follows:

```
`interrupt disable`  
uval = *udst;  
*udst = uval | usrc;  
`interrupt enable`  
return(uval);
```

ATM\_oru is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

ATM\_andu  
ATM\_ori



**ATM\_seti***Atomically set Int memory and return previous value***C Interface**

<b>Syntax</b>	<code>iold = ATM_seti(idst, inew);</code>
<b>Parameters</b>	<code>volatile Int *idst; /* pointer to integer */</code> <code>Int inew; /* new integer value */</code>
<b>Return Value</b>	<code>Int iold; /* previous value of *idst */</code>

**Description**

ATM\_seti atomically sets an Int memory location to a new value and returns its previous value as follows:

```
`interrupt disable`  
ival = *idst;  
*idst = inew;  
`interrupt enable`  
return (ival);
```

ATM\_seti is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

ATM\_setu  
ATM\_cleari

**ATM\_setu***Atomically set Uns memory and return previous value***C Interface**

**Syntax**                    uold = ATM\_setu(udst, unew);

**Parameters**                volatile Uns \*udst;    /\* pointer to unsigned \*/  
                              Uns            unew;            /\* new unsigned value \*/

**Return Value**             Uns        uold;            /\* previous value of \*udst \*/

**Description**

ATM\_setu atomically sets an Uns memory location to a new value and returns its previous value as follows:

```
`interrupt disable`  
uval = *udst;  
*udst = unew;  
`interrupt enable`  
return (uval);
```

ATM\_setu is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

ATM\_clearu  
ATM\_seti

## 2.2 BUF Module

The BUF module maintains buffer pools of fixed-size buffers.

### Functions

- ❑ `BUF_alloc`. Allocate a fixed-size buffer from the buffer pool
- ❑ `BUF_create`. Dynamically create a buffer pool
- ❑ `BUF_delete`. Delete a dynamically-created buffer pool
- ❑ `BUF_free`. Free a fixed-size buffer back to the buffer pool
- ❑ `BUF_maxbuff`. Get the maximum number of buffers used in a pool
- ❑ `BUF_stat`. Get statistics for the specified buffer pool

### Constants, Types, and Structures

```
typedef unsigned long MEM_sizep;

#define BUF_ALLOCSTAMP 0xcafe
#define BUF_FREESTAMP 0xbeef

typedef struct BUF_Obj {
    Ptr startaddr; /* Start addr of buffer pool */
    MEM_sizep size; /* Size before alignment */
    MEM_sizep postalignsize; /* Size after align */
    Ptr nextfree; /* Ptr to next free buffer */
    Uns totalbuffers; /* # of buffers in pool*/
    Uns freebuffers; /* # of free buffers in pool */
    Int segid; /* Mem seg for buffer pool */
} BUF_Obj, *BUF_Handle;

typedef struct BUF_Attrs {
    Int segid; /* segment for element allocation */
} BUF_Attrs;

BUF_Attrs BUF_ATTRS = { /* default attributes */
    0,
};

typedef struct BUF_Stat {
    MEM_sizep postalignsize; /* Size after align */
    MEM_sizep size; /* Original size of buffer */
    Uns totalbuffers; /* Total buffers in pool */
    Uns freebuffers; /* # of free buffers in pool */
} BUF_Stat;
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the BUF Manager Properties and BUF Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

## Module Configuration Parameters

Name	Type	Default (Enum Options)
OBJMEMSEG	Reference	prog.get("DARAM")

## Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
bufSeg	Reference	prog.get("DARAM")
bufCount	Int32	1
size	Int32	4 ('C55x)
align	Int32	2 ('C55x)
len	Int32	4 ('C55x)
postalignsize	Int32	4 ('C55x)

## Description

The BUF module maintains pools of fixed-size buffers. These buffer pools can be created statically or dynamically. Dynamically-created buffer pools are allocated from a dynamic memory heap managed by the MEM module. Applications typically allocate buffer pools statically when size and alignment constraints are known at design time. Run-time allocation is used when these constraints vary during execution.

Within a buffer pool, all buffers have the same size and alignment. Although each frame has a fixed length, the application can put a variable amount of data in each frame, up to the length of the frame. You can create multiple buffer pools, each with a different buffer size.

Buffers can be allocated and freed from a pool as needed at run-time using the BUF\_alloc and BUF\_free functions.

The advantages of allocating memory from a buffer pool instead of from the dynamic memory heaps provided by the MEM module include:

- ❑ **Deterministic allocation times.** The BUF\_alloc and BUF\_free functions require a constant amount of time. Allocating and freeing memory through a heap is not deterministic.
- ❑ **Callable from all thread types.** Allocating and freeing buffers is atomic and non-blocking. As a result, BUF\_alloc and BUF\_free can be called from all types of DSP/BIOS threads: HWI, SWI, TSK, and IDL. In contrast, HWI and SWI threads cannot call MEM\_alloc.
- ❑ **Optimized for fixed-length allocation.** In contrast MEM\_alloc is optimized for variable-length allocation.

## BUF Manager Properties

- ❑ **Less fragmentation.** Since the buffers are of fixed-size, the pool does not become fragmented.

The following global properties can be set for the BUF module in the BUF Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **Object Memory.** The memory segment to contain all BUF objects. (A BUF object may be stored in a different location than the buffer pool memory itself.)  
 Tconf Name: OBJMEMSEG Type: Reference  
 Example: `bios.BUF.OBJMEMSEG = prog.get("myMEM");`

## BUF Object Properties

The following properties can be set for a buffer pool object in the BUF Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script. To create an BUF object in a configuration script, use the following syntax:

```
var myBuf = bios.BUF.create("myBUF");
```

The Tconf examples that follow assume the object has been created as shown.

- ❑ **comment.** Type a comment to identify this BUF object.  
 Tconf Name: comment Type: String  
 Example: `myBuf.comment = "my BUF";`
- ❑ **Memory segment for buffer pool.** Select the memory segment in which the buffer pool is to be created. The linker decides where in the segment the buffer pool starts.  
 Tconf Name: bufSeg Type: Reference  
 Example: `myBuf.bufSeg = prog.get("myMEM");`
- ❑ **Buffer count.** Specify the number of fixed-length buffers to create in this pool.  
 Tconf Name: bufCount Type: Int32  
 Example: `myBuf.bufCount = 128;`
- ❑ **Buffer size.** Specify the size (in MADUs) of each fixed-length buffer inside this buffer pool. The default size shown is the minimum valid value for that platform. This size may be adjusted to accommodate the alignment in the "Buffer size after alignment" property.  
 Tconf Name: size Type: Int32  
 Example: `myBuf.size = 4;`

- ❑ **Buffer alignment.** Specify the alignment boundary for fixed-length buffers in the pool. Each buffer is aligned on boundaries with a multiple of this number. The default size shown is the minimum valid value for that platform. The value must be a power of 2.

Tconf Name: align Type: Int32

Example: `myBuf.align = 2;`
  
- ❑ **Buffer pool length.** The actual length of the buffer pool (in MADUs) is calculated by multiplying the Buffer count by the Buffer size after alignment. You cannot modify this value directly.

Tconf Name: len Type: Int32

Example: `myBuf.len = 4;`
  
- ❑ **Buffer size after alignment.** This property shows the modified Buffer size after applying the alignment. For example, if the Buffer size is 9 and the alignment is 4, the Buffer size after alignment is 12 (the next whole number multiple of 4 after 9).

Tconf Name: postalignsize Type: Int32

Example: `myBuf.postalignsize = 4;`

**BUF\_alloc***Allocate a fixed-size buffer from a buffer pool***C Interface**

**Syntax**                    bufaddr = BUF\_alloc(buf);

**Parameters**                BUF\_Handle buf;        /\* buffer pool object handle \*/

**Return Value**              Ptr                    bufaddr; /\* pointer to free buffer \*/

**Reentrant**                 yes

**Description**              BUF\_alloc allocates a fixed-size buffer from the specified buffer pool and returns a pointer to the buffer. BUF\_alloc does not initialize the allocated buffer space.

The buf parameter is a handle to identify the buffer pool object, from which the fixed size buffer is to be allocated. If the buffer pool was created dynamically, the handle is the one returned by the call to BUF\_create. If the buffer pool was created statically, the handle can be referenced as shown in the example that follows.

If buffers are available in the specified buffer pool, BUF\_alloc returns a pointer to the buffer. If no buffers are available, BUF\_alloc returns NULL.

The BUF module manages synchronization so that multiple threads can share the same buffer pool for allocation and free operations.

The time required to successfully execute BUF\_alloc is deterministic (constant over multiple calls).

**Example**

```
extern BUF_Obj bufferPool;
BUF_Handle buffPoolHandle = &bufferPool;

Ptr buffPtr;

/* allocate a buffer */
buffPtr = BUF_alloc(buffPoolHandle);
if (buffPtr == NULL ) {
    SYS_abort("BUF_alloc failed");
}
```

**See Also**                    BUF\_free  
MEM\_alloc

**BUF\_create***Dynamically create a buffer pool***C Interface**

**Syntax** `buf = BUF_create(numbuff, size, align, attrs);`

**Parameters**

Uns	numbuff;	/* number of buffers in the pool */
MEM_sizep	size;	/* size of a single buffer in the pool */
Uns	align;	/* alignment for each buffer in the pool */
BUF_Attrs	*attrs;	/* pointer to buffer pool attributes */

**Return Value** `BUF_Handle buf;` /\* buffer pool object handle \*/

**Reentrant** no

**Description** BUF\_create creates a buffer pool object dynamically. The parameters correspond to the properties available for statically-created buffer pools, which are described in the BUF Object Properties topic.

The numbuff parameter specifies how many fixed-length buffers the pool should contain. This must be a non-zero number.

The size parameter specifies how long each fixed-length buffer in the pool should be in MADUs. This must be a non-zero number. The size you specify is adjusted as needed to meet the alignment requirements, so the actual buffer size may be larger. The MEM\_sizep type is defined as follows:

```
typedef unsigned long MEM_sizep;
```

The align parameter specifies the alignment boundary for buffers in the pool. Each buffer is aligned on a boundary with an address that is a multiple of this number. The value must be a power of 2. The size of buffers created in the pool is automatically increased to accommodate the alignment you specify.

BUF\_create ensures that the size and alignment are set to at least the minimum values permitted for the platform. The minimum size permitted is 4 ('C55x) MADUs. The minimum alignment permitted is 2 ('C55x).

The attrs parameter points to a structure of type BUF\_Attrs, which is defined as follows:

```
typedef struct BUF_Attrs {
    Int    segid; /* segment for element allocation*/
} BUF_Attrs;
```



The `segid` element can be used to specify the memory segment in which buffer pool should be created. If `attrs` is `NULL`, the new buffer pool is created the default attributes specified in `BUF_ATTRS`, which uses the default memory segment.

`BUF_create` calls `MEM_alloc` to dynamically create the `BUF` object's data structure and the buffer pool.

`BUF_create` returns a handle to the buffer pool of type `BUF_Handle`. If the buffer pool cannot be created, `BUF_create` returns `NULL`. The pool may not be created if the `numbuff` or `size` parameter is zero or if the memory available in the specified heap is insufficient.

The time required to successfully execute `BUF_create` is not deterministic (that is, the time varies over multiple calls).

### Constraints and Calling Context

- ❑ `BUF_create` cannot be called from a SWI or HWI.
- ❑ The product of the `size` (after adjusting for the alignment) and `numbuff` parameters should not exceed the maximum `Uns` value.
- ❑ The alignment should be greater than the minimum value and must be a power of 2. If it is not, proper creation of buffer pool is not guaranteed.

### Example

```
BUF_Handle myBufpool;
BUF_Attrs myAttrs;

myAttrs = BUF_ATTRS;
myBufpool=BUF_create(5, 4, 2, &myAttrs);
if( myBufpool == NULL ){
    LOG_printf(&trace,"BUF_create failed!");
}
```

### See Also

`BUF_delete`

**BUF\_delete***Delete a dynamically-created buffer pool***C Interface**

**Syntax**                    `status = BUF_delete(buf);`

**Parameters**                `BUF_Handle buf;        /* buffer pool object handle */`

**Return Value**              `Uns            status;    /* returned status */`

**Reentrant**                    `no`

**Description**                `BUF_delete` frees the buffer pool object and the buffer pool memory referenced by the handle provided.

The `buf` parameter is the handle that identifies the buffer pool object. This handle is the one returned by the call to `BUF_create`. `BUF_delete` cannot be used to delete statically created buffer pool objects.

`BUF_delete` returns 1 if it has successfully freed the memory for the buffer object and buffer pool. It returns 0 (zero) if it was unable to delete the buffer pool.

`BUF_delete` calls `MEM_free` to delete the `BUF` object and to free the buffer pool memory. `MEM_free` must acquire a lock to the memory before proceeding. If another task already holds a lock on the memory, there is a context switch.

The time required to successfully execute `BUF_delete` is not deterministic (that is, the time varies over multiple calls).

**Constraints and Calling Context**

- ❑ `BUF_delete` cannot be called from a SWI or HWI.
- ❑ `BUF_delete` cannot be used to delete statically created buffer pool objects. No check is performed to ensure that this is the case.
- ❑ `BUF_delete` assumes that all the buffers allocated from the buffer pool have been freed back to the pool.

**Example**

```

BUF_Handle myBufpool;
Uns delstat;

delstat = BUF_delete(myBufpool);
if( delstat == 0 ) {
    LOG_printf(&trace, "BUF_delete failed!");
}

```

**See Also**                    `BUF_create`

**BUF\_free***Free a fixed memory buffer into the buffer pool***C Interface**

**Syntax**                    status = BUF\_free(buf, bufaddr);

**Parameters**                BUF\_Handle buf;        /\* buffer pool object handle \*/  
                               Ptr                bufaddr;     /\* address of buffer to free \*/

**Return Value**            Bool                status;     /\* returned status \*/

**Reentrant**                yes**Description**            BUF\_free frees the specified buffer back to the specified buffer pool. The newly freed buffer is then available for further allocation by BUF\_alloc.

The buf parameter is the handle that identifies the buffer pool object. This handle is the one returned by the call to BUF\_create.

The bufaddr parameter is the pointer returned by the corresponding call to BUF\_alloc.

BUF\_free always returns TRUE if DSP/BIOS real-time analysis is disabled (in the GBL Module Properties). If real-time analysis is enabled, BUF\_free returns TRUE if the bufaddr parameter is within the range of the specified buffer pool; otherwise it returns FALSE.

The BUF module manages synchronization so that multiple threads can share the same buffer pool for allocation and free operations.

The time required to successfully execute BUF\_free is deterministic (constant over multiple calls).

**Example**

```
extern BUF_Obj bufferPool;
BUF_Handle buffPoolHandle = &bufferPool;
Ptr buffPtr;
```

```
...
```

```
BUF_free(buffPoolHandle, buffPtr);
```

**See Also**

BUF\_alloc  
 MEM\_free

## BUF\_maxbuff

*Check the maximum number of buffers from the buffer pool*

### C Interface

**Syntax**                    `count = BUF_maxbuff(buf);`

**Parameters**                `BUF_Handle buf;        /* buffer pool object Handle */`

**Return Value**               `Uns            count;        /*maximum number of buffers used */`

**Reentrant**                    `no`

**Description**                `BUF_maxbuff` returns the maximum number of buffers that have been allocated from the specified buffer pool at any time. The count measures the number of buffers in use, not the total number of times buffers have been allocated.

The `buf` parameter is the handle that identifies the buffer pool object. This handle is the one returned by the call to `BUF_create`.

`BUF_maxbuff` distinguishes free and allocated buffers via a stamp mechanism. Allocated buffers are marked with the `BUF_ALLOCSTAMP` stamp (`0xcafe`). If the application happens to change this stamp to the `BUF_FREESTAMP` stamp (`0xbeef`), the count may be inaccurate. Note that this is not an application error. This stamp is only used for `BUF_maxbuff`, and changing it does not affect program execution.

The time required to successfully execute `BUF_maxbuff` is not deterministic (that is, the time varies over multiple calls).

### Constraints and Calling Context

- ❑ `BUF_maxbuff` cannot be called from a SWI or HWI.
- ❑ The application must implement synchronization to ensure that other threads do not perform `BUF_alloc` during the execution of `BUF_maxbuff`. Otherwise, the count returned by `BUF_maxbuff` may be inaccurate.

### Example

```
extern BUF_Obj bufferPool;
BUF_Handle buffPoolHandle = &bufferPool;
Int  maxbuff;

maxbuff = BUF_maxbuff(buffPoolHandle);
LOG_printf(&trace, "Max buffers used: %d", maxbuff);
```

### See Also

**BUF\_stat***Determine the status of a buffer pool***C Interface**

**Syntax**                    BUF\_stat(buf,statbuf);

**Parameters**                BUF\_Handle buf;        /\* buffer pool object handle \*/  
                               BUF\_Stat     \*statbuf; /\* pointer to buffer status structure \*/

**Return Value**                none

**Reentrant**                    yes

**Description**                BUF\_stat returns the status of the specified buffer pool.

The buf parameter is the handle that identifies the buffer pool object. This handle is the one returned by the call to BUF\_create.

The statbuf parameter must be a structure of type BUF\_Stat. The BUF\_stat function fills in all the fields of the structure. The BUF\_Stat type has the following fields:

```
typedef struct BUF_Stat {
    MEM_sizep postalignsize; /* Size after align */
    MEM_sizep size;         /* Original size of buffer */
    Uns totalbuffers; /* Total # of buffers in pool */
    Uns freebuffers; /* # of free buffers in pool */
} BUF_Stat;
```

Size values are expressed in Minimum Addressable Data Units (MADUs). BUF\_stat collects statistics with interrupts disabled to ensure the correctness of the statistics gathered.

The time required to successfully execute BUF\_stat is deterministic (constant over multiple calls).

**Example**

```
extern BUF_Obj bufferPool;
BUF_Handle buffPoolHandle = &bufferPool;
BUF_Stat stat;

BUF_stat(buffPoolHandle, &stat);
LOG_printf(&trace, "Free buffers Available: %d",
           stat.freebuffers);
```

**See Also**                    MEM\_stat

## 2.3 C55 Module

The C55 module include target-specific functions for the TMS320C5000 family

### Functions

- ❑ C55\_disableIER0, C55\_disableIER1. ASM macros to disable selected interrupts in the IER0/IER1, respectively
- ❑ C55\_disableInt. Disable an individual interrupt.
- ❑ C55\_enableIER0, C55\_enableIER1. ASM macros to enable selected interrupts in the IER0/IER1, respectively
- ❑ C55\_enableInt. Enable an individual interrupt.
- ❑ C55\_I2AckInt. Explicitly acknowledge an L2 interrupt
- ❑ C55\_I2DisableMIR, C55\_I2DisableMIR1. Disable a set of L2 interrupts
- ❑ C55\_I2EnableMIR, C55\_I2EnableMIR1. Enable a set of L2 interrupts
- ❑ C55\_I2SetIntPriority. Set the priority of a L2 interrupt
- ❑ C55\_plug. Plug interrupt vector

### Description

The C55 module provide certain target-specific functions and definitions for the TMS320C5000 family of processors.

See the c55.h file for a complete list of definitions for hardware flags for C. The c55.h file contain C language macros, #defines for various TMS320C5000 registers, and structure definitions. The c55.h55 file also contain assembly language macros for saving and restoring registers in HWIs.

**C55\_disableIER0,  
C55\_disableIER1***Disable certain maskable interrupts***C Interface****Syntax**

```
oldmask = C55_disableIER0(mask);
oldmask = C55_disableIER1(mask);
```

**Parameters**

```
Uns      mask;    /* disable mask */
```

**Return Value**

```
Uns      oldmask; /* actual bits cleared by disable mask */
```

**Description**

C55\_disableIER0 and C55\_disableIER1 disable interrupts by clearing the bits specified by mask in the Interrupt Enable Register (IER0/IER1).

C55\_disableIER0 and C55\_disableIER1 return a mask of bits actually cleared. This return value should be passed to C55\_enableIER0 or C55\_enableIER1 to re-enable interrupts.

See C55\_enableIER0, C55\_enableIER1 for a description and code examples for safely protecting a critical section of code from interrupts.

**See Also**

C55\_enableIER0, C55\_enableIER1

**C55\_disableInt***Disable an individual interrupt***C Interface**

**Syntax**                    C55\_disableInt(vecid);

**Parameters**                Uns            vecid;    /\* vector ID for interrupt \*/

**Return Value**              Void

**Description**                This function disables an individual interrupt referenced by a vector ID. The vector ID can match a level 1 interrupt (vecids 0-31) or an OMAP 2320/2420 level 2 interrupt (vecids 32-63). For OMAP 2320, the additional level 2 interrupts 32-63 can be disabled using vecids 64-95.

The c55.h header file provides some convenient interrupt ID definitions.

**See Also**                    C55\_enableInt



**C55\_enableIER0,  
C55\_enableIER1***Enable certain maskable interrupts***C Interface**

<b>Syntax</b>	C55_enableIER0(oldmask); C55_enableIER1(oldmask);
<b>Parameters</b>	Uns            oldmask; /* enable mask */
<b>Return Value</b>	Void

**Description**

C55\_disableIER0, C55\_disableIER1, C55\_enableIER0, and C55\_enableIER1 disable and enable specific internal interrupts by modifying the Interrupt Enable Register (IER0/IER1). C55\_disableIER0 and C55\_disableIER1 clear the bits specified by the mask parameter in the Interrupt Mask Register and return a mask of the bits it cleared. C55\_enableIER0 and C55\_enableIER1 set the bits specified by the oldmask parameter in the Interrupt Mask Register.

C55\_disableIER0 and C55\_disableIER1 and C55\_enableIER0 and C55\_enableIER1 are usually used in tandem to protect a critical section of code from interrupts. The following code examples show a region protected from all maskable interrupts:

```
/* C example */
Uns    oldmask;

oldmask0 = c55_disableIER0(~0);
  `do some critical operation; `
  `do not call TSK_sleep, SEM_post, etc.`
c55_enableIER0(oldmask0);
```

**Note:**

DSP/BIOS kernel calls that can cause rescheduling of tasks (for example, SEM\_post and TSK\_sleep) should be avoided within a C55\_disableIER0, C55\_disableIER1, C55\_enableIER0, and / C55\_enableIER1 block since the interrupts can be disabled for an indeterminate amount of time if a task switch occurs.

You can use C55\_disableIER0, C55\_disableIER1, C55\_enableIER0, and C55\_enableIER1 to disable selected interrupts, while allowing other interrupts to occur. However, if another hardware interrupt occurs during

this region, it could cause a task switch. You can prevent this by enclosing it with TSK\_disable / TSK\_enable to disable DSP/BIOS task scheduling.

```
Uns    oldmask;

TSK_disable();
oldmask0 = C55_disableIER0(INTMASK0);
oldmask1 = C55_disableIER1(INTMASK1);
    `do some critical operation;`
    `NOT OK to call TSK_sleep, SEM_post, etc.`
C55_enableIER0(oldmask0);
C55_enableIER1(oldmask1);
TSK_enable();
```

---

**Note:**

If you use C55\_disableIER0, C55\_disableIER1, C55\_enableIER0, and C55\_enableIER1 to disable only some interrupts, you must surround this region with SWI\_disable / SWI\_enable, to prevent an intervening HWI from causing a SWI or TSK switch.

---

The second approach is preferable if it is important not to disable all interrupts in your system during the critical operation.

**See Also**

C55\_disableIER0, C55\_disableIER1

**C55\_enableInt***Enable an individual interrupt***C Interface**

<b>Syntax</b>	C55_enableInt(vecid);
<b>Parameters</b>	Uns          vecid;    /* vector ID for interrupt */
<b>Return Value</b>	Void

**Description**

This function enables an individual interrupt referenced by a vector ID. The vector ID can match a level 1 interrupt (vecids 0-31) or an OMAP2320/2420 level 2 interrupt (vecids 32-63). For OMAP 2320, the additional level 2 interrupts 32-63 can be enabled using vecids 64-95.

The c55.h header file provides some convenient interrupt ID definitions.

**Example**

```
Void main ()
{
    HWI_Attrs attrs = HWI_ATTRS;

    // pass vector ID to myIsr
    attrs.arg = (Arg)C55_L2_INT1;

    // Plug Level 2 Interrupt #1 Vector
    HWI_dispatchPlug(C55_L2_INT1, (Fxn)myIsr, &attrs);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}
```

**See Also**

C55\_disableInt

**C55\_I2AckInt***Explicitly acknowledge an L2 interrupt***C Interface****Syntax** C55\_I2AckInt();**Parameters** Void**Return Value** Void**Description**

This API applies to the OMAP 2320/2420 platforms only.

The L2IC requires the interrupts be explicitly acknowledged prior to returning from an ISR in order to allow other L2 interrupts to be processed.

The DSP/BIOS HWI dispatcher handles this acknowledgement for HWI functions coded in C that use the HWI dispatcher. The HWI\_enter and HWI\_exit macros provide this functionality for HWI functions coded in assembly.

The C55\_I2AckInt function is for use only in HWI functions that are coded in C but that do not use the HWI dispatcher. Such functions are "interrupt" defined C code ISRs, which are dynamically plugged using C55\_plug or statically plugged using Tconf.

The C55\_I2AckInt function is #defined so that inline code is generated in order to minimize the register context saving code generated by the compiler when using the "interrupt" keyword.

**Important:** Recall that ISRs defined using the "interrupt" keyword are not allowed to call any DSP/BIOS functions. The C55\_I2AckInt function is an exception to this rule.

**Constraints and Calling Context**

- ❑ This API must be called only in the context of a HWI function. That function must be coded in C using the interrupt keyword. The HWI must not use the HWI dispatcher. In addition, the HWI function must not call any DSP/BIOS functions other than C55\_I2AckInt.

**Example**

```
interrupt void myIsr()
{
    // Acknowledge this level 2 interrupt to the L2IC
    C55_I2AckInt();

    // Your code here
}
```

**See Also**

C55\_I2DisableMIR

**C55\_I2DisableMIR** *Disable certain level 2 interrupts***C Interface**

<b>Syntax</b>	<code>C55_I2DisableMIR(mirmask);</code>
<b>Parameters</b>	<code>LgUns mirmask; /* disable mask */</code>
<b>Return Value</b>	<code>Void</code>

**Description** This API applies to OMAP 2320/2420 platforms only.

C55\_I2DisableMIR disables level 2 interrupts by setting the bits specified by mirmask in the Interrupt Mask Register (MIR). The MIR is a register in the Level 2 Interrupt Controller (L2IC) that defines which level 2 interrupts (0-31) are enabled or disabled. (Set bits are disabled.)

This function provides the functionality of C55\_disableleler0/1 for level 2 interrupts. The mirmask argument is a 32-bit bitmask that defines which level 2 interrupts to disable.

**See Also** C55\_I2EnableMIR

**C55\_I2DisableMIR1***Disable certain level 2 interrupts***C Interface**

**Syntax** `C55_I2DisableMIR1(mir1mask);`

**Parameters** `LgUns mir1mask; /* disable mask */`

**Return Value** `Void`

**Description** This API applies to the OMAP 2320 platform only.

C55\_I2DisableMIR1 disables level 2 interrupts by setting the bits specified by mir1mask in the Interrupt Mask Register1 (MIR1). The MIR1 is a register in the Level 2 Interrupt Controller (L2IC) that defines which level 2 interrupts (32-63) are enabled or disabled. (Set bits are disabled.)

This function provides the functionality of C55\_disableleler0/1 for level 2 interrupts. The mir1mask argument is a 32-bit bitmask that defines which level 2 interrupts to disable.

**See Also** `C55_I2EnableMIR1`

**C55\_I2EnableMIR***Enable certain level 2 interrupts***C Interface**

<b>Syntax</b>	C55_I2EnableMIR(mirmask);
<b>Parameters</b>	LgUns      mirmask; /* disable mask */
<b>Return Value</b>	Void

**Description**

This API applies to the OMAP 2320/2420 platforms only.

C55\_I2EnableMIR enables level 2 interrupts by clearing the bits specified by mirmask in the Interrupt Mask Register (MIR). The MIR is a register in the Level 2 Interrupt Controller (L2IC) that defines which level 2 interrupts (0-31) are enabled or disabled. (Cleared bits are enabled.)

This function provides the functionality of C55\_enableler0/1 for level 2 interrupts. The mirmask argument is a 32-bit bitmask that defines which level 2 interrupts to enable.

**Example**

```
// Enables L2 interrupts 10, 11, 12, 13
// 0x3c00 = 11110000000000 binary
C55_I2EnableMIR(0x00003c00);
```

**See Also**

C55\_I2DisableMIR

**C55\_I2EnableMIR1***Enable certain level 2 interrupts***C Interface**

<b>Syntax</b>	<code>C55_I2EnableMIR1(mir1mask);</code>
<b>Parameters</b>	<code>LgUns        mir1mask; /* disable mask */</code>
<b>Return Value</b>	<code>Void</code>

**Description**                      This API applies to the OMAP 2320 platform only.

`C55_I2EnableMIR1` enables level 2 interrupts by clearing the bits specified by `mir1mask` in the Interrupt Mask Register1 (MIR1). The MIR1 is a register in the Level 2 Interrupt Controller (L2IC) that defines which level 2 interrupts (32-63) are enabled or disabled. (Cleared bits are enabled.)

This function provides the functionality of `C55_enableler0/1` for level 2 interrupts. The `mir1mask` argument is a 32-bit bitmask that defines which level 2 interrupts to enable.

**Example**

```
// Enables L2 interrupts 42, 43, 44, 45
// 0x3c00 = 11110000000000 binary
C55_I2EnableMIR1(0x00003c00);
```

**See Also**

`C55_I2DisableMIR1`



**C55\_L2SetIntPriority***Set the priority of a level 2 interrupt***C Interface****Syntax**

C55\_L2SetIntPriority(vecid, priority);

**Parameters**

Uns            vecid;     /\* vector ID of interrupt \*/  
 Uns            priority; /\* new priority of interrupt \*/

**Return Value**

Void

**Description**

This API applies to the OMAP 2320/2420 platforms only.

The Level 2 Interrupt Controller (L2IC) allows you to set the relative priority of each of the level 2 interrupts.

The default interrupt priorities match the interrupt number. That is, level 2 interrupts 0-31 (logical interrupt IDs 32-63) have priorities 0-31 respectively. The additional OMAP 2320 L2 interrupts 32-63 (logical interrupt IDs 64-95) have priorities 32-63 respectively.

The L2 controller defines level 0 to be the highest priority and level 31 the lowest (63 for the OMAP 2320). Therefore the default priority settings give highest priority to L2 interrupt 0 and lowest to interrupt 31 (63 for the OMAP 2320).

The level 2 interrupt priority setting is independent of whether the interrupt is serviced by the dispatcher or not.

**Example**

```
Void main()
{
    HWI_Attrs attrs;
    attrs = HWI_ATTRS;

    attrs.arg = (Arg)C55_L2_INT10;
    HWI_dispatchPlug( C55_L2_INT10, (Fxn)l2FiqFunc, &attrs);
    C55_L2SetIntPriority( C55_L2_INT10, 0);

    ...
}
```

**See Also**

C55\_enableInt

**C55\_plug***C function to plug an interrupt vector***C Interface****Syntax**

C55\_plug(vecid, fxn);

**Parameters**

Int            vecid;     /\* interrupt id \*/  
Fxn            fxn;       /\* pointer to HWI function \*/

**Return Value**

Void

**Description**

C55\_plug hooks up the specified function as the branch target for a hardware interrupt (fielded by the CPU) at the vector address corresponding to vecid. C55\_plug does not enable the interrupt. Use C55\_enableIER0, C55\_enableIER1 to enable specific interrupts.

**Constraints and Calling Context**

- ❑ vecid must be a valid interrupt ID in the range of 0-31. (The range is 0-95 for OMAP 2320. The range is 0-63 for OMAP 2420.)

**See Also**

C55\_enableIER0, C55\_enableIER1

## 2.4 CLK Module

The CLK module is the clock manager.

### Functions

- ❑ CLK\_countspms. Timer counts per millisecond
- ❑ CLK\_cpuCyclesPerHtime. Return high-res time to CPU cycles factor
- ❑ CLK\_cpuCyclesPerLtime. Return low-res time to CPU cycles factor
- ❑ CLK\_gethtime. Get high-resolution time
- ❑ CLK\_gettime. Get low-resolution time
- ❑ CLK\_getprd. Get period register value
- ❑ CLK\_reconfig. Reset timer period and registers using CPU frequency
- ❑ CLK\_setTimerFunc. Assign function to a 'C5505 timer
- ❑ CLK\_start. Restart low-resolution timer
- ❑ CLK\_stop. Stop low-resolution timer

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the CLK Manager Properties and CLK Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

C55x Name	Type	Default (Enum Options)
OBJMEMSEG	Reference	prog.get("DARAM")
TIMERS_BASE	Numeric	0x7000 (OMAP 2420 only)
TIMERS_BASE_DATAMEM	Numeric	0x7ee000 (OMAP 2420 only)
TIMERSELECT	String	"Timer 0" ("Timer 5" for OMAP 2420)
ENABLECLK	Bool	true
HIRESIZE	Bool	true
ENABLEHTIME	Bool	true (C5501, 5502, OMAP 2320/2420 only)
MICROSECONDS	Int16	1000.0071
CONFIGURETIMER	Bool	false
FIXTDDR	Bool	false (not for OMAP 2320/2420)
LOAD_TIM	Int16	2999 (1x10, 59xx only)

C55x Name	Type	Default (Enum Options)
TCRTDDR	EnumInt	0 (0 to 15) (not for OMAP 2320/2420)
TCRPTV	EnumInt	0 (0 to 7) (1x10, 59xx only)
PRD	Int16	46666, 7499, or 59999 (varies by platform) (not used for 1x10, 59xx)
INPUTCLK	Numeric	0.032 MHz (OMAP 2420 only)
HTIMECLK	Numeric	12.0 MHz (OMAP 2420 only)
TIMER0FUNC to TIMER2FUNC	Extern	prog.extern("FXN_F_nop") (C5505 only)
TIMER0ARG to TIMER2ARG	Arg	0 (C5505 only)

### Instance Configuration Parameters

Name	Type	Default
comment	String	"<add comments here>"
fxn	Extern	prog.extern("FXN_F_nop")
order	Int16	0

## Description

The CLK module provides methods for gathering timing information and for invoking functions periodically. The CLK module provides real-time clocks with functions to access the low-resolution and high-resolution times. These times can be used to measure the passage of time in conjunction with STS accumulator objects, as well as to add timestamp messages in event logs.

DSP/BIOS provides the following timing methods:

- ❑ **Timer Counter.** This DSP/BIOS counter changes at a relatively fast platform-specific rate that is determined by your CLK Manager Property settings. This counter is used only if the Clock Manager is enabled in the CLK Manager Properties.
- ❑ **Low-Resolution Time.** This time is incremented when the timer counter reaches its target value. When this time is incremented, any functions defined for CLK objects are run.
- ❑ **High-Resolution Time.** For some platforms, the timer counter is also used to determine the high-resolution time. For other platforms, a different timer is used for the high-resolution time.

- ❑ **Periodic Rate.** The PRD functions can be run at a multiple of the clock interrupt rate (the low-resolution rate) if you enable the "Use CLK Manager to Drive PRD" in the PRD Manager Properties.
- ❑ **System Clock.** The PRD rate, in turn, can be used to run the system clock, which is used to measure TSK-related timeouts and ticks. If you set the "TSK Tick Driven By" in the TSK Manager Properties to "PRD", the system clock ticks at the specified multiple of the clock interrupt rate (the low-resolution rate).

## Timer Counter

The timer counter changes at a relatively fast rate until it reaches a target value. When the target value is reached, the timer counter is reset, a timer interrupt occurs, the low-resolution time is incremented, and any functions defined for CLK objects are run.

Table 2-1 shows the rate at which the timer counter changes, its target value, and how the value is reset once the target value has been reached.

*Table 2-1. Timer Counter Rates, Targets, and Resets*

Platform	Timer Counter Rate	Target Value	Value Reset
'C5501, 'C5502	Incremented at $\text{CLKOUT} / (\text{PLLDIV1} * (\text{TDDR} + 1))$ , where CLKOUT is the DSP clock speed in MHz (see GBL Module Properties), and TDDR is the value of the timer divide-down register (see CLK Manager Properties). PLLDIV1 is an additional divide-down factor; DSP/BIOS assumes its value is 4. If you change the value of PLLDIV1, timings will be incorrect.	PRD value	Counter reset to 0.
'C5503, 'C5507, 'C5509, 'C5510, 'C5561	Decrementing at $\text{CLKOUT} / (\text{TDDR} + 1)$ , where CLKOUT is the DSP clock speed in MHz (see GBL Module Properties) and TDDR is the value of the timer divide-down register (see CLK Manager Properties).	0	Counter reset to PRD value.
1x10 and 59xx	Decrementing at: $\text{CLKOUT} * (2^{\wedge} (\text{TCRPTV} + 1))$ , where CLKOUT is the DSP clock speed in MHz (see GBL Module Properties) and TCRPTV is the value in the prescaler register (see CLK Manager Properties).	0	Counter reset to PRD value.
OMAP 2320	Incremented at DSP clock speed	Counter register rolls over.	Counter reset to 0.

Table 2-1. *Timer Counter Rates, Targets, and Resets*

Platform	Timer Counter Rate	Target Value	Value Reset
OMAP 2420	Incremented at the INPUTCLK rate, which is usually either 32 kHz or 12 MHz (see CLK Manager Properties).	Counter register rolls over.	Counter reset to period register value of 0xFFFFFFFF minus PRD value in CLK Manager Properties.

**Low-Resolution Time**

When the value of the timer counter is reset to the value in the right-column of Table 2-1, the following actions happen:

- A timer interrupt occurs
- As a result of the timer interrupt, the HWI object for the timer runs the CLK\_F\_isr function.
- The CLK\_F\_isr function causes the low-resolution time to be incremented by 1.
- The CLK\_F\_isr function causes all the CLK Functions to be performed in sequence in the context of that HWI.

Therefore, the low-resolution clock ticks at the timer interrupt rate and returns the number of timer interrupts that have occurred. You can use the CLK\_gettime function to get the low-resolution time and the CLK\_getprd function to get the value of the period register property.

You can use GBL\_setFrequency, CLK\_stop, CLK\_reconfig, and CLK\_start to change the low-resolution timer rate.

The low-resolution time is stored as a 32-bit value. Its value restarts at 0 when the maximum value is reached.

**High-Resolution Time**

The high-resolution time is determined as follows for your platform:

Table 2-2. *High-Resolution Time Determination*

Platform	Description
'C5501, 'C5502	A separate DSP/BIOS counter for the high-resolution time runs at the following rate: CLKOUT / PLLDIV1. This timer counter is stored in 64 bits.
'C5503, 'C5507, 'C5509, 'C5510, 'C5561	Number of times the timer counter has been decremented.
1x10 and 59xx	Number of times the timer counter has been decremented.
OMAP 2320	Number of times the timer counter has been incremented.

Table 2-2. High-Resolution Time Determination

Platform	Description
OMAP 2420	The value of Timer 7 running at 12 MHz. This value is stored in 32 bits.

You can use the `CLK_gethtime` function to get the high-resolution time and the `CLK_countspms` function to get the number of hardware timer counter register ticks per millisecond.

The high-resolution time is stored as a 32-bit value. For platforms that use the same timer counter as the low-resolution time, the 32-bit high-resolution time is actually calculated by multiplying the low-resolution time by the value of the `PRD` property and adding number of timer counter increments or decrements (depending on your platform) since the last timer counter reset.

The high-resolution value restarts at 0 when the maximum value is reached.

## CLK Functions

The CLK functions performed when a timer interrupt occurs are performed in the context of the hardware interrupt that caused the system clock to tick. Therefore, the amount of processing performed within CLK functions should be minimized and these functions can only invoke DSP/BIOS calls that are allowable from within an HWI.

---

### Note:

CLK functions should not call `HWI_enter` and `HWI_exit` as these are called internally by DSP/BIOS when it runs `CLK_F_isr`. Additionally, CLK functions should **not** use the `interrupt` keyword or the `INTERRUPT` pragma in C functions.

---

## CLK Manager Properties

The following global properties can be set for the CLK module in the CLK Manager Properties dialog of the DSP/BIOS Configuration Tool or in a `Tconf` script:

- ❑ **Object Memory.** The memory segment that contains the CLK objects created in the configuration.  
Tconf Name: `OBJMEMSEG` Type: Reference  
Example: `bios.CLK.OBJMEMSEG = prog.get("myMEM");`
- ❑ **CPU Interrupt.** Shows which HWI interrupt is used to drive the timer services. The value is changed automatically when you change the Timer Selection. This is an informational property only.  
Tconf Name: `N/A`

- ❑ **Timer Selection.** The on-device timer to use. Changing this setting also automatically changes the CPU Interrupt used to drive the timer services and the function property of the relevant HWI objects.

Tconf Name: TIMERSELECT Type: String

Options: "Timer 0", "Timer 1" (exception: "Timer 5" and "Timer 6" for OMAP 2420)

Example: `bios.CLK.TIMERSELECT = "Timer 0";`

- ❑ **Base Address of Timers in IO Space.** This property points to the address of GP timer 5 within the DSP address space. This location is set by the DSP MMU configuration shown in Section D.2.2, *GEL Configuration*. The locations of timers 6 and 7 are determined by adding 0x0400 and 0x0800 respectively to the base address. (OMAP 2420 only)

Tconf Name: TIMERS\_BASE Type: Numeric

Example: `bios.CLK.TIMERS_BASE = 0x07000;`

- ❑ **Base Address of Timers in Data Space.** This property points to the address of the OMAP 2420 timers as mapped in the Data space by the ARM. (OMAP 2420 only)

Tconf Name: TIMERS\_BASE\_DATAMEM Type: Numeric

Example: `bios.CLK.TIMERS_BASE_DATAMEM = 0x7ee000;`

- ❑ **Enable CLK Manager.** If this property is set to true, the on-device timer hardware is used to drive the high- and low-resolution times and to trigger execution of CLK functions. On platforms where the separate ENABLEHTIME property is available, setting the ENABLECLK property to true and the ENABLEHTIME property to false enables only the low-resolution timer.

Tconf Name: ENABLECLK Type: Bool

Example: `bios.CLK.ENABLECLK = true;`

- ❑ **Use high resolution time for internal timings.** If this property is set to true, the high-resolution timer is used to monitor internal periods. Otherwise the less intrusive, low-resolution timer is used.

Tconf Name: HIRESTIME Type: Bool

Example: `bios.CLK.HIRESTIME = true;`

- ❑ **Enable high resolution timer.** If this property is set to true, this parameter enables the high-resolution timer. This property is available only for the 'C5501', 'C5502', and OMAP 2320/2420. For



platforms that use only one timer, the high-resolution and low-resolution timers are both enabled and disabled by the "Enable CLK Manager" property.

Tconf Name: ENABLEHTIME Type: Bool

Example: `bios.CLK.ENABLEHTIME = true;`

- ❑ **Microseconds/Int.** The number of microseconds between timer interrupts. The period register is set to a value that achieves the desired period as closely as possible.

Tconf Name: MICROSECONDS Type: Int16

Example: `bios.CLK.MICROSECONDS = 1000;`

- ❑ **Directly configure on-device timer registers.** If this property is set to true, the timer's hardware registers, PRD and TDDR, can be directly set to the desired values. In this case, the Microseconds/Int property is computed based on the values in PRD and TDDR and the CPU clock speed in the GBL Module Properties.

Tconf Name: CONFIGURETIMER Type: Bool

Example: `bios.CLK.CONFIGURETIMER = false;`

- ❑ **Fix TDDR.** If this property is set to true, the value in the TDDR property is not modified by changes to the Microseconds/Int property. (Not available for OMAP 2320/2420.)

Tconf Name: FIXTDDR Type: Bool

Example: `bios.CLK.FIXTDDR = false;`

- ❑ **TDDR register.** The value of the on-device timer prescalar. (Not available for 1x10, 59xx, and OMAP 2320/2420.)

Platform	Options	Size	Registers
'C5503, 'C5507, 'C5509, 'C5510, 'C5561	00h to 0fh	4 bits	part of TCR
'C5501, 'C5502	00h to 0ffffffh	32 bits	PRD3:PRD4

Tconf Name: TCRTDDR Type: EnumInt

Example: `bios.CLK.TCRTDDR = 2;`

- ❑ **PRD Register.** This value specifies the interrupt period and is used to configure the PRD register. The default value varies depending on the platform.

Tconf Name: PRD Type: Int16

Example: `bios.CLK.PRD = 33250;`

- ❑ **LOAD\_TIM register.** This value is used to configure the PRD register. This is supported only for the 1x10 (1510, 1610, and 1710) and 59xx (5905, 5910, and 5912).  
Tconf Name: LOAD\_TIM Type: Int16  
Example: `bios.CLK.LOAD_TIM = 2999;`
- ❑ **PTV register.** Sets the prescaler register value of the timer. This value is used in calculating the rate at which the timer counter is decremented. The valid values of 0 to 7 lead to prescale values from 02 hex to 100 hex. (1x10 and 59xx only.)  
Tconf Name: TCRPTV Type: EnumInt  
Options: 0 to 7  
Example: `bios.CLK.TCRPTV = 0;`
- ❑ **Clock Rate to ltime timer.** Specify the rate in MHz for the low-resolution time. On the OMAP 2420, this may be either the 0.032 MHz clock, the 12 MHz clock, or the external clock. (OMAP 2420 only.)  
Tconf Name: INPUTCLK Type: Numeric  
Example: `bios.CLK.INPUTCLK = 0.032;`
- ❑ **Clock Rate to htime timer.** Specify the rate in MHz for the high-resolution time. On the OMAP 2420, this may be either the 0.032 MHz clock, the 12 MHz clock, or the external clock. (OMAP 2420 only.)  
Tconf Name: HTIMECLK Type: Numeric  
Example: `bios.CLK.HTIMECLK = 12.0;`
- ❑ **Instructions/Int.** The number of instruction cycles represented by the period specified above. This is an informational property only.  
Tconf Name: N/A
- ❑ **Timer 0-2 Function.** Specifies the function to be executed when the corresponding timer interrupt occurs. ('C5505 only.)  
Tconf Name: INPUTCLK Type: Numeric  
Example: `bios.CLK.TIMER0FUNC =  
prog.extern("timer0Fxn");`
- ❑ **Timer 0-2 Argument.** Specifies the argument to be passed to the timer function when the corresponding timer interrupt occurs. ('C5505 only.)  
Tconf Name: INPUTCLK Type: Numeric  
Example: `bios.CLK.TIMER0ARG = 0;`

**CLK Object Properties**

The Clock Manager allows you to create an arbitrary number of CLK objects. Clock objects have functions, which are executed by the Clock Manager every time a timer interrupt occurs. These functions can invoke any DSP/BIOS operations allowable from within an HWI except HWI\_enter or HWI\_exit.

To create a CLK object in a configuration script, use the following syntax:

```
var myClk = bios.CLK.create("myClk");
```

The following properties can be set for a clock function object in the CLK Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. The Tconf examples assume the myClk object has been created as shown.

- comment.** Type a comment to identify this CLK object.

Tconf Name: comment Type: String

Example: `myClk.comment = "Runs timeFxn";`

- function.** The function to be executed when the timer hardware interrupt occurs. This function must be written like an HWI function; it must be written in C or assembly and must save and restore any registers this function modifies. However, this function can not call HWI\_enter or HWI\_exit because DSP/BIOS calls them internally before and after this function runs.

These functions should be very short as they are performed frequently.

Since all CLK functions are performed at the same periodic rate, functions that need to run at a multiple of that rate should either count the number of interrupts and perform their activities when the counter reaches the appropriate value or be configured as PRD objects.

If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. (The DSP/BIOS Configuration Tool generates assembly code, which must use leading underscores when referencing C functions or labels.) If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.

Tconf Name: fxn Type: Extern

Example: `myClk.fxn = prog.extern("timeFxn");`

- order.** You can change the sequence in which CLK functions are executed by specifying the order property of all the CLK functions.

Tconf Name: order Type: Int16

Example: `myClk.order = 2;`

**CLK\_countspms***Number of hardware timer counts per millisecond***C Interface****Syntax**                    ncounts = CLK\_countspms();**Parameters**                Void**Return Value**              LgUns            ncounts;**Reentrant**                    yes**Description**                CLK\_countspms returns the number of high-resolution timer counts per millisecond.

CLK\_countspms can be used to compute an absolute length of time from the number of low resolution timer interrupts. For example, the following code computes time in milliseconds.

```
timeAbs = (CLK_gettime() * CLK_getprd()) / CLK_countspms();
```

The equation below computes time in milliseconds since the last wrap of the high-resolution timer counter.

```
timeAbs = CLK_gettime() / CLK_countspms();
```

**See Also**

CLK\_gettime  
CLK\_getprd  
CLK\_cpuCyclesPerHtime  
CLK\_cpuCyclesPerLtime  
GBL\_getClkin  
STS\_delta

**CLK\_cpuCyclesPerHtime** *Return multiplier for converting high-res time to CPU cycles*

### C Interface

**Syntax** ncycles = CLK\_cpuCyclesPerHtime(Void);

**Parameters** Void

**Return Value** Float ncycles;

**Reentrant** yes

**Description** CLK\_cpuCyclesPerHtime returns the multiplier required to convert from high-resolution time to CPU cycles. High-resolution time is returned by CLK\_gethtime.

For example, the following code returns the number of CPU cycles and the absolute time elapsed during processing.

```
time1 = CLK_gethtime();
... processing ...
time2 = CLK_gethtime();
CPUCycles = (time2 - time1) * CLK_cpuCyclesPerHtime();
/* calculate absolute time in milliseconds */
TimeAbsolute = CPUCycles / GBL_getFrequency();
```

**See Also** CLK\_gethtime  
CLK\_getprd  
GBL\_getClkin

**CLK\_cpuCyclesPerLtime** *Return multiplier for converting low-res time to CPU cycles*

**C Interface**

**Syntax** ncycles = CLK\_cpuCyclesPerLtime(Void);

**Parameters** Void

**Return Value** Float ncycles;

**Reentrant** yes

**Description** CLK\_cpuCyclesPerLtime returns the multiplier required to convert from low-resolution time to CPU cycles. Low-resolution time is returned by CLK\_gettime.

For example, the following code returns the number of CPU cycles and milliseconds elapsed during processing.

```
time1 = CLK_gettime();  
... processing ...  
time2 = CLK_gettime();  
CPUCycles = (time2 - time1) * CLK_cpuCyclesPerLtime();  
/* calculate absolute time in milliseconds */  
TimeAbsolute = CPUCycles / GBL_getFrequency();
```

**See Also** CLK\_gettime  
CLK\_getprd  
GBL\_getClkin

**CLK\_geththime***Get high-resolution time***C Interface**

**Syntax**                    currtime = CLK\_geththime();

**Parameters**                Void

**Return Value**              LgUns            currtime    /\* high-resolution time \*/

**Reentrant**                    no

**Description**                CLK\_geththime returns the number of high-resolution clock cycles that have occurred as a 32-bit value. When the number of cycles reaches the maximum value that can be stored in 32 bits, the value wraps back to 0.

See “High-Resolution Time” on page 2-42 for information about how this rate is set.

CLK\_geththime provides a value with greater accuracy than CLK\_gettime, but which wraps back to 0 more frequently. For example, if the timer tick rate is 200 MHz, then regardless of the period register value, the CLK\_geththime value wraps back to 0 approximately every 86 seconds.

CLK\_geththime can be used in conjunction with STS\_set and STS\_delta to benchmark code. CLK\_geththime can also be used to add a time stamp to event logs.

**Constraints and Calling Context**

❑ CLK\_geththime cannot be called from the program’s main() function.

**Example**

```
/* ===== showTime ===== */

Void showTicks
{
    LOG_printf(&trace, "time = %d", CLK_geththime());
}
```

**See Also**

CLK\_gettime  
PRD\_getticks  
STS\_delta

**CLK\_gettime***Get low-resolution time***C Interface**

**Syntax** `currtime = CLK_gettime();`

**Parameters** Void

**Return Value** `LgUns currtime /* low-resolution time */`

**Reentrant** yes

**Description** CLK\_gettime returns the number of timer interrupts that have occurred as a 32-bit time value. When the number of interrupts reaches the maximum value that can be stored in 32 bits, value wraps back to 0 on the next interrupt.

The low-resolution time is the number of timer interrupts that have occurred. See “Low-Resolution Time” on page 2-42 for information about how this rate is set.

The default low resolution interrupt rate is 1 millisecond/interrupt. By adjusting the period register, you can set rates from less than 1 microsecond/interrupt to more than 1 second/interrupt.

CLK\_gethtime provides a value with more accuracy than CLK\_gettime, but which wraps back to 0 more frequently. For example, if the timer tick rate is 80 MHz, and you use the default period register value of 40000, the CLK\_gethtime value wraps back to 0 approximately every 107 seconds, while the CLK\_gettime value wraps back to 0 approximately every 49.7 days.

CLK\_gettime is often used to add a time stamp to event logs for events that occur over a relatively long period of time.

**Constraints and Calling Context**

❑ CLK\_gettime cannot be called from the program’s main() function.

**Example**

```
/* ===== showTicks ===== */

Void showTicks
{
    LOG_printf(&trace, "time = 0x%x %x",
        (Int)(CLK_gettime() >> 16), (Int)CLK_gettime());
}
```

**See Also**

CLK\_gethtime  
PRD\_getticks  
STS\_delta



**CLK\_getprd***Get period register value***C Interface**

**Syntax**                    period = CLK\_getprd();

**Parameters**                Void

**Return Value**            Uns            period    /\* period register value \*/

**Reentrant**                 yes

**Description**             CLK\_getprd returns the number of high-resolution timer counts per low-resolution interrupt.

CLK\_getprd can be used to compute an absolute length of time from the number of low-resolution timer interrupts. For example, the following code computes time in milliseconds.

```
timeAbs = (CLK_gettime() * CLK_getprd()) / CLK_countspms();
```

**See Also**

CLK\_countspms  
 CLK\_gettime  
 CLK\_cpuCyclesPerHtime  
 CLK\_cpuCyclesPerLtime  
 GBL\_getClkin  
 STS\_delta

**CLK\_reconfig***Reset timer period and registers using current CPU frequency***C Interface**

<b>Syntax</b>	status = CLK_reconfig();
<b>Parameters</b>	Void
<b>Return Value</b>	Bool            status    /* FALSE if failed */
<b>Reentrant</b>	yes

**Description**

This function needs to be called after a call to GBL\_setFrequency. It computes values for the timer period and the prescaler registers using the new CPU frequency. The new values for the period and prescaler registers ensure that the CLK interrupt runs at the statically configured interval in microseconds.

The return value is FALSE if the timer registers cannot accommodate the current frequency or if some other internal error occurs.

When calling CLK\_reconfig outside of main(), you must also call CLK\_stop and CLK\_start to stop and restart the timer. Use the following call sequence:

```
/* disable interrupts if an interrupt could lead to
   another call to CLK_reconfig or if interrupt
   processing relies on having a running timer */
HWI_disable() or SWI_disable()
GBL_setFrequency(cpuFreqInKhz);
CLK_stop();
CLK_reconfig();
CLK_start();
HWI_restore() or SWI_enable()
```

When calling CLK\_reconfig from main(), the timer has not yet been started. (The timer is started as part of BIOS\_startup(), which is called internally after main.) As a result, you can use the following simplified call sequence in main():

```
GBL_setFrequency(cpuFreqInKhz);
CLK_reconfig(Void);
```

Note that GBL\_setFrequency does not affect the PLL, and therefore has no effect on the actual frequency at which the DSP is running. It is used only to make DSP/BIOS aware of the DSP frequency you are using.

**Constraints and  
Calling Context**

- ❑ When calling CLK\_reconfig from anywhere other than main(), you must also use CLK\_stop and CLK\_start.
- ❑ Call HWI\_disable/HWI\_restore or SWI\_disable/SWI\_enable around a block that stops, configures, and restarts the timer as needed to prevent re-entrancy or other problems. That is, you must disable interrupts if an interrupt could lead to another call to CLK\_reconfig or if interrupt processing relies on having a running timer to ensure that these non-reentrant functions are not interrupted.
- ❑ If you use the PWRM module for V/F scaling and the "Reprogram BIOS clock after frequency scaling" PWRM property is configured as "true", do not call CLK\_reconfig. This is because the PWRM module internally calls this API.
- ❑ If you do not stop and restart the timer, CLK\_reconfig can only be called from the program's main() function.
- ❑ If you use CLK\_reconfig, you should also use GBL\_setFrequency.

**See Also**

GBL\_getFrequency  
GBL\_setFrequency  
CLK\_start  
CLK\_stop

**CLK\_setTimerFunc***Set the function for a 'C5505 timer***C Interface****Syntax**

```
CLK_setTimerFunc(timerId, *func, arg);
```

**Parameters**

```
Uns      timerId;      /* timer ID number */
Void     (*func)(Arg); /* function for timer to run */
Arg      arg;          /* argument to pass to timer function */
```

**Return Value**

```
Void
```

**Description**

This function dynamically sets a timer interrupt function for one of the three 'C5505 timers. See Appendix A for details.

The timerId should be 0, 1, or 2 to correspond to the timer being used. By default, the DSP/BIOS CLK manager uses timer 0.

The timer interrupt function you specify should have the following signature:

```
Void timerfunc(Arg arg);
```

Your timer function must acknowledge the timer's interrupt and clear the timer's interrupt pending status in the timer's "interrupt" register as well as its corresponding status in the "Timer Interrupt Aggregation Flag Register" at IO address 0x1c14.

For example, the following statement dynamically sets timer 1's interrupt handler:

```
CLK_setTimerFunc(1, myTimer1Func, 4);
```

When timer 1's interrupt occurs, the CLK interrupt dispatcher calls the configured handler as follows:

```
myTimer1Func(4);
```

In addition to specifying a user function using this API, you must fully configure the timer specified by timerId.

**See Also**

C55\_enableInt

**CLK\_start***Restart the low-resolution timer***C Interface****Syntax** CLK\_start();**Parameters** Void**Return Value** Void**Reentrant** no**Description**

This function starts the low-resolution timer if it has been halted by CLK\_stop. The period and prescaler registers are updated to reflect any changes made by a call to CLK\_reconfig. This function then resets the timer counters and starts the timer.

CLK\_start should only be used in conjunction with CLK\_reconfig and CLK\_stop. See the section on CLK\_reconfig for details and the allowed calling sequence.

Note that all 'C55x platforms except the 'C5501, 'C5502, and OMAP 2320/2420 use the same timer to drive low-resolution and high-resolution times. On such platforms, both times are affected by this API.

**Constraints and Calling Context**

- ❑ Call HWI\_disable/HWI\_restore or SWI\_disable/SWI\_enable around a block that stops, configures, and restarts the timer as needed to prevent re-entrancy or other problems. That is, you must disable interrupts if an interrupt could lead to another call to CLK\_start or if interrupt processing relies on having a running timer to ensure that these non-reentrant functions are not interrupted
- ❑ This function cannot be called from main().
- ❑ If you use the PWRM module for V/F scaling and the "Reprogram BIOS clock after frequency scaling" PWRM property is "true", do not call CLK\_start. This is because the PWRM module internally calls this API.

**See Also**

CLK\_reconfig  
 CLK\_stop  
 GBL\_setFrequency

**CLK\_stop***Halt the low-resolution timer***C Interface****Syntax** CLK\_stop();**Parameters** Void**Return Value** Void**Reentrant** no**Description**

This function stops the low-resolution timer. It can be used in conjunction with CLK\_reconfig and CLK\_start to reconfigure the timer at run-time.

Note that all 'C55x platforms except the 'C5501, 'C5502, and OMAP 2320/2420 use the same timer to drive low-resolution and high-resolution times. On such platforms, both times are affected by this API.

CLK\_stop should only be used in conjunction with CLK\_reconfig and CLK\_start, and only in the required calling sequence. See the section on CLK\_reconfig for details.

**Constraints and Calling Context**

- ❑ Call HWI\_disable/HWI\_restore or SWI\_disable/SWI\_enable around a block that stops, configures, and restarts the timer as needed to prevent re-entrancy or other problems. That is, you must disable interrupts if an interrupt could lead to another call to CLK\_stop or if interrupt processing relies on having a running timer to ensure that these non-reentrant functions are not interrupted
- ❑ This function cannot be called from main().
- ❑ If you use the PWRM module for V/F scaling and the "Reprogram BIOS clock after frequency scaling" PWRM property is "true", do not call CLK\_stop. This is because the PWRM module internally calls this API.

**See Also**

CLK\_reconfig  
CLK\_start  
GBL\_setFrequency

## 2.5 DEV Module

The DEV module provides the device interface.

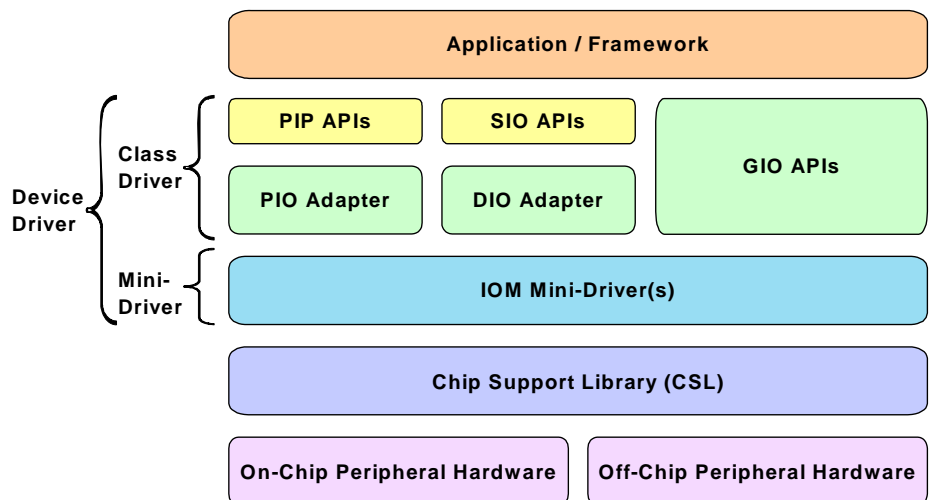
### Functions

- ❑ DEV\_createDevice. Dynamically create device
- ❑ DEV\_deleteDevice. Delete dynamically-created device
- ❑ DEV\_match. Match device name with driver
- ❑ Dxx\_close. Close device
- ❑ Dxx\_ctrl. Device control
- ❑ Dxx\_idle. Idle device
- ❑ Dxx\_init. Initialize device
- ❑ Dxx\_issue. Send frame to device
- ❑ Dxx\_open. Open device
- ❑ Dxx\_ready. Device ready
- ❑ Dxx\_reclaim. Retrieve frame from device

### Description

DSP/BIOS provides two device driver models that enable applications to communicate with DSP peripherals: IOM and SIO/DEV.

The components of the IOM model are illustrated in the following figure. It separates hardware-independent and hardware-dependent layers. Class drivers are hardware independent; they manage device instances, synchronization and serialization of I/O requests. The lower-level mini-driver is hardware-dependent. See the *DSP/BIOS Driver Developer's Guide* (SPRU616) for more information on the IOM model.



The SIO/DEV model provides a streaming I/O interface. In this model, the application indirectly invokes DEV functions implemented by the driver managing the physical device attached to the stream, using generic functions provided by the SIO module. See the *DSP/BIOS User's Guide* (SPRU423) for more information on the SIO/DEV model.

The model used by a device is identified by its function table type. A type of IOM\_Fxns is used with the IOM model. A type of DEV\_Fxns is used with the DEV/SIO model.

The DEV module provides the following capabilities:

- ❑ **Device object creation.** You can create device objects through static configuration or dynamically through the DEV\_createDevice function. The DEV\_deleteDevice and DEV\_match functions are also provided for managing device objects.
- ❑ **Driver function templates.** The Dxx functions listed as part of the DEV module are templates for driver functions. These are the functions you create for drivers that use the DEV/SIO model.

## Constants, Types, and Structures

```
#define DEV_INPUT      0
#define DEV_OUTPUT    1

typedef struct DEV_Frame { /* frame object */
    QUE_Elem  link;      /* queue link */
    Ptr       addr;      /* buffer address */
    size_t    size;      /* buffer size */
    Arg       misc;      /* reserved for driver */
    Arg       arg;        /* user argument */
    Uns       cmd;        /* mini-driver command */
    Int       status;    /* status of command */
} DEV_Frame;

typedef struct DEV_Obj { /* device object */
    QUE_Handle todevice; /* downstream frames here */
    QUE_Handle fromdevice; /* upstream frames here */
    size_t     bufsize; /* buffer size */
    Uns        nbufs;    /* number of buffers */
    Int        segid;    /* buffer segment ID */
    Int        mode;     /* DEV_INPUT/DEV_OUTPUT */
#if (defined(_54_) && defined(_FAR_MODE)) || defined(_55_)
    LgInt     devid;    /* device ID */
#else
    Int       devid;    /* device ID */
#endif
    Ptr        params;   /* device parameters */
    Ptr        object;   /* ptr to dev instance obj */
}
```



```

        DEV_Fxns fxns;    /* driver functions */
        Uns      timeout; /* SIO_reclaim timeout value */
        Uns      align;   /* buffer alignment */
        DEV_Callback *callback; /* pointer to callback */
    } DEV_Obj;

typedef struct DEV_Fxns { /* driver function table */
    Int      (*close)(  DEV_Handle );
    Int      (*ctrl)(  DEV_Handle, Uns, Arg );
    Int      (*idle)(  DEV_Handle, Bool );
    Int      (*issue)( DEV_Handle );
    Int      (*open)(  DEV_Handle, String );
    Bool     (*ready)( DEV_Handle, SEM_Handle );
    size_t   (*reclaim)( DEV_Handle );
} DEV_Fxns;

typedef struct DEV_Callback {
    Fxn      fxn;    /* function */
    Arg      arg0;   /* argument 0 */
    Arg      arg1;   /* argument 1 */
} DEV_Callback;

typedef struct DEV_Device { /* device specifier */
    String   name;   /* device name */
    Void *   fxns;   /* device function table*/
#if (defined(_54_) && defined(_FAR_MODE)) || defined(_55_)
    LgInt    devid; /* device ID */
#else
    Int      devid; /*device ID */
#endif
    Ptr      params; /* device parameters */
    Uns      type;   /* type of the device */
    Ptr      devp;   /* pointer to device handle */
} DEV_Device;

typedef struct DEV_Attrs {
#if (defined(_54_) && defined(_FAR_MODE)) || defined(_55_)
    LgInt    devid; /* device id */
#else
    Int      devid; /* device id */
#endif
    Ptr      params; /* device parameters */
    Uns      type;   /* type of the device */
    Ptr      devp;   /* device global data ptr */
} DEV_Attrs;

```

## Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DEV Manager Properties and DEV Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

## Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
initFxn	Arg	0x00000000
fxnTable	Arg	0x00000000
fxnTableType	EnumString	"DEV_Fxns" ("IOM_Fxns")
deviceId	Arg	0x00000000
params	Arg	0x00000000
deviceGlobalDataPtr	Arg	0x00000000

### DEV Manager Properties

The default configuration contains managers for the following built-in device drivers:

- ❑ **DGN Driver (software generator driver).** pseudo-device that generates one of several data streams, such as a sin/cos series or white noise. This driver can be useful for testing applications that require an input stream of data.
- ❑ **DHL Driver (host link driver).** Driver that uses the HST interface to send data to and from the Host Channel Control Analysis Tool.
- ❑ **DIO Adapter (class driver).** Driver used with the device driver model.
- ❑ **DPI Driver (pipe driver).** Software device used to stream data between DSP/BIOS tasks.

To configure devices for other drivers, use Tconf to create a User-defined Device (UDEDEV) object. There are no global properties for the user-defined device manager.

The following additional device drivers are supplied with DSP/BIOS:

- ❑ **DGS Driver.** Stackable gather/scatter driver
- ❑ **DNL Driver.** Null driver
- ❑ **DOV Driver.** Stackable overlap driver
- ❑ **DST Driver.** Stackable "split" driver
- ❑ **DTR Driver.** Stackable streaming transformer driver

### DEV Object Properties

The following properties can be set for a user-defined device in the UDEDEV Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. To create a user-defined device object in a configuration script, use the following syntax:

```
var myDev = bios.UDEV.create("myDev");
```

The Tconf examples assume the myDev object is created as shown.

- ❑ **comment.** Type a comment to identify this object.

Tconf Name: `comment` Type: String

Example: `myDev.comment = "My device";`
- ❑ **init function.** Specify the function to run to initialize this device. Use a leading underscore before the function name if the function is written in C and you are using the DSP/BIOS Configuration Tool. If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.

Tconf Name: `initFxn` Type: Arg

Example: `myDev.initFxn = prog.extern("myInit");`
- ❑ **function table ptr.** Specify the name of the device functions table for the driver or mini-driver. This table is of type DEV\_Fxns or IOM\_Fxns depending on the setting for the function table type property.

Tconf Name: `fxnTable` Type: Arg

Example: `myDev.fxnTable = prog.extern("mydevFxnTable");`
- ❑ **function table type.** Choose the type of function table used by the driver to which this device interfaces. Use the IOM\_Fxns option if you are using the DIO class driver to interface to a mini-driver with an IOM\_Fxns function table. Otherwise, use the DEV\_Fxns option for other drivers that use a DEV\_Fxns function table and Dxx functions. You can create a DIO object only if a UDEV object with the IOM\_Fxns function table type exists.

Tconf Name: `fxnTableType` Type: EnumString

Options: `"DEV_Fxns", "IOM_Fxns"`

Example: `myDev.fxnTableType = "DEV_Fxns";`
- ❑ **device id.** Specify the device ID. If the value you provide is non-zero, the value takes the place of a value that would be appended to the device name in a call to SIO\_create. The purpose of such a value is driver-specific.

Tconf Name: `deviceId` Type: Arg

Example: `myDev.deviceId = prog.extern("devID");`
- ❑ **device params ptr.** If this device uses additional parameters, provide the name of the parameter structure. This structure should have a name with the format DXX\_Params where XX is the two-letter code for the driver used by this device.

Use a leading underscore before the structure name if the structure is declared in C and you are using the DSP/BIOS Configuration Tool.

Tconf Name: `params` Type: Arg

Example: `myDev.params = prog.extern("myParams");`

- ❑ **device global data ptr.** Provide a pointer to any global data to be used by this device. This value can be set only if the function table type is IOM\_Fxns.

Tconf Name: `deviceGlobalDataPtr` Type: Arg

Example: `myDev.deviceGlobalDataPtr = 0x00000000;`

**DEV\_createDevice***Dynamically create device***C Interface****Syntax**

```
status = DEV_createDevice(name, fxns, initFxn, attrs);
```

**Parameters**

```
String      name;      /* name of device to be created */
Void        *fxns;     /* pointer to device function table */
Fxn         initFxn;   /* device init function */
DEV_Attrs   *attrs;    /* pointer to device attributes */
```

**Return Value**

```
Int         status;    /* result of operation */
```

**Reentrant**

no

**Description**

DEV\_createDevice allows an application to create a user-defined device object at run-time. The object created has parameters similar to those defined statically for the DEV Object Properties. After being created, the device can be used as with statically-created DEV objects.

The name parameter specifies the name of the device. The device name should begin with a slash (/) for consistency with statically-created devices and to permit stacking drivers. For example "/codec" might be the name. The name must be unique within the application. If the specified device name already exists, this function returns failure.

The fxns parameter points to the device function table. The function table may be of type DEV\_Fxns or IOM\_Fxns.

The initFxn parameter specifies a device initialization function. The function passed as this parameter is run if the device is created successfully. The initialization function is called with interrupts disabled. If several devices may use the same driver, the initialization function (or a function wrapper) should ensure that one-time initialization actions are performed only once.

The attrs parameter points to a structure of type DEV\_Attrs. This structure is used to pass additional device attributes to DEV\_createDevice. If attrs is NULL, the device is created with default attributes. DEV\_Attrs has the following structure:

```

typedef struct DEV_Attrs {
#ifdef (_54_) && defined(_FAR_MODE) || defined(_55_)
    LgInt    devid; /* device id */
#else
    Int      devid; /* device id */
#endif
    Ptr      params; /* device parameters */
    Uns      type; /* type of the device */
    Ptr      devp; /* device global data ptr */
} DEV_Attrs;

```

The `devid` item specifies the device ID. If the value you provide is non-zero, the value takes the place of a value that would be appended to the device name in a call to `SIO_create`. The purpose of such a value is driver-specific. The default value is `NULL`.

The `params` item specifies the name of a parameter structure that may be used to provide additional parameters. This structure should have a name with the format `DXX_Params` where `XX` is the two-letter code for the driver used by this device. The default value is `NULL`.

The `type` item specifies the type of driver used with this device. The default value is `DEV_IOMTYPE`. The options are:

Type	Use With
<code>DEV_IOMTYPE</code>	Mini-drivers used in the IOM model.
<code>DEV_SIOTYPE</code>	DIO adapter with SIO streams or other DEV/SIO drivers

The `devp` item specifies the device global data pointer, which points to any global data to be used by this device. This value can be set only if the table type is `IOM_Fxns`. The default value is `NULL`.

If an `initFxn` is specified, that function is called as a result of calling `DEV_createDevice`. In addition, if the device type is `DEV_IOMTYPE`, the `mdBindDev` function in the function table pointed to by the `fxns` parameter is called as a result of calling `DEV_createDevice`. Both of these calls are made with interrupts disabled.

`DEV_createDevice` returns one of the following status values:

Constant	Description
<code>SYS_OK</code>	Success.
<code>SYS_EINVAL</code>	A device with the specified name already exists.
<code>SYS_EALLOC</code>	The heap is not large enough to allocate the device.

DEV\_createDevice calls SYS\_error if mdBindDev returns a failure condition. The device is not created if mdBindDev fails, and DEV\_createDevice returns the IOM error returned by the mdBindDev failure.

### Constraints and Calling Context

- ❑ This function cannot be called from a SWI or HWI.
- ❑ This function can only be used if dynamic memory allocation is enabled.
- ❑ The device function table must be consistent with the type specified in the attrs structure. DSP/BIOS does not check to ensure that the types are consistent.

### Example

```
Int status;

/* Device attributes of device "/pipe0" */
DEV_Attrs dpiAttrs = {
    NULL,
    NULL,
    DEV_SIOTYPE,
    0
};

status = DEV_createDevice("/pipe0", &DPI_FXNS,
    (Fxn)DPI_init, &dpiAttrs);
if (status != SYS_OK) {
    SYS_abort("Unable to create device");
}
```

### See Also

SIO\_create

**DEV\_deleteDevice***Delete a dynamically-created device***C Interface**

**Syntax**                    `status = DEV_deleteDevice(name);`

**Parameters**                `String        name;        /* name of device to be deleted */`

**Return Value**              `Int            status;      /* result of operation */`

**Reentrant**                    `no`

**Description**                `DEV_deleteDevice` deallocates the specified dynamically-created device and deletes it from the list of devices in the application.

The name parameter specifies the device to delete. This name must match a name used with `DEV_createDevice`.

Before deleting a device, delete any SIO streams that use the device. `SIO_delete` cannot be called after the device is deleted.

If the device type is `DEV_IOMTYPE`, the `mdUnBindDev` function in the function table pointed to by the `fxns` parameter of the device is called as a result of calling `DEV_deleteDevice`. This call is made with interrupts disabled.

`DEV_createDevice` returns one of the following status values:

Constant	Description
<code>SYS_OK</code>	Success.
<code>SYS_ENODEV</code>	No device with the specified name exists.

`DEV_deleteDevice` calls `SYS_error` if `mdUnBindDev` returns a failure condition. The device is deleted even if `mdUnBindDev` fails, but `DEV_deleteDevice` returns the IOM error returned by `mdUnBindDev`.

**Constraints and Calling Context**

- This function cannot be called from a SWI or HWI.
- This function can be used only if dynamic memory allocation is enabled.
- The device name must match a dynamically-created device. DSP/BIOS does not check that the device was not created statically.

**Example**                    `status = DEV_deleteDevice("/pipe0");`

**See Also**                    `SIO_delete`



**DEV\_match***Match a device name with a driver***C Interface**

**Syntax**                    substr = DEV\_match(name, device);

**Parameters**                String        name;     /\* device name \*/  
DEV\_Device \*\*device; /\* pointer to device table entry \*/

**Return Value**             String        substr;     /\* remaining characters after match \*/

**Description**

DEV\_match searches the device table for the first device name that matches a prefix of name. The output parameter, device, points to the appropriate entry in the device table if successful and is set to NULL on error. The DEV\_Device structure is defined in dev.h.

The substr return value contains a pointer to the characters remaining after the match. This string is used by stacking devices to specify the name(s) of underlying devices (for example, /scale10/sine might match /scale10, a stacking device, which would, in turn, use /sine to open the underlying generator device).

**See Also**

SIO\_create

**Dxx\_close***Close device*

**Important Note:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

**C Interface****Syntax**

```
status = Dxx_close(device);
```

**Parameters**

```
DEV_Handle device; /* device handle */
```

**Return Value**

```
Int          status; /* result of operation */
```

**Description**

Dxx\_close closes the device associated with device and returns an error code indicating success (SYS\_OK) or failure. device is bound to the device through a prior call to Dxx\_open.

SIO\_delete first calls Dxx\_idle to idle the device. Then it calls Dxx\_close.

Once device has been closed, the underlying device is no longer accessible via this descriptor.

**Constraints and Calling Context**

- ❑ device must be bound to a device by a prior call to Dxx\_open.

**See Also**

Dxx\_idle  
Dxx\_open  
SIO\_delete

**Dxx\_ctrl***Device control operation*


---

**Important Note:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**C Interface****Syntax**

```
status = Dxx_ctrl(device, cmd, arg);
```

**Parameters**

```
DEV_Handle device    /* device handle */
Uns         cmd;     /* driver control code */
Arg         arg;     /* control operation argument */
```

**Return Value**

```
Int         status;  /* result of operation */
```

**Description**

Dxx\_ctrl performs a control operation on the device associated with device and returns an error code indicating success (SYS\_OK) or failure. The actual control operation is designated through cmd and arg, which are interpreted in a driver-dependent manner.

Dxx\_ctrl is called by SIO\_ctrl to send control commands to a device.

**Constraints and Calling Context**

- ❑ device must be bound to a device by a prior call to Dxx\_open.

**See Also**

SIO\_ctrl

**Dxx\_idle***Idle device*


---

**Important Note:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**C Interface****Syntax**

```
status = Dxx_idle(device, flush);
```

**Parameters**

```
DEV_Handle device; /* device handle */
Bool        flush; /* flush output flag */
```

**Return Value**

```
Int        status; /* result of operation */
```

**Description**

Dxx\_idle places the device associated with device into its idle state and returns an error code indicating success (SYS\_OK) or failure. Devices are initially in this state after they are opened with Dxx\_open.

Dxx\_idle returns the device to its initial state. Dxx\_idle should move any frames from the device->toqueue to the device->fromqueue. In SIO\_ISSUERECLAIM mode, any outstanding buffers issued to the stream must be reclaimed in order to return the device to its true initial state.

Dxx\_idle is called by SIO\_idle, SIO\_flush, and SIO\_delete to recycle frames to the appropriate queue.

flush is a boolean parameter that indicates what to do with any pending data of an output stream. If flush is TRUE, all pending data is discarded and Dxx\_idle does not block waiting for data to be processed. If flush is FALSE, the Dxx\_idle function does not return until all pending output data has been rendered. All pending data in an input stream is always discarded, without waiting.

**Constraints and Calling Context**

- ❑ device must be bound to a device by a prior call to Dxx\_open.

**See Also**

```
SIO_delete
SIO_idle
SIO_flush
```

**Dxx\_init***Initialize device*

**Important Note:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

**C Interface**

**Syntax** Dxx\_init();

**Parameters** Void

**Return Value** Void

**Description**

Dxx\_init is used to initialize the device driver module for a particular device. This initialization often includes resetting the actual device to its initial state.

Dxx\_init is called at system startup, before the application's main() function is called.

**Dxx\_issue***Send a buffer to the device*


---

**Important Note:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**C Interface****Syntax**

```
status = Dxx_issue(device);
```

**Parameters**

```
DEV_Handle device; /* device handle */
```

**Return Value**

```
Int          status; /* result of operation */
```

**Description**

Dxx\_issue is used to notify a device that a new frame has been placed on the device->todevice queue. If the device was opened in DEV\_INPUT mode, Dxx\_issue uses this frame for input. If the device was opened in DEV\_OUTPUT mode, Dxx\_issue processes the data in the frame, then outputs it. In either mode, Dxx\_issue ensures that the device has been started and returns an error code indicating success (SYS\_OK) or failure.

Dxx\_issue does not block. In output mode it processes the buffer and places it in a queue to be rendered. In input mode, it places a buffer in a queue to be filled with data, then returns.

Dxx\_issue is used in conjunction with Dxx\_reclaim to operate a stream. The Dxx\_issue call sends a buffer to a stream, and the Dxx\_reclaim retrieves a buffer from a stream. Dxx\_issue performs processing for output streams, and provides empty frames for input streams. The Dxx\_reclaim recovers empty frames in output streams, retrieves full frames, and performs processing for input streams.

SIO\_issue calls Dxx\_issue after placing a new input frame on the device->todevice. If Dxx\_issue fails, it should return an error code. Before attempting further I/O through the device, the device should be idled, and all pending buffers should be flushed if the device was opened for DEV\_OUTPUT.

In a stacking device, Dxx\_issue must preserve all information in the DEV\_Frame object except link and misc. On a device opened for DEV\_INPUT, Dxx\_issue should preserve the size and the arg fields. On a device opened for DEV\_OUTPUT, Dxx\_issue should preserve the buffer data (transformed as necessary), the size (adjusted as appropriate by the transform) and the arg field. The DEV\_Frame objects themselves do not need to be preserved, only the information they contain.

Dxx\_issue must preserve and maintain buffers sent to the device so they can be returned in the order they were received, by a call to Dxx\_reclaim.

**Constraints and  
Calling Context**

- ❑ device must be bound to a device by a prior call to Dxx\_open.

**See Also**

Dxx\_reclaim  
SIO\_issue

**Dxx\_open***Open device*

---

**Important Note:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**C Interface****Syntax**

```
status = Dxx_open(device, name);
```

**Parameters**

```
DEV_Handle device; /* driver handle */  
String      name;  /* device name */
```

**Return Value**

```
Int        status; /* result of operation */
```

**Description**

Dxx\_open is called by SIO\_create to open a device. Dxx\_open opens a device and returns an error code indicating success (SYS\_OK) or failure.

The device parameter points to a DEV\_Obj whose fields have been initialized by the calling function (that is, SIO\_create). These fields can be referenced by Dxx\_open to initialize various device parameters. Dxx\_open is often used to attach a device-specific object to device->object. This object typically contains driver-specific fields that can be referenced in subsequent Dxx driver calls.

name is the string remaining after the device name has been matched by SIO\_create using DEV\_match.

**See Also**

Dxx\_close  
SIO\_create



**Dxx\_ready***Check if device is ready for I/O*


---

**Important Note:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**C Interface****Syntax**

```
status = Dxx_ready(device, sem);
```

**Parameters**

```
DEV_Handle device;    /* device handle */
SEM_Handle sem;      /* semaphore to post when ready */
```

**Return Value**

```
Bool          status; /* TRUE if device is ready */
```

**Description**

Dxx\_ready is called by SIO\_select and SIO\_ready to determine if the device is ready for an I/O operation. In this context, ready means a call that retrieves a buffer from a device does not block. If a frame exists, Dxx\_ready returns TRUE, indicating that the next SIO\_get, SIO\_put, or SIO\_reclaim operation on the device does not cause the calling task to block. If there are no frames available, Dxx\_ready returns FALSE. This informs the calling task that a call to SIO\_get, SIO\_put, or SIO\_reclaim for that device would result in blocking.

Dxx\_ready registers the device's ready semaphore with the SIO\_select semaphore sem. In cases where SIO\_select calls Dxx\_ready for each of several devices, each device registers its own ready semaphore with the unique SIO\_select semaphore. The first device that becomes ready calls SEM\_post on the semaphore.

SIO\_select calls Dxx\_ready twice; the second time, sem = NULL. This results in each device's ready semaphore being set to NULL. This information is needed by the Dxx HWI that normally calls SEM\_post on the device's ready semaphore when I/O is completed; if the device ready semaphore is NULL, the semaphore should not be posted.

SIO\_ready calls Dxx\_ready with sem = NULL. This is equivalent to the second Dxx\_ready call made by SIO\_select, and the underlying device driver should just return status without registering a semaphore.

**See Also**

SIO\_select

**Dxx\_reclaim***Retrieve a buffer from a device*


---

**Important Note:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**C Interface****Syntax**

```
status = Dxx_reclaim(device);
```

**Parameters**

```
DEV_Handle device; /* device handle */
```

**Return Value**

```
Int          status; /* result of operation */
```

**Description**

Dxx\_reclaim is used to request a buffer back from a device. Dxx\_reclaim does not return until a buffer is available for the client in the device->fromdevice queue. If the device was opened in DEV\_INPUT mode then Dxx\_reclaim blocks until an input frame has been filled with the number of MADUs requested, then processes the data in the frame and place it on the device->fromdevice queue. If the device was opened in DEV\_OUTPUT mode, Dxx\_reclaim blocks until an output frame has been emptied, then place the frame on the device->fromdevice queue. In either mode, Dxx\_reclaim blocks until it has a frame to place on the device->fromdevice queue, or until the stream's timeout expires, and it returns an error code indicating success (SYS\_OK) or failure.

If device->timeout is not equal to SYS\_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

If device->timeout is SYS\_FOREVER, the task remains suspended until a frame is available on the device's fromdevice queue. If timeout is 0, Dxx\_reclaim returns immediately.

If timeout expires before a buffer is available on the device's fromdevice queue, Dxx\_reclaim returns SYS\_ETIMEOUT. Otherwise Dxx\_reclaim returns SYS\_OK for success, or an error code.

If Dxx\_reclaim fails due to a time out or any other reason, it does not place a frame on the device->fromdevice queue.

Dxx\_reclaim is used in conjunction with Dxx\_issue to operate a stream. The Dxx\_issue call sends a buffer to a stream, and the Dxx\_reclaim retrieves a buffer from a stream. Dxx\_issue performs processing for

output streams, and provides empty frames for input streams. The Dxx\_reclaim recovers empty frames in output streams, and retrieves full frames and performs processing for input streams.

SIO\_reclaim calls Dxx\_reclaim, then it gets the frame from the device->fromdevice queue.

In a stacking device, Dxx\_reclaim must preserve all information in the DEV\_Frame object except link and misc. On a device opened for DEV\_INPUT, Dxx\_reclaim should preserve the buffer data (transformed as necessary), the size (adjusted as appropriate by the transform), and the arg field. On a device opened for DEV\_OUTPUT, Dxx\_reclaim should preserve the size and the arg field. The DEV\_Frame objects themselves do not need to be preserved, only the information they contain.

Dxx\_reclaim must preserve buffers sent to the device. Dxx\_reclaim should never return a buffer that was not received from the client through the Dxx\_issue call. Dxx\_reclaim always preserves the ordering of the buffers sent to the device, and returns with the oldest buffer that was issued to the device.

## Constraints and Calling Context

- ❑ device must be bound to a device by a prior call to Dxx\_open.

## See Also

Dxx\_issue  
SIO\_issue  
SIO\_get  
SIO\_put

**DGN Driver***Software generator driver*


---

**Important Note:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

The DGN driver manages a class of software devices known as generators, which produce an input stream of data through successive application of some arithmetic function. DGN devices are used to generate sequences of constants, sine waves, random noise, or other streams of data defined by a user function. The number of active generator devices in the system is limited only by the availability of memory.

**Configuring a DGN Device**

To create a DGN device object in a configuration script, use the following syntax:

```
var myDgn = bios.DGN.create("myDgn");
```

See the DGN Object Properties for the device you created.

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DGN Object Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

**Instance Configuration Parameters**

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
device	EnumString	"user" ("sine", "random", "constant", "printHex", "printInt")
useDefaultParam	Bool	false
deviceId	Arg	prog.extern("DGN_USER", "asm")
constant	Numeric	1
seedValue	Int32	1
lowerLimit	Numeric	-32767
upperLimit	Numeric	32767
gain	Numeric	32767
frequency	Numeric	1
phase	Numeric	0

Name	Type	Default (Enum Options)
rate	Int32	256
fxn	Extern	prog.extern("FXN_F_nop")
arg	Arg	0x00000000

### Data Streaming

The DGN driver places no inherent restrictions on the size or memory segment of the data buffers used when streaming from a generator device. Since generators are fabricated entirely in software and do not overlap I/O with computation, no more than one buffer is required to attain maximum performance.

Since DGN generates data “on demand,” tasks do not block when calling SIO\_get, SIO\_put, or SIO\_reclaim on a DGN data stream. High-priority tasks must, therefore, be careful when using these streams since lower- or even equal-priority tasks do not get a chance to run until the high-priority task suspends execution for some other reason.

### DGN Driver Properties

There are no global properties for the DGN driver manager.

### DGN Object Properties

The following properties can be set for a DGN device on the DGN Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. To create a DGN device object in a script, use the following syntax:

```
var myDgn = bios.DGN.create("myDgn");
```

The Tconf examples assume the myDgn object is created as shown.

- ❑ **comment.** Type a comment to identify this object.  
Tconf Name: comment Type: String  
Example: `myDgn.comment = "DGN device";`
- ❑ **Device category.** The device category—user, sine, random, constant, printHex, printInt—determines the type of data stream produced by the device. A sine, random, or constant device can be opened for input data streaming only. A printHex or printInt device can be opened for output data streaming only.
  - **user.** Uses a custom function to produce or consume a data stream.
  - **sine.** Produce a stream of sine wave samples.
  - **random.** Produces a stream of random values.
  - **constant.** Produces a constant stream of data.
  - **printHex.** Writes the stream data buffers to the trace buffer in hexadecimal format.

- **printInt.** Writes the stream data buffers to the trace buffer in integer format.

Tconf Name: device Type: EnumString

Options: "user", "sine", "random", "constant", "printHex",  
"printInt"

Example: `myDgn.device = "user";`

- **Use default parameters.** Set this property to true if you want to use the default parameters for the Device category you selected.

Tconf Name: useDefaultParam Type: Bool

Example: `myDgn.useDefaultParam = false;`

- **Device ID.** This property is set automatically when you select a Device category.

Tconf Name: deviceId Type: Arg

Example: `myDgn.deviceId = prog.extern("DGN_USER",  
"asm");`

- **Constant value.** The constant value to be generated if the Device category is constant.

Tconf Name: constant Type: Numeric

Example: `myDgn.constant = 1;`

- **Seed value.** The initial seed value used by an internal pseudo-random number generator if the Device category is random. Used to produce a uniformly distributed sequence of numbers ranging between Lower limit and Upper limit.

Tconf Name: seedValue Type: Int32

Example: `myDgn.seedValue = 1;`

- **Lower limit.** The lowest value to be generated if the Device category is random.

Tconf Name: lowerLimit Type: Numeric

Example: `myDgn.lowerLimit = -32767;`

- **Upper limit.** The highest value to be generated if the Device category is random.

Tconf Name: upperLimit Type: Numeric

Example: `myDgn.upperLimit = 32767;`

- **Gain.** The amplitude scaling factor of the generated sine wave if the Device category is sine. This factor is applied to each data point. To improve performance, the sine wave magnitude (maximum and minimum) value is approximated to the nearest power of two. This is done by computing a shift value by which each entry in the table is

right-shifted before being copied into the input buffer. For example, if you set the Gain to 100, the sine wave magnitude is 128, the nearest power of two.

Tconf Name: gain Type: Numeric

Example: `myDgn.gain = 32767;`

- ❑ **Frequency.** The frequency of the generated sine wave (in cycles per second) if the Device category is sine. DGN uses a static (256 word) sine table to approximate a sine wave. Only frequencies that divide evenly into 256 can be represented exactly with DGN. A “step” value is computed at open time for stepping through this table:

$step = (256 * Frequency / Rate)$

Tconf Name: frequency Type: Numeric

Example: `myDgn.frequency = 1;`

- ❑ **Phase.** The phase of the generated sine wave (in radians) if the Device category is sine.

Tconf Name: phase Type: Numeric

Example: `myDgn.phase = 0;`

- ❑ **Sample rate.** The sampling rate of the generated sine wave (in sample points per second) if the Device category is sine.

Tconf Name: rate Type: Int32

Example: `myDgn.rate = 256;`

- ❑ **User function.** If the Device category is user, specifies the function to be used to compute the successive values of the data sequence in an input device, or to be used to process the data stream, in an output device. If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.

Tconf Name: fxn Type: Extern

Example: `myDgn.fxn = prog.extern("usrFxn");`

- ❑ **User function argument.** An argument to pass to the User function.

A user function must have the following form:

`fxn(Arg arg, Ptr buf, Uns nmadus)`

where buf contains the values generated or to be processed. buf and nmadus correspond to the buffer address and buffer size (in MADUs), respectively, for an SIO\_get operation.

Tconf Name: arg Type: Arg

Example: `myDgn.arg = prog.extern("myArg");`

**DGS Driver***Stackable gather/scatter driver*

---

**Important Note:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

The DGS driver manages a class of stackable devices which compress or expand a data stream by applying a user-supplied function to each input or output buffer. This driver might be used to pack data buffers before writing them to a disk file or to unpack these same buffers when reading from a disk file. All (un)packing must be completed on frame boundaries as this driver (for efficiency) does not maintain remainders across I/O operations.

On opening a DGS device by name, DGS uses the unmatched portion of the string to recursively open an underlying device.

This driver requires a transform function and a packing/unpacking ratio which are used when packing/unpacking buffers to/from the underlying device.

**Configuring a DGS Device**

To create a DGS device object in a configuration script, use the following syntax:

```
var myDgs = bios.UDEV.create("myDgs");
```

Modify the myDgs properties as follows.

- ❑ **init function.** Type 0 (zero).
- ❑ **function table ptr.** Type `_DGS_FXNS`
- ❑ **function table type.** `DEV_Fxns`
- ❑ **device id.** Type 0 (zero).
- ❑ **device params ptr.** Type 0 (zero) to use the default parameters. To use different values, you must declare a `DGS_Params` structure (as described after this list) containing the values to use for the parameters.



DGS\_Params is defined in dgs.h as follows:

```

/* ===== DGS_Params ===== */
typedef struct DGS_Params {      /* device parameters */
    Fxn    createFxn;
    Fxn    deleteFxn;
    Fxn    transFxn;
    Arg    arg;
    Int    num;
    Int    den;
} DGS_Params;

```

The device parameters are:

- ❑ **create function.** Optional, default is NULL. Specifies a function that is called to create and/or initialize a transform specific object. If non-NULL, the create function is called in DGS\_open upon creating the stream with argument as its only parameter. The return value of the create function is passed to the transform function.
- ❑ **delete function.** Optional, default is NULL. Specifies a function to be called when the device is closed. It should be used to free the object created by the create function.
- ❑ **transform function.** Required, default is localcopy. Specifies the transform function that is called before calling the underlying device's output function in output mode and after calling the underlying device's input function in input mode. Your transform function should have the following interface:

```
dstsize = myTrans(Arg arg, Void *src, Void *dst, Int srcsize)
```

where arg is an optional argument (either argument or created by the create function), and \*src and \*dst specify the source and destination buffers, respectively. srcsize specifies the size of the source buffer and dstsize specifies the size of the resulting transformed buffer (srcsize \* numerator/denominator).

- ❑ **arg.** Optional argument, default is 0. If the create function is non-NULL, the arg parameter is passed to the create function and the create function's return value is passed as a parameter to the transform function; otherwise, argument is passed to the transform function.
- ❑ **num and den** (numerator and denominator). Required, default is 1 for both parameters. These parameters specify the size of the transformed buffer. For example, a transformation that compresses two 32-bit words into a single 32-bit word would have numerator = 1 and denominator = 2 since the buffer resulting from the transformation is 1/2 the size of the original buffer.

## Transform Functions

The following transform functions are already provided with the DGS driver:

- ❑ **u32tou8/u8tou32.** These functions provide conversion to/from packed unsigned 8-bit integers to unsigned 32-bit integers. The buffer must contain a multiple of 4 number of 32-bit/8-bit unsigned values.
- ❑ **u16tou32/u32tou16.** These functions provide conversion to/from packed unsigned 16-bit integers to unsigned 32-bit integers. The buffer must contain an even number of 16-bit/32-bit unsigned values.
- ❑ **i16toi32/i32toi16.** These functions provide conversion to/from packed signed 16-bit integers to signed 32-bit integers. The buffer must contain an even number of 16-bit/32-bit integers.
- ❑ **u8toi16/i16tou8.** These functions provide conversion to/from a packed 8-bit format (two 8-bit words in one 16-bit word) to a one word per 16 bit format.
- ❑ **i16tof32/f32toi16.** These functions provide conversion to/from packed signed 16-bit integers to 32-bit floating point values. The buffer must contain an even number of 16-bit integers/32-bit floats.
- ❑ **localcopy.** This function simply passes the data to the underlying device without packing or compressing it.

## Data Streaming

DGS devices can be opened for input or output. DGS\_open allocates buffers for use by the underlying device. For input devices, the size of these buffers is (bufsize \* numerator) / denominator. For output devices, the size of these buffers is (bufsize \* denominator) / numerator. Data is transformed into or out of these buffers before or after calling the underlying device's output or input functions respectively.

You can use the same stacking device in more than one stream, provided that the terminating device underneath it is not the same. For example, if u32tou8 is a DGS device, you can create two streams dynamically as follows:

```
stream = SIO_create("/u32tou8/codec", SIO_INPUT, 128, NULL);
...
stream = SIO_create("/u32tou8/port", SIO_INPUT, 128, NULL);
```

You can also create the streams with Tconf. To do that, add two new SIO objects. Enter /codec (or any other configured terminal device) as the Device Control String for the first stream. Then select the DGS device configured to use u32tou8 in the Device property. For the second stream, enter /port as the Device Control String. Then select the DGS device configured to use u32tou8 in the Device property.

**Example**

The following code example declares DGS\_PRMS as a DGS\_Params structure:

```
#include <dgs.h>

DGS_Params DGS_PRMS {
    NULL,          /* optional create function */
    NULL,          /* optional delete function */
    u32tou8,       /* required transform function */
    0,             /* optional argument */
    4,             /* numerator */
    1              /* denominator */
}
```

By typing `_DGS_PRMS` for the Parameters property of a device, the values above are used as the parameters for this device.

**See Also**

DTR Driver

**DHL Driver***Host link driver*

---

**Important Note:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

The DHL driver manages data streaming between the host and the DSP. Each DHL device has an underlying HST object. The DHL device allows the target program to send and receive data from the host through an HST channel using the SIO streaming API rather than using pipes. The DHL driver copies data between the stream's buffers and the frames of the pipe in the underlying HST object.

**Configuring a DHL Device**

To add a DHL device you must first create an HST object and make it available to the DHL driver. To do this, use the following syntax:

```
var myHst = bios.HST.create("myHst");  
myHst.availableForDHL = true;
```

Also be sure to set the mode property to "output" or "input" as needed by the DHL device. For example:

```
myHst.mode = "output";
```

Once there are HST channels available for DHL, you can create a DHL device object in a configuration script using the following syntax:

```
var myDhl = bios.DHL.create("myDhl");
```

Then, you can set this object's properties to select which HST channel, of those available for DHL, is used by this DHL device. If you plan to use the DHL device for output to the host, be sure to select an HST channel whose mode is output. Otherwise, select an HST channel with input mode.

Note that once you have selected an HST channel to be used by a DHL device, that channel is now owned by the DHL device and is no longer available to other DHL channels.

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DHL Driver Properties and DHL Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

## Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

## Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
hstChannel	Reference	prog.get("myHST")
mode	EnumString	"output" ("input")

## Data Streaming

DHL devices can be opened for input or output data streaming. A DHL device used by a stream created in output mode must be associated with an output HST channel. A DHL device used by a stream created in input mode must be associated with an input HST channel. If these conditions are not met, a SYS\_EBADOBJ error is reported in the system log during startup when the BIOS\_start routine calls the DHL\_open function for the device.

To use a DHL device in a statically-created stream, set the deviceName property of the SIO object to match the name of the DHL device you configured.

```
mySio.deviceName = prog.get("myDhl");
```

To use a DHL device in a stream created dynamically with SIO\_create, use the DHL device name (as it appears in your Tconf script) preceded by "/" (forward slash) as the first parameter of SIO\_create:

```
stream = SIO_create("/dh10", SIO_INPUT, 128, NULL);
```

To enable data streaming between the target and the host through streams that use DHL devices, you must bind and start the underlying HST channels of the DHL devices from the Host Channels Control in Code Composer Studio, just as you would with other HST objects.

DHL devices copy the data between the frames in the HST channel's pipe and the stream's buffers. In input mode, it is the size of the frame in the HST channel that drives the data transfer. In other words, when all the data in a frame has been transferred to stream buffers, the DHL device returns the current buffer to the stream's fromdevice queue, making it available to the application. (If the stream buffers can hold more data than the HST channel frames, the stream buffers always come back partially full.) In output mode it is the opposite: the size of the buffers in the stream drives the data transfer so that when all the data in a buffer



- ❑ **Underlying HST Channel.** Select the underlying HST channel from the drop-down list. The "Make this channel available for a new DHL device" property in the HST Object Properties must be set to true for that HST object to be known here.

Tconf Name: hstChannel

Type: Reference

Example: `myDhl.hstChannel = prog.get("myHST");`

- ❑ **Mode.** This informational property shows the mode (input or output) of the underlying HST channel. This becomes the mode of the DHL device.

Tconf Name: mode

Type: EnumString

Options: "input", "output"

Example: `myDhl.mode = "output";`

**DIO Adapter***SIO Mini-driver adapter***Description**

The DIO adapter allows GIO-compliant mini-drivers to be used through SIO module functions. Such mini-drivers are described in the *DSP/BIOS Device Driver Developer's Guide* (SPRU616).

**Configure Mini-driver**

To create a DIO device object in a configuration script, first use the following syntax:

```
var myUdev = bios.UDEV.create("myUdev");
```

Set the DEV Object Properties for the device as follows.

- init function.** Type 0 (zero).
- function table ptr.** Type \_DIO\_FXNS
- function table type.** IOM\_Fxns
- device id.** Type 0 (zero).
- device params ptr.** Type 0 (zero).

Once there is a UDEV object with the IOM\_Fxns function table type in the configuration, you can create a DIO object with the following syntax and then set properties for the object:

```
var myDio = bios.Dio.create("myDio");
```

**DIO Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DIO Driver Properties and DIO Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

**Module Configuration Parameters**

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")
STATICCREATE	Bool	false

**Instance Configuration Parameters**

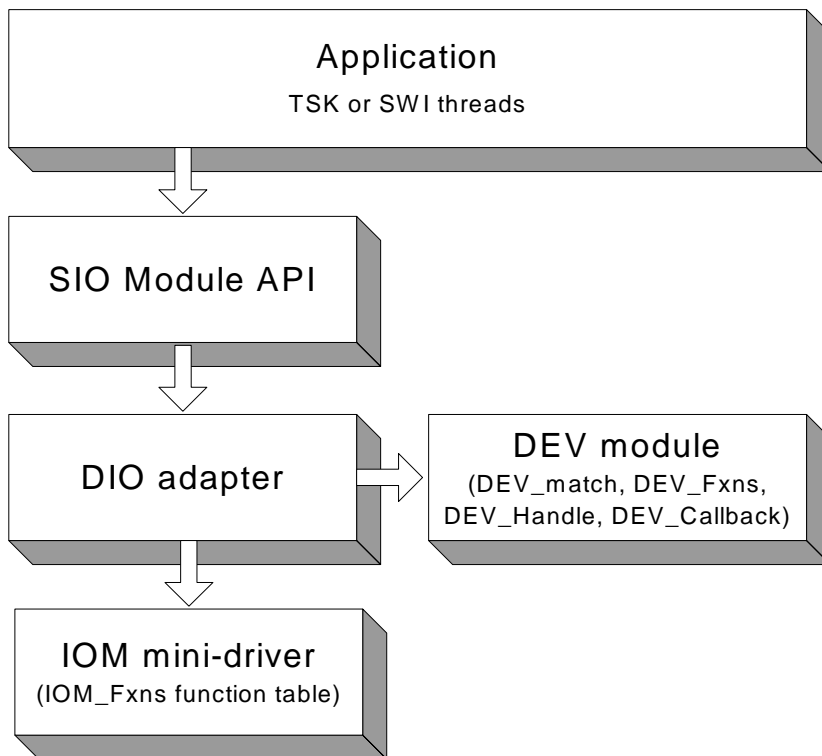
Name	Type	Default
comment	String	"<add comments here>"
useCallBackFxn	Bool	false
deviceName	Reference	prog.get("UDEVO")
chanParams	Arg	0x00000000



**Description**

The mini-drivers described in the *DSP/BIOS Device Driver Developer's Guide* (SPRU616) are intended for use with the GIO module. However, the DIO driver allows them to be used with the SIO module instead of the GIO module.

The following figure summarizes how modules are related in an application that uses the DIO driver and a mini-driver:

**DIO Driver Properties**

The following global properties can be set for the DIO - Class Driver on the DIO Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script:

- Object memory.** Enter the memory segment from which to allocate DIO objects.  
Tconf Name: OBJMEMSEG Type: Reference  
Example: `bios.DIO.OBJMEMSEG = prog.get("myMEM");`
- Create All DIO Objects Statically.** Set this property to true if you want DIO objects to be created completely statically. If this property is false (the default), MEM\_alloc is used internally to allocate space for DIO objects. If this property is true, you must create all SIO and DIO objects using the DSP/BIOS Configuration Tool or Tconf. Any

calls to SIO\_create fail. Setting this property to true reduces the application's code size (so long as the application does not call MEM\_alloc or its related functions elsewhere).

Tconf Name: STATICCREATE Type: Bool

Example: `bios.DIO.STATICCREATE = false;`

## DIO Object Properties

The following properties can be set for a DIO device using the DIO Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. To create a DIO device object in a configuration script, use the following syntax:

```
var myDio = bios.DIO.create("myDio");
```

The Tconf examples assume the myDio object has been created as shown.

- comment.** Type a comment to identify this object.

Tconf Name: comment Type: String

Example: `myDio.comment = "DIO device";`

- use callback version of DIO function table.** Set this property to true if you want to use DIO with a callback function. Typically, the callback function is SWI\_andnHook or a similar function that posts a SWI. Do not set this property to true if you want to use DIO with a TSK thread.

Tconf Name: useCallBackFxn Type: Bool

Example: `myDio.useCallBackFxn = false;`

- fxnsTable.** This informational property shows the DIO function table used as a result of the settings in the "use callback version of DIO function table" and "Create ALL DIO Objects Statically" properties. The four possible setting combinations of these two properties correspond to the four function tables: DIO\_tskDynamicFxn, DIO\_tskStaticFxn, DIO\_cbDynamicFxn, and DIO\_cbStaticFxn.

Tconf Name: N/A

- device name.** Name of the device to use with this DIO object.

Tconf Name: deviceName Type: Reference

Example: `myDio.deviceName = prog.get("UDEVO");`

- channel parameters.** This property allows you to pass an optional argument to the mini-driver create function. See the chanParams parameter of the GIO\_create function.

Tconf Name: chanParams Type: Arg

Example: `myDio.chanParams = 0x00000000;`

**DNL Driver***Null driver*


---

**Important Note:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

The DNL driver manages “empty” devices which nondestructively produce or consume data streams. The number of empty devices in the system is limited only by the availability of memory; DNL instantiates a new object representing an empty device on opening, and frees this object when the device is closed.

The DNL driver does not define device ID values or a params structure which can be associated with the name used when opening an empty device. The driver also ignores any unmatched portion of the name declared in the system configuration file when opening a device.

**Configuring a DNL Device**

To create a DNL device object in a configuration script, use the following syntax:

```
var myDnl = bios.UDEV.create("myDnl");
```

Set DEV Object Properties for the device you created as follows.

- ❑ **init function.** Type 0 (zero).
- ❑ **function table ptr.** Type `_DNL_FXNS`
- ❑ **function table type.** `DEV_Fxns`
- ❑ **device id.** Type 0 (zero).
- ❑ **device params ptr.** Type 0 (zero).

**Data Streaming**

DNL devices can be opened for input or output data streaming. Note that these devices return buffers of undefined data when used for input.

The DNL driver places no inherent restrictions on the size or memory segment of the data buffers used when streaming to or from an empty device. Since DNL devices are fabricated entirely in software and do not overlap I/O with computation, no more than one buffer is required to attain maximum performance.

Tasks do not block when using `SIO_get`, `SIO_put`, or `SIO_reclaim` with a DNL data stream.

**DOV Driver***Stackable overlap driver*


---

**Important Note:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

The DOV driver manages a class of stackable devices that generate an overlapped stream by retaining the last N minimum addressable data units (MADUs) of each buffer input from an underlying device. These N points become the first N points of the next input buffer. MADUs are equivalent to a 16-bit word in the data address space of the processor on C54x and C55x platforms.

**Configuring a DOV Device**

To create a DOV device object in a configuration script, use the following syntax:

```
var myDov = bios.UDEV.create("myDov");
```

Set the DEV Object Properties for the device you created as follows.

- init function.** Type 0 (zero).
- function table ptr.** Type `_DOV_FXNS`
- function table type.** `DEV_Fxns`
- device id.** Type 0 (zero).
- device params ptr.** Type 0 (zero) or the length of the overlap as described after this list.

If you enter 0 for the Device ID, you need to specify the length of the overlap when you create the stream with `SIO_create` by appending the length of the overlap to the device name. If you statically create the stream (with `Tconf`) instead, enter the length of the overlap in the Device Control String for the stream.

For example, if you statically create a device called `overlap`, and use 0 as its Device ID, you can open a stream with:

```
stream = SIO_create("/overlap16/codec", SIO_INPUT, 128, NULL);
```

This causes SIO to open a stack of two devices. `/overlap16` designates the device called `overlap`, and 16 tells the driver to use the last 16 MADUs of the previous frame as the first 16 MADUs of the next frame. `codec` specifies the name of the physical device which corresponds to the actual source for the data.

If, on the other hand you add a device called overlap and enter 16 as its Device ID, you can open the stream with:

```
stream = SIO_create("/overlap/codec", SIO_INPUT, 128, NULL);
```

This causes the SIO Module to open a stack of two devices. /overlap designates the device called overlap, which you have configured to use the last 16 MADUs of the previous frame as the first 16 MADUs of the next frame. As in the previous example, codec specifies the name of the physical device that corresponds to the actual source for the data.

If you create the stream statically and enter 16 as the Device ID property, leave the Device Control String blank.

In addition to the configuration properties, you need to specify the value that DOV uses for the first overlap, as in the example:

```
#include <dov.h>

static DOV_Config DOV_CONFIG = {
    (Char) 0
}
DOV_Config *DOV = &DOV_CONFIG;
```

If floating point 0.0 is required, the initial value should be set to (Char) 0.0.

## Data Streaming

DOV devices can only be opened for input. The overlap size, specified in the string passed to SIO\_create, must be greater than 0 and less than the size of the actual input buffers.

DOV does not support any control calls. All SIO\_ctrl calls are passed to the underlying device.

You can use the same stacking device in more than one stream, provided that the terminating device underneath it is not the same. For example, if overlap is a DOV device with a Device ID of 0:

```
stream = SIO_create("/overlap16/codec", SIO_INPUT, 128, NULL);
...
stream = SIO_create("/overlap4/port", SIO_INPUT, 128, NULL);
```

or if overlap is a DOV device with positive Device ID:

```
stream = SIO_create("/overlap/codec", SIO_INPUT, 128, NULL);
...
stream = SIO_create("/overlap/port", SIO_INPUT, 128, NULL);
```

To create the same streams statically (rather than dynamically with SIO\_create), add SIO objects with Tconf. Enter the string that identifies the terminating device preceded by "/" (forward slash) in the SIO object's Device Control Strings (for example, /codec, /port). Then select the stacking device (overlap, overlapio) from the Device property.

**See Also**

DTR Driver  
DGS Driver

**DPI Driver***Pipe driver*


---

**Important Note:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

The DPI driver is a software device used to stream data between tasks on a single processor. It provides a mechanism similar to that of UNIX named pipes; a reader and a writer task can open a named pipe device and stream data to/from the device. Thus, a pipe simply provides a mechanism by which two tasks can exchange data buffers.

Any stacking driver can be stacked on top of DPI. DPI can have only one reader and one writer task.

It is possible to delete one end of a pipe with SIO\_delete and recreate that end with SIO\_create without deleting the other end.

**Configuring a DPI Device**

To add a DPI device, right-click on the DPI - Pipe Driver folder, and select Insert DPI. From the Object menu, choose Rename and type a new name for the DPI device.

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DPI Object Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

**Instance Configuration Parameters**

Name	Type	Default
comment	String	"<add comments here>"
allowVirtual	Bool	false

**Data Streaming**

After adding a DPI device called pipe0 in the configuration, you can use it to establish a communication pipe between two tasks. You can do this dynamically, by calling in the function for one task:

```
inStr = SIO_create("/pipe0", SIO_INPUT, bufsize, NULL);
...
SIO_get(inStr, bufp);
```

And in the function for the other task:

```
outStr = SIO_create("/pipe0", SIO_OUTPUT, bufsize, NULL);  
...  
SIO_put(outStr, bufp, nmadus);
```

or by adding with Tconf two streams that use pipe0, one in output mode (outStream) and the other one in input mode(inStream). Then, from the reader task call:

```
extern SIO_Obj inStream;  
SIO_handle inStr = &inStream  
...  
SIO_get(inStr, bufp);
```

and from the writer task call:

```
extern SIO_Obj outStream;  
SIO_handle outStr = &outStream  
...  
SIO_put(outStr, bufp, nmadus);
```

The DPI driver places no inherent restrictions on the size or memory segments of the data buffers used when streaming to or from a pipe device, other than the usual requirement that all buffers be the same size.

Tasks block within DPI when using SIO\_get, SIO\_put, or SIO\_reclaim if a buffer is not available. SIO\_select can be used to guarantee that a call to one of these functions do not block. SIO\_select can be called simultaneously by both the input and the output sides.

## **DPI and the SIO\_ISSUERECLAIM Streaming Model**

In the SIO\_ISSUERECLAIM streaming model, an application reclaims buffers from a stream in the same order as they were previously issued. To preserve this mechanism of exchanging buffers with the stream, the default implementation of the DPI driver for ISSUERECLAIM copies the full buffers issued by the writer to the empty buffers issued by the reader.

A more efficient version of the driver that exchanges the buffers across both sides of the stream, rather than copying them, is also provided. To use this variant of the pipe driver for ISSUERECLAIM, edit the C source file dpi.c provided in the C:\ti\c5000\bios\src\drivers folder. Comment out the following line:

```
#define COPYBUFS
```

Rebuild dpi.c. Link your application with this version of dpi.obj instead of the default one. To do this, add this version of dpi.obj to your project explicitly. This buffer exchange alters the way in which the streaming



mechanism works. When using this version of the DPI driver, the writer reclaims first the buffers issued by the reader rather than its own issued buffers, and vice versa.

This version of the pipe driver is not suitable for applications in which buffers are broadcasted from a writer to several readers. In this situation it is necessary to preserve the ISSUERECLAIM model original mechanism, so that the buffers reclaimed on each side of a stream are the same that were issued on that side of the stream, and so that they are reclaimed in the same order that they were issued. Otherwise, the writer reclaims two or more different buffers from two or more readers, when the number of buffers it issued was only one.

### Converting a Single Processor Application to a Multiprocessor Application

It is trivial to convert a single-processor application using tasks and pipes into a multiprocessor application using tasks and communication devices. If using SIO\_create, the calls in the source code would change to use the names of the communication devices instead of pipes. (If the communication devices were given names like /pipe0, there would be no source change at all.) If the streams were created statically with Tconf instead, you would need to change the Device property for the stream in the configuration template, save and rebuild your application for the new configuration. No source change would be necessary.

### Constraints

Only one reader and one writer can open the same pipe.

### DPI Driver Properties

There are no global properties for the DPI driver manager.

### DPI Object Properties

The following property can be set for a DPI device in the DPI Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. To create a DPI device object in a configuration script, use the following syntax:

```
var myDpi = bios.DPI.create("myDpi");
```

The Tconf examples assume the myDpi object has been created as shown.

- comment.** Type a comment to identify this object.

Tconf Name: comment

Type: String

Example: `myDpi.comment = "DPI device";`

- Allow virtual instances of this device.** Set this property to true if you want to be able to use SIO\_create to dynamically create multiple streams to use this DPI device. DPI devices are used by SIO stream objects, which you create with Tconf or the SIO\_create function.

If this property is set to true, when you use SIO\_create, you can create multiple streams that use the same DPI driver by appending numbers to the end of the name. For example, if the DPI object is

named "pipe", you can call `SIO_create` to create `pipe0`, `pipe1`, and `pipe2`. Only integer numbers can be appended to the name.

If this property is set to `false`, when you use `SIO_create`, the name of the SIO object must exactly match the name of the DPI object. As a result, only one open stream can use the DPI object. For example, if the DPI object is named "pipe", an attempt to use `SIO_create` to create `pipe0` fails.

Tconf Name: `allowVirtual`

Type: Bool

Example: `myDpi.allowVirtual = false;`

**DST Driver***Stackable split driver*


---

**Important Note:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

This stacking driver can be used to input or output buffers that are larger than the physical device can actually handle. For output, a single (large) buffer is split into multiple smaller buffers which are then sent to the underlying device. For input, multiple (small) input buffers are read from the device and copied into a single (large) buffer.

**Configuring a DST Device**

To create a DST device object in a configuration script, use the following syntax:

```
var myDst = bios.UDEV.create("myDst");
```

Set the DEV Object Properties for the device you created as follows.

- ❑ **init function.** Type 0 (zero).
- ❑ **function table ptr.** Type `_DST_FXNS`
- ❑ **function table type.** `DEV_Fxns`
- ❑ **device id.** Type 0 (zero) or the number of small buffers corresponding to a large buffer as described after this list.
- ❑ **device params ptr.** Type 0 (zero).

If you enter 0 for the Device ID, you need to specify the number of small buffers corresponding to a large buffer when you create the stream with `SIO_create`, by appending it to the device name.

**Example 1:**

For example, if you create a user-defined device called `split` with `Tconf`, and enter 0 as its Device ID property, you can open a stream with:

```
stream = SIO_create("/split4/codec", SIO_INPUT, 1024, NULL);
```

This causes SIO to open a stack of two devices: `/split4` designates the device called `split`, and 4 tells the driver to read four 256-word buffers from the codec device and copy the data into 1024-word buffers for your application. `codec` specifies the name of the physical device which corresponds to the actual source for the data.

Alternatively, you can create the stream with Tconf (rather than by calling SIO\_create at run-time). To do so, first create and configure two user-defined devices called split and codec. Then, create an SIO object. Type 4/codec as the Device Control String. Select split from the Device list.

**Example 2:**

Conversely, you can open an output stream that accepts 1024-word buffers, but breaks them into 256-word buffers before passing them to /codec, as follows:

```
stream = SIO_create("/split4/codec", SIO_OUTPUT, 1024, NULL);
```

To create this output stream with Tconf, you would follow the steps for example 1, but would select output for the Mode property of the SIO object.

**Example 3:**

If, on the other hand, you add a device called split and enter 4 as its Device ID, you need to open the stream with:

```
stream = SIO_create("/split/codec", SIO_INPUT, 1024, NULL);
```

This causes SIO to open a stack of two devices: /split designates the device called split, which you have configured to read four buffers from the codec device and copy the data into a larger buffer for your application. As in the previous example, codec specifies the name of the physical device that corresponds to the actual source for the data.

When you type 4 as the Device ID, you do not need to type 4 in the Device Control String for an SIO object created with Tconf. Type only/codec for the Device Control String.

**Data Streaming**

DST stacking devices can be opened for input or output data streaming.

**Constraints**

- ❑ The size of the application buffers must be an integer multiple of the size of the underlying buffers.
- ❑ This driver does not support any SIO\_ctrl calls.

**DTR Driver***Stackable streaming transformer driver*


---

**Important Note:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

The DTR driver manages a class of stackable devices known as transformers, which modify a data stream by applying a function to each point produced or consumed by an underlying device. The number of active transformer devices in the system is limited only by the availability of memory; DTR instantiates a new transformer on opening a device, and frees this object when the device is closed.

Buffers are read from the device and copied into a single (large) buffer.

**Configuring a DTR Device**

To create a DTR device object in a configuration script, use the following syntax:

```
var myDtr = bios.UDEV.create("myDtr");
```

Set the DEV Object Properties for the device you created as follows.

- ❑ **init function.** Type 0 (zero).
- ❑ **function table ptr.** Type `_DTR_FXNS`
- ❑ **function table type.** `DEV_Fxns`
- ❑ **device id.** Type 0 (zero), `_DTR_multiply`, or `_DTR_multiplyInt16`.

If you type 0, you need to supply a user function in the device parameters. This function is called by the driver as follows to perform the transformation on the data stream:

```
if (user.fxn != NULL) {
    (*user.fxn)(user.arg, buffer, size);
}
```

If you type `_DTR_multiply`, a built-in data scaling operation is performed on the data stream to multiply the contents of the buffer by the `scale.value` of the device parameters.

If you type `_DTR_multiplyInt16`, a built-in data scaling operation is performed on the data stream to multiply the contents of the buffer by the `scale.value` of the device parameters. The data stream is assumed to contain values of type `Int16`.

- ❑ **device params ptr.** Enter the name of a DTR\_Params structure declared in your C application code. See the information following this list for details.

The DTR\_Params structure is defined in dtr.h as follows:

```
/* ===== DTR_Params ===== */
typedef struct {          /* device parameters */
    struct {
        DTR_Scale  value; /* scaling factor */
    } scale;
    struct {
        Arg        arg;   /* user-defined argument */
        Fxn        fxn;   /* user-defined function */
    } user;
} DTR_Params;
```

In the following code example, DTR\_PRMS is declared as a DTR\_Params structure:

```
#include <dtr.h>
...
struct DTR_Params DTR_PRMS = {
    10.0,
    NULL,
    NULL,
};
```

By typing `_DTR_PRMS` as the Parameters property of a DTR device, the values above are used as the parameters for this device.

You can also use the default values that the driver assigns to these parameters by entering `_DTR_PARAMS` for this property. The default values are:

```
DTR_Params DTR_PARAMS = {
    { 1 },          /* scale.value */
    { (Arg)NULL,   /* user.arg */
      (Fxn)NULL }, /* user.fxn */
};
```

`scale.value` is a floating-point quantity multiplied with each data point in the input or output stream.

If you do not configure one of the built-in scaling functions for the device ID, use `user.fxn` and `user.arg` in the DTR\_Params structure to define a transformation that is applied to inbound or outbound blocks of data, where `buffer` is the address of a data block containing `size` points; if the value of `user.fxn` is `NULL`, no transformation is performed at all.

```
if (user.fxn != NULL) {  
    (*user.fxn)(user.arg, buffer, size);  
}
```

## Data Streaming

DTR transformer devices can be opened for input or output and use the same mode of I/O with the underlying streaming device. If a transformer is used as a data source, it inputs a buffer from the underlying streaming device and then transforms this data in place. If the transformer is used as a data sink, it outputs a given buffer to the underlying device after transforming this data in place.

The DTR driver places no inherent restrictions on the size or memory segment of the data buffers used when streaming to or from a transformer device; such restrictions, if any, would be imposed by the underlying streaming device.

Tasks do not block within DTR when using the SIO Module. A task can, of course, block as required by the underlying device.

## 2.6 GBL Module

This module is the global settings manager.

### Functions

- ❑ GBL\_getClkin. Gets configured value of board input clock in KHz.
- ❑ GBL\_getFrequency. Gets current frequency of the CPU in KHz.
- ❑ GBL\_getProcid. Gets configured processor ID used by MSGQ.
- ❑ GBL\_getVersion. Gets DSP/BIOS version information.
- ❑ GBL\_setFrequency. Set frequency of CPU in KHz for DSP/BIOS.
- ❑ GBL\_setProcid. Set configured value of processor ID.

### Configuration Properties

The following list shows the properties for this module that can be configured in a Tconf script, along with their types and default values. For details, see the GBL Module Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

C55x Name	Type	Default (Enum Options)
BOARDNAME	String	"c55xx"
PROCID	Int16	0
CLKIN	UInt32	20000 KHz
CLKOUT	Int16	'C5502, etc: 300 'C5510, etc: 140 'C5561: 60 'C59xx: 12 1x10 (1510, 1610, and 1710): 12 OMAP 2320/2420: 12
SPECIFYRTSLIB	Bool	false
RTSLIB	String	""
MEMORYMODEL	EnumString	"LARGE" ("HUGE")
CALLUSERINITFXN	Bool	false
USERINITFXN	Extern	prog.extern("FXN_F_nop")
ENABLEINST	Bool	true
INSTRUMENTED	Bool	true
ENABLEALLTRC	Bool	true
DCRPOSTEDERITE	Bool	true (OMAP 2320/2420 only)

### Description

This module does not manage any individual objects, but rather allows you to control global or system-wide settings used by other modules.



## GBL Module Properties

The following Global Settings can be made:

- ❑ **Target Board Name.** The name of the board or board family.

Tconf Name: BOARDNAME Type: String

Example: `bios.GBL.BOARDNAME = "c55xx";`
- ❑ **Processor ID (PROCID).** ID used to communicate with other processors using the MSGQ Module. The proclid is also defined in the MSGQ\_TransportObj array that is part of the MSGQ\_Config structure. This value can be obtained with GBL\_getProclid and modified by GBL\_setProclid (but only within the User Init Function).

Tconf Name: PROCID Type: Int16

Example: `bios.GBL.PROCID = 0;`
- ❑ **Board Clock In KHz (Informational Only).** Frequency of the input clock in KHz. You should set this property to match the actual board clock rate. This property does not change the rate of the board; it is informational only. The configured value can be obtained at run-time using the GBL\_getClkin API. This property is used on the 'C5503 to compute the USB PLL settings. The default value is 20000 KHz.

Tconf Name: CLKIN Type: Uint32

Example: `bios.GBL.CLKIN = 20000;`
- ❑ **DSP Speed In MHz (CLKOUT).** This number, times 1000000, is the number of instructions the processor can execute in 1 second. You should set this property to match the actual rate. This property does not change the rate of the board. This value is used by the CLK manager to calculate register settings for the on-device timers.

Tconf Name: CLKOUT Type: Int16

Example: `bios.GBL.CLKOUT = 100.0000;`
- ❑ **Specify RTS Library.** Determines whether a user can specify the run-time support library to which the application is linked. The RTS library contains the printf, malloc, and other standard C library functions. For information about using this library, see "std.h and stdlib.h functions" on page 2-511. If you do not choose to specify a library, the default library for your platform is used.

Tconf Name: SPECIFYRTSLIB Type: Bool

Example: `bios.GBL.SPECIFYRTSLIB = false;`

- ❑ **Run-Time Support Library.** The name of the run-time support (RTS) library to which the application is linked. These libraries are located in the <BIOS\_INSTALL\_DIR>\xdctools\packages\ti\targets tree. The library you select is used in the linker command file generated from the Tconf script when you build your application.

Tconf Name: RTSLIB Type: String

Example: `bios.GBL.RTSLIB = "";`

- ❑ **Modify CLKMD.** Set this property to true if you want to modify the value of the Clock Mode Register, which is used to program the PLL (phase-locked loop).

Tconf Name: MODIFYCLKMD Type: Bool

Example: `bios.GBL.MODIFYCLKMD = false;`

- ❑ **CLKMD - (PLL) Clock Mode Register.** The value of the Clock Mode Register.

Tconf Name: CLKMD Type: Numeric

Example: `bios.GBL.CLKMD = 0x0000;`

- ❑ **Memory Model.** This specifies the address reach within the 'C55x program. The options are large and huge. In the large and huge models, data addressing uses the full 23-bit range. Program space addressing always uses the full 24-bit range.

Both the large and huge models support the same addressing range. The difference is that the huge model allows buffers to cross 64K page boundaries. For the large model, size\_t is 16 bits (64K). For the huge model, size\_t is 23 bits, which requires 32 bits of storage since the minimum storage unit is 16 bits.

Tconf Name: MEMORYMODEL Type: EnumString

Options: "LARGE", "HUGE"

Example: `bios.GBL.MEMORYMODEL = "LARGE";`

- ❑ **Call User Init Function.** Set this property to true if you want an initialization function to be called early during program initialization, after .cinit processing and before the main() function.

Tconf Name: CALLUSERINITFXN Type: Bool

Example: `bios.GBL.CALLUSERINITFXN = false;`

- ❑ **User Init Function.** Type the name of the initialization function. This function runs early in the initialization process and is intended to be used to perform hardware setup that needs to run before DSP/BIOS is initialized. The code in this function should not use any DSP/BIOS API calls, unless otherwise specified for that API, since a number of DSP/BIOS modules have not been initialized when this function runs.

In contrast, the Initialization function that may be specified for HOOK Module objects runs later and is intended for use in setting up data structures used by other functions of the same HOOK object.

Tconf Name: USERINITFXN Type: Extern

Example: `bios.GBL.USERINITFXN =  
prog.extern("FXN_F_nop");`

- ❑ **Enable Real Time Analysis.** If this property is true, target-to-host communication is enabled by the addition of IDL objects to run the IDL\_cpuLoad, LNK\_dataPump, and RTA\_dispatch functions. If this property is false, these IDL objects are removed and target-to-host communications are not supported. As a result, support for DSP/BIOS implicit instrumentation is removed.

Tconf Name: ENABLEINST Type: Bool

Example: `bios.GBL.ENABLEINST = true;`

- ❑ **Use Instrumented BIOS Library.** Specifies whether to link with the instrumented or non-instrumented version of the DSP/BIOS library. The non-instrumented versions are somewhat smaller but do not provide support for LOG, STS, and TRC instrumentation. The libraries are located in <BIOS\_INSTALL\_DIR>\packages\ti\bios\lib. By default, the instrumented version of the library for your platform is used.

Tconf Name: INSTRUMENTED Type: Bool

Example: `bios.GBL.INSTRUMENTED = true;`

- ❑ **Enable All TRC Trace Event Classes.** Set this property to false if you want all types of tracing to be initially disabled when the program is loaded. If you disable tracing, you can still use the RTA Control Panel or the TRC\_enable function to enable tracing at run-time.

Tconf Name: ENABLEALLTRC Type: Bool

Example: `bios.GBL.ENABLEALLTRC = true;`

- ❑ **DPORT write in posted mode.** D-port write operations are set to posted or non-posted mode via the data port configuration register DCR.WPE bit. The default for this parameter is true, and all D-port writes are posted. Set this parameter to false if you want the D-port operations to be non-posted. (OMAP 2320/2420 only)

Tconf Name: DCRPOSTEDERITE Type: Bool

Example: `bios.GBL.DCRPOSTEDERITE = true;`

**GBL\_getClkin***Get configured value of board input clock in KHz***C Interface****Syntax** `clkin = GBL_getClkin(Void);`**Parameters** Void**Return Value** Uint32 clkin; /\* CLKIN frequency \*/**Reentrant** yes**Description** Returns the configured value of the board input clock (CLKIN) frequency in KHz. For example, on the 'C5509, CLKIN is used to compute the settings of the USB PLL.**See Also** CLK\_countspms  
CLK\_getprd

**GBL\_getFrequency***Get current frequency of the CPU in KHz***C Interface****Syntax** frequency = GBL\_getFrequency(Void);**Parameters** Void**Return Value** Uint32 frequency; /\* CPU frequency in KHz \*/**Reentrant** yes**Description** Returns the current frequency of the DSP CPU in an integer number of KHz. This is the frequency set by GBL\_setFrequency, which must also be an integer. The default value is the value of the CLKOUT property, which is configured as one of the GBL Module Properties.**See Also** GBL\_getClkin  
GBL\_setFrequency

**GBL\_getProcid***Get configured value of processor ID***C Interface**

**Syntax**                    procid = GBL\_getProcid(Void);

**Parameters**                Void

**Return Value**            Uint16        procid;    /\* processor ID \*/

**Reentrant**                 yes

**Description**             Returns the configured value of the processor ID (PROCID) for this processor. This numeric ID value is used by the MSGQ module when determining which processor to communicate with.

The procid is also defined in the MSGQ\_TransportObj array that is part of the MSGQ\_Config structure. The same processor ID should be defined for this processor in both locations.

During the User Init Function, the application may modify the statically configured processor ID by calling GBL\_setProcid. In this case, the User Init Function may need to call GBL\_getProcid first to get the statically configured processor ID.

**See Also**                 MSGQ Module: Static Configuration  
GBL\_setProcid

**GBL\_getVersion***Get DSP/BIOS version information***C Interface**

**Syntax**                    `version = GBL_getVersion(Void);`

**Parameters**                `Void`

**Return Value**            `Uint16        version;   /* version data */`

**Reentrant**                 `yes`

**Description**             Returns DSP/BIOS kernel version information as a 4-digit hex number. For example: 0x5100. Note that the kernel version is different from the DSP/BIOS product version.

When comparing versions, compare the highest digits that are different. The digits in the version information are as follows:

Bits	Compatibility with Older DSP/BIOS Versions
12-15 (first hex digit)	Not compatible. Changes to application C, assembly, or configuration (Tconf) code may be required. For example, moving from 0x5100 to 0x6100 may require code changes.
8-11 (second hex digit)	No code changes required but you should recompile. For example, moving from 0x5100 to 0x5200 requires recompilation.
0-7 (third and fourth hex digits)	No code changes or recompile required. You should re-link if either of these digits are different. For example, moving from 0x5100 to 0x5102 requires re-linking.

The version returned by GBL\_getVersion matches the version in the DSP/BIOS header files. (For example, tsk.h.) If the header file version is as follows, GBL\_getVersion returns 0x5001. If there are three items, the last item uses two digits (for example, 01) in the returned hex number.

\* @(#) DSP/BIOS\_Kernel 5,0,1 05-30-2004 (cuda-106)

**GBL\_setFrequency***Set frequency of the CPU in KHz***C Interface****Syntax** GBL\_setFrequency( frequency );**Parameters** Uint32 frequency; /\* CPU frequency in KHz \*/**Return Value** Void**Reentrant** yes**Description** This function sets the value of the CPU frequency known to DSP/BIOS.

Note that GBL\_setFrequency does not affect the PLL, and therefore has no effect on the actual frequency at which the DSP is running. It is used only to make DSP/BIOS aware of the DSP frequency you are using.

If you call GBL\_setFrequency to update the CPU frequency known to DSP/BIOS, you should follow the sequence shown in the CLK\_reconfig topic to reconfigure the timer.

The frequency must be an integer number of KHz.

If you enable the PWRM module, do not call GBL\_setFrequency. When you use frequency scaling, the PWRM module internally calls this API to update the value known to DSP/BIOS.

**Constraints and Calling Context**

- ❑ If you change the frequency known to DSP/BIOS, you should also reconfigure the timer (with CLK\_reconfig) so that the actual frequency is the same as the frequency known to DSP/BIOS.
- ❑ Do not call this function if you use the PWRM module.

**See Also**

CLK\_reconfig  
GBL\_getClkin  
GBL\_getFrequency  
PWRM\_changeSetpoint



**GBL\_setProclId**

*Set configured value of processor ID*

**C Interface**

**Syntax**                    GBL\_setProclId( proclId );

**Parameters**                Uint16            proclId;           /\* processor ID \*/

**Return Value**                Void

**Reentrant**                    no

**Description**

Sets the processor ID (PROCID) for this processor. This numeric ID value is used by the MSGQ module to determine which processor to communicate with.

The proclId is also defined in the MSGQ\_TransportObj array that is part of the MSGQ\_Config structure.

This function can only be called in the User Init Function configured as part of the GBL Module Properties. That is, this function may only be called at the beginning of DSP/BIOS initialization.

The application may determine the true processor ID for the device during the User Init Function and call GBL\_setProclId with the correct processor ID. This is useful in applications that run a single binary image on multiple DSP processors.

How the application determines the correct processor ID is application- or board-specific. For example, you might use GPIO. You can call GBL\_getProclId from the User Init Function to get the statically configured processor ID.

**Constraints and Calling Context**

- ❑ This function can only be called in the User Init Function configured as part of the GBL Module Properties.

**See Also**

MSGQ Manager Properties  
 GBL\_getProclId

## 2.7 GIO Module

The GIO module is the Input/Output Module used with IOM mini-drivers as described in *DSP/BIOS Device Driver Developer's Guide* (SPRU616).

### Functions

- ❑ GIO\_abort. Abort all pending input and output.
- ❑ GIO\_control. Device specific control call.
- ❑ GIO\_create. Allocate and initialize a GIO object.
- ❑ GIO\_delete. Delete underlying mini-drivers and free up the GIO object and any associated IOM packet structures.
- ❑ GIO\_flush. Drain output buffers and discard any pending input.
- ❑ GIO\_new. Initialize a GIO object using pre-allocated memory.
- ❑ GIO\_read. Synchronous read command.
- ❑ GIO\_submit. Submits a packet to the mini-driver.
- ❑ GIO\_write. Synchronous write command.

### Constants, Types, and Structures

```

/* Modes for GIO_create */
#define IOM_INPUT      0x0001
#define IOM_OUTPUT     0x0002
#define IOM_INOUT      (IOM_INPUT | IOM_OUTPUT)

/* IOM Status and Error Codes */
#define IOM_COMPLETED SYS_OK /* I/O successful */
#define IOM_PENDING    1 /* I/O queued and pending */
#define IOM_FLUSHED    2 /* I/O request flushed */
#define IOM_ABORTED    3 /* I/O aborted */
#define IOM_EBADIO     -1 /* generic failure */
#define IOM_ETIMEOUT   -2 /* timeout occurred */
#define IOM_ENOPACKETS -3 /* no packets available */
#define IOM_EFREE      -4 /* unable to free resources */
#define IOM_EALLOC     -5 /* unable to alloc resource */
#define IOM_EABORT     -6 /* I/O aborted uncompleted */
#define IOM_EBADMODE   -7 /* illegal device mode */
#define IOM_EOF        -8 /* end-of-file encountered */
#define IOM_ENOTIMPL   -9 /* operation not supported */
#define IOM_EBADARGS   -10 /* illegal arguments used */
#define IOM_ETIMEOUTUNREC -11
                        /* unrecoverable timeout occurred */
#define IOM_EINUSE     -12 /* device already in use */

```

```

/* Command codes for IOM_Packet */
#define IOM_READ    0
#define IOM_WRITE   1
#define IOM_ABORT   2
#define IOM_FLUSH   3
#define IOM_USER    128 /* 0-127 reserved for system */

/* Command codes reserved for control */
#define IOM_CHAN_RESET    0 /* reset channel only */
#define IOM_CHAN_TIMEDOUT 1
                        /* channel timeout occurred */
#define IOM_DEVICE_RESET  2 /* reset entire device */
#define IOM_CNTL_USER     128
                        /* 0-127 reserved for system */

/* Structure passed to GIO_create */
typedef struct GIO_Attrs {
    Int    nPackets; /* number of asynch I/O packets */
    Uns    timeout;  /* for blocking (SYS_FOREVER) */
} GIO_Attrs;

/* Struct passed to GIO_submit for synchronous use*/
typedef struct GIO_AppCallback {
    GIO_TappCallback    fxn;
    Ptr                 arg;
} GIO_AppCallback;

typedef struct GIO_Obj {
    IOM_Fxns    *fxns; /* ptr to function table */
    Uns         mode;  /* create mode */
    Uns         timeout; /* timeout for blocking */
    IOM_Packet  syncPacket; /* for synchronous use */
    QUE_Obj    freeList; /* frames for asynch I/O */
    Ptr        syncObj;  /* ptr to synchro. obj */
    Ptr        mdChan;   /* ptr to channel obj */
} GIO_Obj, *GIO_Handle;

typedef struct IOM_Fxns
{
    IOM_TmdBindDev    mdBindDev;
    IOM_TmdUnBindDev mdUnBindDev;
    IOM_TmdControlChan mdControlChan;
    IOM_TmdCreateChan mdCreateChan;
    IOM_TmdDeleteChan mdDeleteChan;
    IOM_TmdSubmitChan mdSubmitChan;
} IOM_Fxns;

```

```

typedef struct IOM_Packet { /* frame object */
    QUE_Elem  link;      /* queue link */
    Ptr       addr;      /* buffer address */
    size_t    size;      /* buffer size */
    Arg       misc;      /* reserved for driver */
    Arg       arg;        /* user argument */
    Uns       cmd;        /* mini-driver command */
    Int       status;    /* status of command */
} IOM_Packet;

```

## Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the GIO Manager Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

### Module Configuration Parameters

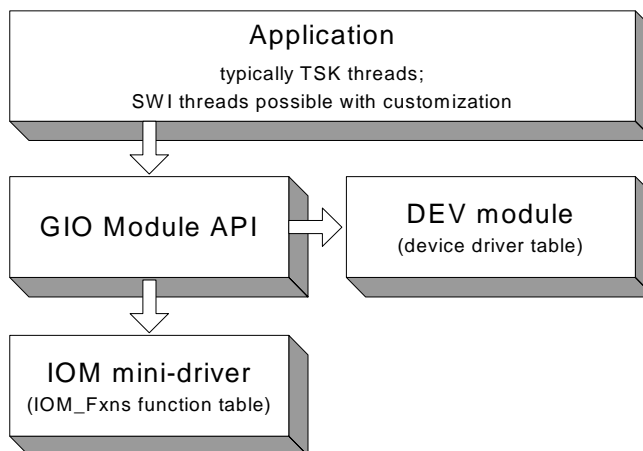
Name	Type	Default
ENABLEGIO	Bool	false
CREATEFXN	Extern	prog.extern("FXN_F_nop")
DELETFXN	Extern	prog.extern("FXN_F_nop")
PENDFXN	Extern	prog.extern("FXN_F_nop")
POSTFXN	Extern	prog.extern("FXN_F_nop")

## Description

The GIO module provides a standard interface to mini-drivers for devices such as UARTs, codecs, and video capture/display devices. The creation of such mini-drivers is not covered in this manual; it is described in *DSP/BIOS Device Driver Developer's Guide* (SPRU616).

The GIO module is independent of the actual mini-driver being used. It allows the application to use a common interface for I/O requests. It also handles response synchronization. It is intended as common "glue" to bind applications to device drivers.

The following figure shows how modules are related in an application that uses the GIO module and an IOM mini-driver:



The GIO module is the basis of communication between applications and mini-drivers. The DEV module is responsible for maintaining the table of device drivers that are present in the system. The GIO module obtains device information by using functions such as DEV\_match.

## GIO Manager Properties

The following global properties can be set for the GIO module in the GIO Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **Enable General Input/Output Manager.** Set this property to true to enable use of the GIO module. If your application does not use GIO, you should leave it disabled to prevent additional modules (such as SEM) from being linked into your application.

Tconf Name: ENABLEGIO Type: Bool

Example: `bios.GIO.ENABLEGIO = false;`

- ❑ **Create Function.** The function the GIO module should use to create a synchronization object. This function is typically SEM\_create. If you use another function, that function should have a prototype that matches that of SEM\_create: `Ptr CREATEFXN(Int count, Ptr attrs);`

Tconf Name: CREATEFXN Type: Extern

Example: `bios.GIO.CREATEFXN =  
          prog.extern("SEM_create");`

- ❑ **Delete Function.** The function the GIO module should use to delete a synchronization object. This function is typically `SEM_delete`. If you use another function, that function should have a prototype that matches that of `SEM_delete`: `Void DELETEDFXN(Ptr semHandle)`;

Tconf Name: `DELETEDFXN` Type: Extern

Example: 

```
bios.GIO.DELETEDFXN =  
    prog.extern("SEM_delete");
```

- ❑ **Pend Function.** The function the GIO module should use to pend on a synchronization object. This function is typically `SEM_pend`. If you use another function, that function should have a prototype that matches that of `SEM_pend`: `Bool PENDFXN(Ptr semHandle, Uns timeout)`;

Tconf Name: `PENDFXN` Type: Extern

Example: 

```
bios.GIO.PENDFXN =  
    prog.extern("SEM_pend");
```

- ❑ **Post Function.** The function the GIO module should use to post a synchronization object. This function is typically `SEM_post`. If you use another function, that function should have a prototype that matches that of `SEM_post`: `Void POSTFXN(Ptr semHandle)`;

Tconf Name: `POSTFXN` Type: Extern

Example: 

```
bios.GIO.POSTFXN =  
    prog.extern("SEM_post");
```

## GIO Object Properties

GIO objects cannot be created statically. In order to create a GIO object, the application should call `GIO_create` or `GIO_new`.







**GIO\_create***Allocate and initialize a GIO object***C Interface**

**Syntax**                   gioChan = GIO\_create(name, mode, \*status, chanParams, \*attrs)

**Parameters**

String	name	/* name of the device to open */
Int	mode	/* mode in which the device is to be opened */
Int	*status	/* address to place driver return status */
Ptr	chanParams	/* optional */
GIO_Attrs	*attrs	/* pointer to a GIO_Attrs structure */

**Return Value**           GIO\_Handle gioChan;    /\* handle to an instance of the device \*/

**Description**

An application calls GIO\_create to create a GIO\_Obj object and open a communication channel. This function initializes the I/O channel and opens the lower-level device driver channel. The GIO\_create call also creates the synchronization objects it uses and stores them in the GIO\_Obj object.

The name argument is the name specified for the device when it was created in the configuration or at runtime.

The mode argument specifies the mode in which the device is to be opened. This may be IOM\_INPUT, IOM\_OUTPUT, or IOM\_INOUT.

If the status returned by the device is non-NULL, a status value is placed at the address specified by the status parameter.

The chanParams parameter is a pointer that may be used to pass device or domain-specific arguments to the mini-driver. The contents at the specified address are interpreted by the mini-driver in a device-specific manner.

The attrs parameter is a pointer to a structure of type GIO\_Attrs.

```
typedef struct GIO_Attrs {
    Int  nPackets; /* number of asynch I/O packets */
    Uns  timeout; /* for blocking calls (SYS_FOREVER) */
} GIO_Attrs;
```

If attrs is NULL, a default set of attributes is used. The default for nPackets is 2. The default for timeout is SYS\_FOREVER.

The GIO\_create call allocates a list of IOM\_Packet items as specified by the nPackets member of the GIO\_Attrs structure and stores them in the GIO\_Obj object it creates.

GIO\_create returns a handle to the GIO\_Obj object created upon a successful open. The handle returned by this call should be used by the application in subsequent calls to GIO functions. This function returns a NULL handle if the device could not be opened. For example, if a device is opened in a mode not supported by the device, this call returns a NULL handle.

A call to GIO\_create results in a call to the mdCreateChan function of the associated mini-driver.

### Constraints and Calling Context

- ❑ A GIO stream can only be used by one task simultaneously. Catastrophic failure can result if more than one task calls GIO\_read on the same input stream, or more than one task calls GIO\_write on the same output stream.
- ❑ GIO\_create cannot be called from the context of a SWI or HWI thread.
- ❑ This function can be called only after the device has been loaded and initialized.

### Example

```
/* Create a device instance */
gioAttrs = GIO_ATTRS;
gioChan = GIO_create("\Codec0", IOM_INPUT, NULL, NULL,
                    &gioAttrs);
GIO_new
```



**GIO\_flush***Drain output buffers and discard any pending input***C Interface**

**Syntax**                    `status = GIO_flush(gioChan);`

**Parameters**                `GIO_Handle gioChan; /* handle to an instance of the device */`

**Return Value**              `Int                status; /* returns IOM_COMPLETED if successful */`

**Description**

An application calls `GIO_flush` to flush the input and output channels of the device. All input data is discarded; all pending output requests are completed. When this call is made, all pending input calls are completed with a status of `IOM_FLUSHED`, and all output calls are completed routinely.

The `gioChan` parameter is the handle returned by `GIO_create` or `GIO_new`.

This call returns `IOM_COMPLETED` upon successfully flushing all input and output. If an error occurs, the device returns a negative value. For a list of error values, see “Constants, Types, and Structures” on page 2-118.

A call to `GIO_flush` results in a call to the `mdSubmit` function of the associated mini-driver. The `IOM_FLUSH` command is passed to the `mdSubmit` function. The `mdSubmit` call is typically a blocking call, so calling `GIO_flush` can result in the thread blocking while waiting for output calls to be completed.

**Constraints and Calling Context**

- ❑ This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to `GIO_create` or `GIO_new`.
- ❑ `GIO_flush` cannot be called from a SWI or HWI unless the underlying mini-driver is a non-blocking driver and the GIO Manager properties are set to use non-blocking synchronization methods.

**Example**

```
/* Flush all I/O given to the device*/
GIO_flush(gioChan);
```

**GIO\_new***Initialize a GIO object with pre-allocated memory***C Interface**

<b>Syntax</b>	<code>gioChan = GIO_new(gioChan, name, mode, *status, optArgs, packetBuf[], syncObject, *attrs);</code>																
<b>Parameters</b>	<table> <tr> <td><code>GIO_Handle gioChan</code></td> <td><code>/* Handle to GIO Obj */</code></td> </tr> <tr> <td><code>String name</code></td> <td><code>/* name of the device to open */</code></td> </tr> <tr> <td><code>Int mode</code></td> <td><code>/* mode in which the device is to be opened */</code></td> </tr> <tr> <td><code>Int *status</code></td> <td><code>/* address to place driver return status */</code></td> </tr> <tr> <td><code>Ptr optArgs</code></td> <td><code>/* optional args to mdCreateChan */</code></td> </tr> <tr> <td><code>IOM_packet packetBuf[]</code></td> <td><code>/* to be initialized to zero */</code></td> </tr> <tr> <td><code>Ptr syncObject</code></td> <td><code>/* sync Object */</code></td> </tr> <tr> <td><code>GIO_Attrs *attrs</code></td> <td><code>/* pointer to a GIO_Attrs structure */</code></td> </tr> </table>	<code>GIO_Handle gioChan</code>	<code>/* Handle to GIO Obj */</code>	<code>String name</code>	<code>/* name of the device to open */</code>	<code>Int mode</code>	<code>/* mode in which the device is to be opened */</code>	<code>Int *status</code>	<code>/* address to place driver return status */</code>	<code>Ptr optArgs</code>	<code>/* optional args to mdCreateChan */</code>	<code>IOM_packet packetBuf[]</code>	<code>/* to be initialized to zero */</code>	<code>Ptr syncObject</code>	<code>/* sync Object */</code>	<code>GIO_Attrs *attrs</code>	<code>/* pointer to a GIO_Attrs structure */</code>
<code>GIO_Handle gioChan</code>	<code>/* Handle to GIO Obj */</code>																
<code>String name</code>	<code>/* name of the device to open */</code>																
<code>Int mode</code>	<code>/* mode in which the device is to be opened */</code>																
<code>Int *status</code>	<code>/* address to place driver return status */</code>																
<code>Ptr optArgs</code>	<code>/* optional args to mdCreateChan */</code>																
<code>IOM_packet packetBuf[]</code>	<code>/* to be initialized to zero */</code>																
<code>Ptr syncObject</code>	<code>/* sync Object */</code>																
<code>GIO_Attrs *attrs</code>	<code>/* pointer to a GIO_Attrs structure */</code>																
<b>Return Value</b>	<code>GIO_Handle gioChan;</code> <code>/* handle to the initialized GIO object */</code>																

**Description**

An application calls `GIO_new` to initialize a `GIO_Obj` object and open a communication channel. This function initializes the I/O channel and opens the lower-level device driver channel. The `GIO_new` call *does not* allocate any memory. It requires pre-allocated memory.

The "gioChan" parameter is a handle to a structure of type `GIO_Obj` that your program has declared. `GIO_new` initializes this structure.

```
typedef struct GIO_Obj {
    IOM_Fxns *fxns;      /* ptr to function table */
    Uns mode;           /* create mode */
    Uns timeout;        /* timeout for blocking */
    IOM_Packet syncPacket; /* for synchronous use */
    QUE_Obj freeList;   /* frames for asynch I/O */
    Ptr syncObj;        /* ptr to synchro. obj */
    Ptr mdChan;         /* ptr to channel obj */
} GIO_Obj, *GIO_Handle;
```

The "name" parameter is the name previously specified for the device. It is used to find a matching name in the device table.

The "mode" parameter specifies the mode in which the device is to be opened. This may be `IOM_INPUT`, `IOM_OUTPUT`, or `IOM_INOUT`.

If the status returned by the device is non-NULL, a status value is placed at the address specified by the "status" parameter.

The "optArgs" parameter is a pointer that may be used to pass device or domain-specific arguments to the mini-driver. The contents at the specified address are interpreted by the mini-driver in a device-specific manner.

Use the "packetBuf[]" array to pass a list of IOM\_Packet items. The number of items should match the nPackets member of the GIO\_Attrs structure passed to the "attrs" parameter. GIO\_new initializes these IOM\_Packet items.

The "syncObject" parameter is usually a SEM handle.

The "attrs" parameter is a pointer to a structure of type GIO\_Attrs.

```
typedef struct GIO_Attrs {
    Int nPackets; /* number of asynch I/O packets */
    Uns timeout; /* for blocking calls (SYS_FOREVER) */
} GIO_Attrs;
```

If attrs is NULL, a default set of attributes is used. The default for nPackets is 2. The default for timeout is SYS\_FOREVER. GIO\_new initializes the packets, but does not allocate them.

GIO\_new returns the non-NULL handle to the GIO\_Obj when initialization is successful. The handle returned by this call should be used by the application in subsequent calls to GIO functions. Usually, this is the same handle passed to GIO\_new. However, GIO\_new returns a NULL handle if the device could not be initialized. For example, if a device is opened in a mode not supported by the device, this call returns a NULL handle.

A call to GIO\_new results in a call to the mdCreateChan function of the associated mini-driver.

## Constraints and Calling Context

- ❑ This function can be called only after the device has been loaded and initialized.

## Example

```
/* Initialize a device object */
output = GIO_new(&outObj, "/printf", IOM_OUTPUT,
                &status, NULL, outPacketBuf, outSem, &attrs);
GIO_create
```

**GIO\_read***Synchronous read command***C Interface**

<b>Syntax</b>	<code>status = GIO_read(gioChan, bufp, *pSize);</code>
<b>Parameters</b>	<p><code>GIO_Handle gioChan; /* handle to an instance of the device */</code>  <code>Ptr bufp /* pointer to data structure for buffer data */</code>  <code>size_t *pSize /* pointer to size of bufp structure */</code></p>
<b>Return Value</b>	<code>Int status; /* returns IOM_COMPLETED if successful */</code>

**Description**

An application calls `GIO_read` to read a specified number of MADUs (minimum addressable data units) from the communication channel.

The `gioChan` parameter is the handle returned by `GIO_create` or `GIO_new`.

The `bufp` parameter points to a device-defined data structure for passing buffer data between the device and the application. This structure may be generic across a domain or specific to a single mini-driver. In some cases, this parameter may point directly to a buffer that holds the read data. In other cases, this parameter may point to a structure that packages buffer information, size, offset to be read from, and other device-dependent data. For example, for video capture devices this structure may contain pointers to RGB buffers, their sizes, video format, and a host of data required for reading a frame from a video capture device. Upon a successful read, this argument points to the returned data.

The `pSize` parameter points to the size of the buffer or data structure pointed to by the `bufp` parameter. When the function returns, this parameter points to the number of MADUs read from the device. This parameter is relevant only if the `bufp` parameter points to a raw data buffer. In cases where it points to a device-defined structure it is redundant—the size of the structure is known to the mini-driver and the application. At most, it can be used for error checking.

`GIO_read` returns `IOM_COMPLETED` upon successfully reading the requested number of MADUs from the device. If an error occurs, the device returns a negative value. For a list of error values, see “Constants, Types, and Structures” on page 2-118.

A call to `GIO_read` results in a call to the `mdSubmit` function of the associated mini-driver. The `IOM_READ` command is passed to the `mdSubmit` function. The `mdSubmit` call is typically a blocking call, so calling `GIO_read` can result in the thread blocking.

## Constraints and Calling Context

- ❑ This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to `GIO_create` or `GIO_new`.
- ❑ `GIO_read` cannot be called from a SWI, HWI, or `main()` unless the underlying mini-driver is a non-blocking driver and the GIO Manager properties are set to use non-blocking synchronization methods.

## Example

```
/* Read from the device */  
size = sizeof(readStruct);  
status = GIO_read(gioChan, &readStruct, &size);
```





The `appCallback` parameter points to either a callback structure that contains the callback function to be called when the request completes, or it points to `NULL`, which causes the call to be synchronous. When a queued request is completed, the callback routine (if specified) is invoked (i.e. blocking).

`GIO_submit` returns `IOM_COMPLETED` upon successfully carrying out the requested functionality. If the request is queued, then a status of `IOM_PENDING` is returned. If an error occurs, the device returns a negative value. For a list of error values, see “Constants, Types, and Structures” on page 2-118.

A call to `GIO_submit` results in a call to the `mdSubmit` function of the associated mini-driver. The specified command is passed to the `mdSubmit` function.

### Constraints and Calling Context

- ❑ This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to `GIO_create` or `GIO_new`.
- ❑ This function can be called within the program's `main()` function only if the GIO channel is asynchronous (non-blocking).

### Example

```
/* write asynchronously to the device*/
size = sizeof(userStruct);
status = GIO_submit(gioChan, IOM_WRITE, &userStruct,
                   &size, &callbackStruct);

/* write synchronously to the device */
size = sizeof(userStruct);
status = GIO_submit(gioChan, IOM_WRITE, &userStruct,
                   &size, NULL);
```



## Constraints and Calling Context

- ❑ This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to GIO\_create or GIO\_new.
- ❑ This function can be called within the program's main() function only if the GIO channel is asynchronous (non-blocking).
- ❑ GIO\_write cannot be called from a SWI or HWI unless the underlying mini-driver is a non-blocking driver and the GIO Manager properties are set to use non-blocking synchronization methods.

## Example

```
/* write synchronously to the device*/  
size = sizeof(writeStruct);  
status = GIO_write(gioChan, &writeStrct, &size);
```

## 2.8 HOOK Module

The HOOK module is the Hook Function manager.

### Functions

- ❑ `HOOK_getenv`. Get environment pointer for a given HOOK and TSK combination.
- ❑ `HOOK_setenv`. Set environment pointer for a given HOOK and TSK combination.

### Constants, Types, and Structures

```
typedef Int HOOK_Id;          /* HOOK instance id */

typedef Void (*HOOK_InitFxn)(HOOK_Id id);
typedef Void (*HOOK_CreateFxn)(TSK_Handle task);
typedef Void (*HOOK_DeleteFxn)(TSK_Handle task);
typedef Void (*HOOK_ExitFxn)(Void);
typedef Void (*HOOK_ReadyFxn)(TSK_Handle task);
typedef Void (*HOOK_SwitchFxn)(TSK_Handle prev,
                               TSK_Handle next);
```

### Configuration Properties

The following list shows the properties that can be configured in a `Tconf` script, along with their types and default values. For details, see the HOOK Object Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Instance Configuration Parameters

Name	Type	Default
comment	String	"<add comments here>"
initFxn	Extern	prog.extern("FXN_F_nop")
createFxn	Extern	prog.extern("FXN_F_nop")
deleteFxn	Extern	prog.extern("FXN_F_nop")
exitFxn	Extern	prog.extern("FXN_F_nop")
callSwitchFxn	Bool	false
switchFxn	Extern	prog.extern("FXN_F_nop")
callReadyFxn	Bool	false
readyFxn	Extern	prog.extern("FXN_F_nop")
order	Int16	2

### Description

The HOOK module is an extension to the TSK function hooks defined in the TSK Manager Properties. It allows multiple sets of hook functions to be performed at key execution points. For example, an application that integrates third-party software may need to perform both its own hook functions and the hook functions required by the third-party software.

In addition, each HOOK object can maintain private data environments for each task for use by its hook functions.

The key execution points at which hook functions can be executed are during program initialization and at several TSK execution points.

The HOOK module manages objects that reference a set of hook functions. Each HOOK object is assigned a numeric identifier during DSP/BIOS initialization. If your program calls HOOK API functions, you must implement an initialization function for the HOOK instance that records the identifier in a variable of type `HOOK_Id`. DSP/BIOS passes the HOOK object's ID to the initialization function as the lone parameter.

The following function, `myInit`, could be configured as the Initialization function for a HOOK object using `Tconf`.

```
#include <hook.h>
HOOK_Id myId;

Void myInit(HOOK_Id id)
{
    myId = id;
}
```

The `HOOK_setenv` function allows you to associate an environment pointer to any data structure with a particular HOOK object and TSK object combination.

There is no limit to the number of HOOK objects that can be created. However, each object requires a small amount of memory in the `.bss` section to contain the object.

A HOOK object initially has all of its functions set to `FXN_F_nop`. You can set some hook functions and use this no-op function for the remaining events. Since the switch and ready events occur frequently during real-time processing, a separate property controls whether any function is called.

When you create a HOOK object, any TSK module hook functions you have specified are automatically placed in a HOOK object called `HOOK_KNL`. To set any properties of this object other than the Initialization function, use the TSK module. To set the Initialization function property of the `HOOK_KNL` object, use the HOOK module.

When an event occurs, all HOOK functions for that event are called in the order set by the order property in the configuration. When you select the HOOK manager in the DSP/BIOS Configuration Tool, you can change the execution order by dragging objects within the ordered list.

## HOOK Manager Properties

There are no global properties for the HOOK manager. HOOK objects are placed in the C Variables Section (.bss).

## HOOK Object Properties

The following properties can be set for a HOOK object in the DPI Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script. To create a HOOK object in a configuration script, use the following syntax:

```
var myHook = bios.HOOK.create("myHook");
```

The Tconf examples that follow assume the object has been created as shown.

- ❑ **comment.** A comment to identify this HOOK object.

Tconf Name: comment Type: String

Example: `myHook.comment = "HOOK funcs";`

- ❑ **Initialization function.** The name of a function to call during program initialization. Such functions run during the BIOS\_init portion of application startup, which runs before the program's main() function. Initialization functions can call most functions that can be called from the main() function. However, they should not call TSK module functions, because the TSK module is initialized after initialization functions run. In addition to code specific to the module hook, this function should be used to record the object's ID, if it is needed in a subsequent hook function. This initialization function is intended for use in setting up data structures used by other functions of the same HOOK object. In contrast, the User Init Function property of the GBL Module Properties runs early in the initialization process and is intended to be used to perform hardware setup that needs to run before DSP/BIOS is initialized.

Tconf Name: initFxn Type: Extern

Example: `myHook.initFxn = prog.extern("myInit");`

- ❑ **Create function.** The name of a function to call when any task is created. This includes tasks that are created statically and those created dynamically using TSK\_create. The TSK\_create topic describes the prototype required for the Create function. If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.

Tconf Name: createFxn Type: Extern

Example: `myHook.createFxn =  
          prog.extern("myCreate");`

- ❑ **Delete function.** The name of a function to call when any task is deleted at run-time with `TSK_delete`.  
Tconf Name: `deleteFxn` Type: Extern  
Example: 

```
myHook.deleteFxn =  
    prog.extern("myDelete");
```
- ❑ **Exit function.** The name of a function to call when any task exits. The `TSK_exit` topic describes the Exit function.  
Tconf Name: `exitFxn` Type: Extern  
Example: 

```
myHook.exitFxn = prog.extern("myExit");
```
- ❑ **Call switch function.** Set this property to true if you want a function to be called when any task switch occurs.  
Tconf Name: `callSwitchFxn` Type: Bool  
Example: 

```
myHook.callSwitchFxn = false;
```
- ❑ **Switch function.** The name of a function to call when any task switch occurs. This function can give the application access to both the current and next task handles. The `TSK Module` topic describes the Switch function.  
Tconf Name: `switchFxn` Type: Extern  
Example: 

```
myHook.switchFxn =  
    prog.extern("mySwitch");
```
- ❑ **Call ready function.** Set this property to true if you want a function to be called when any task becomes ready to run.  
Tconf Name: `callReadyFxn` Type: Bool  
Example: 

```
myHook.callReadyFxn = false;
```
- ❑ **Ready function.** The name of a function to call when any task becomes ready to run. The `TSK Module` topic describes the Ready function.  
Tconf Name: `readyFxn` Type: Extern  
Example: 

```
myHook.readyFxn =  
    prog.extern("myReady");
```
- ❑ **order.** Set this property for all HOOK function objects match the order in which HOOK functions should be executed.  
Tconf Name: `order` Type: Int16  
Example: 

```
myHook.order = 2;
```



**HOOK\_getenv***Get environment pointer for a given HOOK and TSK combination***C Interface**

**Syntax**                    `environ = HOOK_getenv(task, id);`

**Parameters**                `TSK_Handle task;        /* task object handle */`  
`HOOK_Id    id;        /* HOOK instance id */`

**Return Value**            `Ptr            environ;   /* environment pointer */`

**Reentrant**                `yes`

**Description**             HOOK\_getenv returns the environment pointer associated with the specified HOOK and TSK objects. The environment pointer, environ, references the data structure specified in a previous call to HOOK\_setenv.

**See Also**                 HOOK\_setenv  
TSK\_getenv

**HOOK\_setenv***Set environment pointer for a given HOOK and TSK combination***C Interface**

**Syntax**                   HOOK\_setenv(task, id, environ);

**Parameters**               TSK\_Handle task;       /\* task object handle \*/  
HOOK\_Id     id;         /\* HOOK instance id \*/  
Ptr            environ; /\* environment pointer \*/

**Return Value**            Void

**Reentrant**                yes

**Description**            HOOK\_setenv sets the environment pointer associated with the specified HOOK and TSK objects to environ. The environment pointer, environ, should reference an data structure to be used by the hook functions for a task or tasks.

Each HOOK object may have a separate environment pointer for each task. A HOOK object may also point to the same data structure for all tasks, depending on its data sharing needs.

The HOOK\_getenv function can be used to get the environ pointer for a particular HOOK and TSK object combination.

**See Also**                HOOK\_getenv  
TSK\_setenv

## 2.9 HST Module

---

**Important Note:** This module is being deprecated and will no longer be supported in the next major release of DSP/BIOS.

---

The HST module is the host channel manager.

### Functions

- ❑ HST\_getpipe. Get corresponding pipe object

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the HST Manager Properties and HST Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default (Enum Options)
OBJMEMSEG	Reference	prog.get("DARAM")
HOSTLINKTYPE	EnumString	"RTDX" ("NONE")

#### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
mode	EnumString	"output" ("input")
bufSeg	Reference	prog.get("DARAM")
bufAlign	Int16	4
frameSize	Int16	128
numFrames	Int16	2
statistics	Bool	false
availableForDHL	Bool	false
notifyFxn	Extern	prog.extern("FXN_F_nop")
arg0	Arg	3

### Description

The HST module manages host channel objects, which allow an application to stream data between the target and the host. Host channels are statically configured for input or output. Input channels (also called the source) read data from the host to the target. Output channels (also called the sink) transfer data from the target to the host.



**HST Object Properties**

A host channel maintains a buffer partitioned into a fixed number of fixed length frames. All I/O operations on these channels deal with one frame at a time; although each frame has a fixed length, the application can put a variable amount of data in each frame.

The following properties can be set for a host file object in the HST Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script. To create an HST object in a configuration script, use the following syntax:

```
var myHst = bios.HST.create("myHst");
```

The Tconf examples that follow assume the object has been created as shown.

- ❑ **comment.** A comment to identify this HST object.  
 Tconf Name: comment Type: String  
 Example: `myHst.comment = "my HST";`
  
- ❑ **mode.** The type of channel: input or output. Input channels are used by the target to read data from the host; output channels are used by the target to transfer data from the target to the host.  
 Tconf Name: mode Type: EnumString  
 Options: "output", "input"  
 Example: `myHst.mode = "output";`
  
- ❑ **bufseg.** The memory segment from which the buffer is allocated; all frames are allocated from a single contiguous buffer (of size framesize x numframes).  
 Tconf Name: bufSeg Type: Reference  
 Example: `myHst.bufSeg = prog.get("myMEM");`
  
- ❑ **bufalign.** The alignment (in words) of the buffer allocated within the specified memory segment.  
 Tconf Name: bufAlign Type: Int16  
 Options: must be >= 4 and a power of 2  
 Example: `myHst.bufAlign = 4;`
  
- ❑ **framesize.** The length of each frame (in words)  
 Tconf Name: frameSize Type: Int16  
 Example: `myHst.frameSize = 128;`
  
- ❑ **numframes.** The number of frames  
 Tconf Name: numFrames Type: Int16  
 Example: `myHst.numFrames = 2;`

- ❑ **statistics.** Set this property to true if you want to monitor this channel with an STS object. You can display the STS object for this channel to see a count of the number of frames transferred with the Statistics View Analysis Tool.

Tconf Name: statistics

Type: Bool

Example: `myHst.statistics = false;`

- ❑ **Make this channel available for a new DHL device.** Set this property to true if you want to use this HST object with a DHL device. DHL devices allow you to manage data I/O between the host and target using the SIO module, rather than the PIP module. See the DHL Driver topic for more details.

Tconf Name: availableForDHL

Type: Bool

Example: `myHst.availableForDHL = false;`

- ❑ **notify.** The function to execute when a frame of data for an input channel (or free space for an output channel) is available. To avoid problems with recursion, this function should not directly call any of the PIP module functions for this HST object.

Tconf Name: notifyFxn

Type: Extern

Example: `myHst.notifyFxn =  
          prog.extern("hstNotify");`

- ❑ **arg0, arg1.** Two Arg type arguments passed to the notify function.

Tconf Name: arg0

Type: Arg

Tconf Name: arg1

Type: Arg

Example: `myHst.arg0 = 3;`

**HST\_getpipe***Get corresponding pipe object*


---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS.

---

**C Interface****Syntax**

pipe = HST\_getpipe(hst);

**Parameters**

HST\_Handle hst       /\* host object handle \*/

**Return Value**

PIP\_Handle pip       /\* pipe object handle\*/

**Reentrant**

yes

**Description**

HST\_getpipe gets the address of the pipe object for the specified host channel object.

**Example**

```

Void copy(HST_Obj *input, HST_Obj *output)
{
    PIP_Obj      *in, *out;
    Uns          *src, *dst;
    Uns          size;

    in = HST_getpipe(input);
    out = HST_getpipe(output);
    if (PIP_getReaderNumFrames == 0 ||
        PIP_getWriterNumFrames == 0) {
        error;
    }

    /* get input data and allocate output frame */
    PIP_get(in);
    PIP_alloc(out);

    /* copy input data to output frame */
    src = PIP_getReaderAddr(in);
    dst = PIP_getWriterAddr(out);
    size = PIP_getReaderSize();
    out->writerSize = size;

    for (; size > 0; size--) {
        *dst++ = *src++;
    }

    /* output copied data and free input frame */
    PIP_put(out);
    PIP_free(in);
}

```

**See Also**

PIP\_alloc

## 2.10 HWI Module

The HWI module is the hardware interrupt manager.

### Functions

- ❑ HWI\_disable. Disable hardware interrupts
- ❑ HWI\_dispatchPlug. Plug the HWI dispatcher
- ❑ HWI\_enable. Enable hardware interrupts
- ❑ HWI\_enter. Hardware ISR prolog
- ❑ HWI\_exit. Hardware ISR epilog
- ❑ HWI\_isHWI. Check current thread calling context.
- ❑ HWI\_restore. Restore hardware interrupt state

### Constants, Types, and Structures

```
typedef struct HWI_Attrs {
    Uns    ier0mask;    /* IER0 bitmask */
    Uns    ier1mask;    /* IER1 bitmask */
    Arg    arg;         /* fxn arg (default = 0) */
    LgUns  mirmask;     /* OMAP 2320/2420 only */
    LgUns  mir1mask;    /* OMAP 2320 only */
} HWI_Attrs;

HWI_Attrs HWI_ATTRS = {
    1,        /* IER0 mask (1 => self) */
    1,        /* IER1 mask (1 => self) */
    0        /* argument to ISR */
};

/* If ier0mask and ier1mask are both '1',
   mask to disable "self" is created. */
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the HWI Manager Properties and HWI Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

C55x Name	Type	Default (Enum Options)
STACKMODE	EnumString	"C54X_STK" ("USE_RETA", "NO_RETA")
INTC_BASE	Numeric	0x7e4800 (OMAP 2320/2420 only)



## Instance Configuration Parameters

HWI instances are provided as a default part of the configuration and cannot be created. In the items that follow, HWI\_INT\* may be any provided instance. Default values for many HWI properties are different for each instance

C55x Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
fxn	Extern	prog.extern("HWI_unused", "asm")
monitor	EnumString	"Nothing" ("Data Value", "xsp", "ac0g", "ac0h", "ac0l", "ac1g", "ac1h", "ac1l", "ac2g", "ac2h", "ac2l", "ac3g", "ac3h", "ac3l", "xar0", "xar1", "xar2", "xar3", "xar4", "xar5", "xar6", "xar7", "t0", "t1", "t2", "t3", "xssp", "tim", "st0_55", "st1_55", "st2_55", "st3_55", "trn0", "bk03", "brc0", "xdp", "xcdp", "dph", "mdp05", "mdp67", "pdp", "bk47", "bkc", "bsa01", "bsa23", "bsa45", "bsa67", "bsac", "trn1", "brc1", "csr", "rptc")
addr	Arg	0x00000000
dataType	EnumString	"signed" ("unsigned")
operation	EnumString	"STS_add(*addr)" ("STS_delta(*addr)", "STS_add(-*addr)", "STS_delta(-*addr)", "STS_add(!*addr)", "STS_delta(!*addr)")
useDispatcher	Bool	false
arg	Arg	0
interruptMask0	EnumString	"self" ("all", "none", "bitmask")
interruptMask1	EnumString	"self" ("all", "none", "bitmask")
interruptBitMask0	Numeric	0x0010 *
interruptBitMask1	Numeric	0x0010 *
iMirMask	EnumString	"self" ("all", "none", "bitmask") (OMAP 2320/2420 only)
mirmask	Numeric	0x00000000 * (OMAP 2320/2420 only)
mir1mask	Numeric	0x00000000 * (OMAP 2320 only)
priority	Numeric	0 (0-31 or 0-63) (OMAP 2320/2420 only)

\* Depends on interrupt ID

### Description

The HWI module manages hardware interrupts. Using Tconf, you can assign routines that run when specific hardware interrupts occur. Some routines are assigned to interrupts automatically by the HWI module. For example, the interrupt for the timer that you select for the CLK global properties is automatically configured to run a function that increments the low-resolution time. See the CLK Module for more details.

You can also dynamically assign routines to interrupts at run-time using the HWI\_dispatchPlug function or the C55\_plug function.

Interrupt routines can be written completely in assembly, completely in C, or in a mix of assembly and C. In order to support interrupt routines written completely in C, an HWI dispatcher is provided that performs the requisite prolog and epilog for an interrupt routine.

---

**Note: RTS Functions Callable from TSK Threads Only**

Many runtime support (RTS) functions use lock and unlock functions to prevent reentrancy. However, DSP/BIOS SWI and HWI threads cannot call LCK\_pend and LCK\_post. As a result, RTS functions that call LCK\_pend or LCK\_post *must not be called in the context of a SWI or HWI thread*. For a list of RTS functions that should not be called from a SWI or an HWI function, see "LCK\_pend" on page 2-180.

---

The C++ "new" operator calls malloc, which in turn calls LCK\_pend. As a result, the "new" operator cannot be used in the context of a SWI or HWI thread.

**HWI Dispatcher vs. HWI\_enter/exit**

The HWI dispatcher is the preferred method for handling an interrupt.

When an HWI object does not use the dispatcher, the HWI\_enter assembly macro must be called prior to any DSP/BIOS API calls that affect other DSP/BIOS objects, such as posting a SWI or a semaphore, and the HWI\_exit assembly macro must be called at the very end of the function's code.

When an HWI object is configured to use the dispatcher, the dispatcher handles the HWI\_enter prolog and HWI\_exit epilog, and the HWI function can be completely written in C. It would, in fact, cause a system crash for the dispatcher to call a function that contains the HWI\_enter/HWI\_exit macro pair. Using the dispatcher allows you to save code space by including only one instance of the HWI\_enter/HWI\_exit code.

---

**Note:**

CLK functions should not call HWI\_enter and HWI\_exit as these are called internally by DSP/BIOS when it runs CLK\_F\_isr. Additionally, CLK functions should **not** use the *interrupt* keyword or the INTERRUPT pragma in C functions.

---

## Notes

In the following notes, references to the usage of HWI\_enter/HWI\_exit also apply to usage of the HWI dispatcher since, in effect, the dispatcher calls HWI\_enter/HWI\_exit.

- ❑ Do not call SWI\_disable or SWI\_enable within an HWI function.
- ❑ Do not call HWI\_enter, HWI\_exit, or any other DSP/BIOS functions from a non-maskable interrupt (NMI) service routine. In addition, the HWI dispatcher cannot be used with the NMI service routine.
- ❑ Do not call HWI\_enter/HWI\_exit from a HWI function that is invoked by the dispatcher.
- ❑ The DSP/BIOS API calls that require an HWI function to use HWI\_enter and HWI\_exit are:
  - SWI\_andn
  - SWI\_andnHook
  - SWI\_dec
  - SWI\_inc
  - SWI\_or
  - SWI\_orHook
  - SWI\_post
  - PIP\_alloc
  - PIP\_free
  - PIP\_get
  - PIP\_put
  - PRD\_tick
  - SEM\_post
  - MBX\_post
  - TSK\_yield
  - TSK\_tick

Any PIP API call can cause the pipe's notifyReader or notifyWriter function to run. If an HWI function calls a PIP function, the notification functions run as part of the HWI function.

An HWI function must use HWI\_enter and HWI\_exit or must be dispatched by the HWI dispatcher if it indirectly runs a function containing any of the API calls listed above.

If your HWI function and the functions it calls do not call any of these API operations, you do not need to disable SWI scheduling by calling HWI\_enter and HWI\_exit.

## DSP/BIOS and NMI Support

You should use the NMI interrupt only if tasking is disabled (that is, in a SWI-only system) or if tasking is enabled but all the task stacks and the ISR stack are in the same memory page. This is because it is not possible to atomically modify SP, SSP, and the page register such that the whole operation is protected from an NMI (non-maskable interrupt). When tasking is enabled, DSP/BIOS modifies these registers whenever an interrupt occurs, whenever a SWI is executed, and whenever a task context switch takes place. Thus it is possible for an NMI to occur when the state of these registers is not internally consistent. This could result in unpredictable behavior when the DSP tries to push the processor state onto the stack on its way to the NMI vector.

## Registers and Stack

Whether a hardware interrupt is dispatched by the HWI dispatcher or handled with the `HWI_enter`/`HWI_exit` macros, a common interrupt stack (called the system stack) is used for the duration of the HWI. This same stack is also used by all SWI routines.

The register mask argument to `HWI_enter` and `HWI_exit` allows you to save and restore registers used within the function. Other arguments, for example, allow the HWI to control the settings of the IMR or, in the case of the C55x device, the IER0[IER1].

---

**Note:**

By using `HWI_enter` and `HWI_exit` as an HWI function's prolog and epilog, an HWI function can be interrupted; that is, a hardware interrupt can interrupt another interrupt. For the c55x device, you can use the `IER0DISABLEMASK` and `IER1DISABLEMASK` parameters to prevent this from occurring.

---

## HWI Manager Properties

DSP/BIOS manages the hardware interrupt vector table and provides basic hardware interrupt control functions; for example, enabling and disabling the execution of hardware interrupts.

The following global properties can be set for the HWI module in the HWI Manager Properties dialog of Gconf or in a Tconf script:

- Stack Mode.** Select the Stack Mode used for the application: `C54X_STK`, `USE_RETA` or `NO_RETA`. The stack mode selected here takes effect only if the program address `0xffff00` (the hardware reset vector location) is programmable and the linker is configured to place the vector table (`.hwi_vec` section) at address `0xffff00`. If this

address is located in ROM space, it is not programmable. DSP/BIOS does not report an error if it is unable to modify the value at this address to set the specified stack mode.

Tconf Name: STACKMODE Type: EnumString

Options: "C54X\_STK", "USE\_RETA", "NO\_RETA"

Example: `bios.HWI.STACKMODE = "C54X_STK";`

To set the 'C55x stackmode, perform all of the following steps:

- Set the stackmode configuration property to the mode you want to use in your configuration using a statement similar to the preceding example.
- Add the following arguments to your linker command line. These arguments force a soft reset using the RAM-based interrupt vector table.

```
-u C55_c_int00 -e C55_c_int00
```

- Make sure the .hwi\_vec memory section (the interrupt vector table) is located in RAM. By default, this section is automatically located at the top of RAM.

- **Interrupt Controller Base.** By default, the OMAP 2420 Level 2 Interrupt Controller (L2IC) resides at data memory address 0x7e4800. This coincides with the reset IOMA value of 0x3f. For OMAP 2320, the default base address is 0x7c4800, which coincides with the reset IOMA value of 0x3e. The IO MAP (IOMA) base address is the page index used to access DSP I/O space addresses from DSP memory space. If you modify IOMA for any reason, you need to use this property to tell DSP/BIOS the new base address for the L2IC. (OMAP 2320/2420 only)

Tconf Name: INTC\_BASE Type: Numeric

Example: `bios.HWI.INTC_BASE = 0x7e4800;`

## HWI Object Properties

The following properties can be set for an HWI object in the HWI Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script. The HWI objects for the platform are provided in the default configuration and cannot be created.

- **comment.** A comment is provided to identify each HWI object.

Tconf Name: comment Type: String

Example: `bios.HWI_INT2.comment = "myISR";`

- **function.** The function to execute. Interrupt routines that use the dispatcher can be written completely in C or any combination of assembly and C but must not call the HWI\_enter/HWI\_exit macro pair. Interrupt routines that don't use the dispatcher must be written

at least partially in assembly language. Within an HWI function that does not use the dispatcher, the `HWI_enter` assembly macro must be called prior to any DSP/BIOS API calls that affect other DSP/BIOS objects, such as posting a SWI or a semaphore. HWI functions can post SWIs, but they do not run until your HWI function (or the dispatcher) calls the `HWI_exit` assembly macro, which must be the last statement in any HWI function that calls `HWI_enter`.

Tconf Name: `fxn` Type: Extern

Example: `bios.HWI_INT2.fxn = prog.extern("myHWI", "asm");`

- ❑ **monitor.** If set to anything other than Nothing, an STS object is created for this HWI that is passed the specified value on every invocation of the HWI function. The STS update occurs just before entering the HWI routine.

Be aware that when the monitor property is enabled for a particular HWI object, a code preamble is inserted into the HWI routine to make this monitoring possible. The overhead for monitoring is 20 to 30 instructions per interrupt, per HWI object monitored. Leaving this instrumentation turned on after debugging is not recommended, since HWI processing is the most time-critical part of the system.

Options: "Nothing", "Data Value", "xsp", "ac0g", "ac0h", "ac0l", "ac1g", "ac1h", "ac1l", "ac2g", "ac2h", "ac2l", "ac3g", "ac3h", "ac3l", "xar0", "xar1", "xar2", "xar3", "xar4", "xar5", "xar6", "xar7", "t0", "t1", "t2", "t3", "xssp", "tim", "st0\_55", "st1\_55", "st2\_55", "st3\_55", "trn0", "bk03", "brc0", "xdp", "xcdp", "dph", "mdp05", "mdp67", "pdp", "bk47", "bkc", "bsa01", "bsa23", "bsa45", "bsa67", "bsac", "trn1", "brc1", "csr", "rptc"

Example: `bios.HWI_INT2.monitor = "Nothing";`

- ❑ **addr.** If the monitor property above is set to Data Address, this property lets you specify a data memory address to be read; the word-sized value is read and passed to the STS object associated with this HWI object.

Tconf Name: `addr` Type: Arg

Example: `bios.HWI_INT2.addr = 0x00000000;`

- ❑ **type.** The type of the value to be monitored: unsigned or signed. Signed quantities are sign extended when loaded into the accumulator; unsigned quantities are treated as word-sized positive values.

Tconf Name: `dataType` Type: EnumString

Options: "signed", "unsigned"

Example: `bios.HWI_INT2.dataType = "signed";`

- ❑ **operation.** The operation to be performed on the value monitored. You can choose one of several STS operations.

Tconf Name: operation Type: EnumString

Options: "STS\_add(\*addr)", "STS\_delta(\*addr)", "STS\_add(-\*addr)", "STS\_delta(-\*addr)", "STS\_add(!\*addr)", "STS\_delta(!\*addr)"

Example: 

```
bios.HWI_INT2.operation =
           "STS_add(*addr)";
```

- ❑ **Use Dispatcher.** A check box that controls whether the HWI dispatcher is used. The HWI dispatcher cannot be used for the non-maskable interrupt (NMI) service routine.

Tconf Name: useDispatcher Type: Bool

Example: 

```
bios.HWI_INT2.useDispatcher = false;
```

- ❑ **Arg.** This argument is passed to the function as its only parameter. You can use either a literal integer or a symbol defined by the application. This property is available only when using the HWI dispatcher.

Tconf Name: arg Type: Arg

Example: 

```
bios.HWI_INT2.arg = 3;
```

- ❑ **Interrupt Mask.** Specifies which interrupts the dispatcher should disable before calling the function. This property is available only when using the HWI dispatcher.

- The "self" option causes the dispatcher to disable only the current interrupt and causes the appropriate interruptBitMask0, interruptBitMask1, and mirmask/mir1mask values to be generated for the interrupt being configured. When using "self", set both interruptMask0 and interruptMask1 (and iMirMask if the platform is OMAP 2320/2420) to "self".

- The "all" option disables all interrupts.

- The "none" option disables no interrupts.

- The "bitmask" option causes the interruptBitMask[0/1] property to be used to specify which interrupts to disable.

(For 'C55x, separate interruptMasks are provided for IER0 and IER1.) (For OMAP 2320/2420, these properties control only the level 1 interrupts. The iMirMask property controls the level 2 interrupts.)

Tconf Name: interruptMask0 Type: EnumString

Tconf Name: interruptMask1 Type: EnumString

Options: "self", "all", "none", "bitmask"

Example: 

```
bios.HWI_INT2.interruptMask0 = "self";
```

- ❑ **Interrupt Bit Mask.** An integer property that is writable when the interrupt mask is set to "bitmask". This should be a hexadecimal integer bitmask specifying the interrupts to disable. (For 'C55x, separate properties are provided for IER0 and IER1.) For OMAP 2320/2420, these properties disable only level 1 interrupts. The mirmask property (and mir1mask for OMAP 2320) controls the level 2 interrupts.

Tconf Name: interruptBitMask0 Type: Numeric

Tconf Name: interruptBitMask1 Type: Numeric

Example: `bios.HWI_INT2.interruptBitMask0 =  
0x0010;`

- ❑ **L2 Interrupt Mask MIR (and MIR1).** This property is valid for both level 1 and 2 interrupts. It specifies which level 2 interrupts the dispatcher should disable before calling this HWI function. This property is writeable only if the useDispatcher property is set to true.
  - The "self" option causes the dispatcher to disable only the current interrupt and causes the appropriate interruptBitMask0, interruptBitMask1, mirmask, and mir1mask values to be generated for the interrupt being configured. When using "self", set all of interruptMask0, interruptMask1, and iMirMask to "self".
  - The "all" option disables all level 2 interrupts.
  - The "none" option disables no level 2 interrupts.
  - The "bitmask" option causes the mirmask (and mir1mask for OMAP 2320) property to be used to specify which level 2 interrupts to disable.

This property is similar to interruptMask0 and interruptMask1, which deal with level 1 interrupts. (OMAP 2320/2420 only)

Tconf Name: iMirMask Type: EnumString

Options: "self", "all", "none", "bitmask"

Example: `bios.HWI_INT2.iMirMask = "self";`

- ❑ **L2 Interrupt Bit Mask MIR.** This property is valid for both level 1 and 2 interrupts. It defines a bitmask of level 2 interrupts 0-31 to be disabled by the DSP/BIOS HWI dispatcher when executing this HWI function. This property is writeable only when the useDispatcher property is set to true and iMirMask is set to "bitmask". This property is similar to interruptBitMask0 and interruptBitMask1, which mask level 1 interrupts. The default value is to disable only the current level 2 interrupt. (OMAP 2320/2420 only)

Tconf Name: mirmask Type: Numeric

Example: `bios.HWI_INT2.mirmask = 0x00000000;`



- ❑ **L2 Interrupt Bit Mask MIR1.** This property is similar to the previous one, except that it defines a bitmask of level 2 interrupts 32-63 for OMAP 2320 only.

Tconf Name: mir1mask

Type: Numeric

Example: `bios.HWI_INT2.mir1mask = 0x00000000;`

- ❑ **L2 Interrupt Priority.** For OMAP 2320, sets a priority from 0 to 63 for a level 2 interrupt. For OMAP 2420, sets a priority from 0 to 31 for a level 2 interrupt. Zero is the highest priority. The default priority for a level 2 interrupt matches its interrupt number. Although this field exists for all HWI interrupt objects, it cannot be configured for level 1 interrupts. You can change the priority at run-time using the C55\_I2SetIntPriority API. (OMAP 2320/2420 only)

Tconf Name: priority

Type: Numeric

Example: `bios.HWI_INT2.priority = 0;`

Although it is not possible to create new HWI objects, most interrupts supported by the device architecture have a precreated HWI object. Your application can require that you select interrupt sources other than the default values in order to rearrange interrupt priorities or to select previously unused interrupt sources.

In addition to the precreated HWI objects, some HWI objects are preconfigured for use by certain DSP/BIOS modules. For example, the CLK module configures an HWI object.

Table 2-3 list these precreated objects and their default interrupt sources. The HWI object names are the same as the interrupt names.

Table 2-3. HWI interrupts for the 'C55x

<b>Name</b>	<b>Interrupt Type</b>
HWI_RESET	Reset interrupt.
HWI_NMI	Non-maskable interrupt. (See page 2–152)
HWI_INT2	Maskable (IER0, bit2) hardware interrupt.
HWI_INT3	Maskable (IER0, bit3) hardware interrupt.
HWI_TINT	Timer interrupt. (IER, bit4)
HWI_INT5 through HWI_INT15	Maskable (IER0, bit5) hardware interrupt through Maskable (IER0, bit15) hardware interrupt.
HWI_INT16 through HWI_INT23	Maskable (IER1, bit0) hardware interrupt through Maskable (IER1, bit7) hardware interrupt.
HWI_BERR	Maskable (IER1, bit8) bus error interrupt.
HWI_DLOG	Maskable (IER1, bit9) data log interrupt.
HWI_RTOS	Maskable (IER1, bit10) RTOS interrupt.
HWI_SINT27 through HWI_SINT31	Non-maskable software interrupt.
HWI_L2_INT0 through HWI_L2_INT31	Level 2 interrupts (OMAP 2320/2420 only)
HWI_L2_INT32 through HWI_L2_INT63	Level 2 interrupts (OMAP 2320 only)

**HWI\_disable***Disable hardware interrupts***C Interface****Syntax**                    `oldST1 = HWI_disable();`**Parameters**                `Void`**Return Value**              `Uns oldST1;`**Reentrant**                    `yes`**Description**

HWI\_disable disables hardware interrupts by setting the `intm` bit in the status register. Call HWI\_disable before a portion of a function that needs to run without interruption. When critical processing is complete, call HWI\_restore or HWI\_enable to reenale hardware interrupts.

Interrupts that occur while interrupts are disabled are postponed until interrupts are reenaled. However, if the same type of interrupt occurs several times while interrupts are disabled, the interrupt's function is executed only once when interrupts are reenaled.

A context switch can occur when calling HWI\_enable or HWI\_restore if an enabled interrupt occurred while interrupts are disabled.

HWI\_disable may be called from `main()`. However, since HWI interrupts are already disabled in `main()`, such a call has no effect.

**Example**

```
old = HWI_disable();
    'do some critical operation'
HWI_restore(old);
```

**See Also**

HWI\_enable  
HWI\_restore  
SWI\_disable  
SWI\_enable

**HWI\_dispatchPlug***Plug the HWI dispatcher***C Interface**

<b>Syntax</b>	HWI_dispatchPlug(vecid, fxn, attrs);									
<b>Parameters</b>	<table> <tr> <td>Int</td> <td>vecid;</td> <td>/* interrupt id */</td> </tr> <tr> <td>Fxn</td> <td>fxn;</td> <td>/* pointer to HWI function */</td> </tr> <tr> <td>HWI_Attrs</td> <td>*attrs</td> <td>/*pointer to HWI dispatcher attributes */</td> </tr> </table>	Int	vecid;	/* interrupt id */	Fxn	fxn;	/* pointer to HWI function */	HWI_Attrs	*attrs	/*pointer to HWI dispatcher attributes */
Int	vecid;	/* interrupt id */								
Fxn	fxn;	/* pointer to HWI function */								
HWI_Attrs	*attrs	/*pointer to HWI dispatcher attributes */								
<b>Return Value</b>	Void									
<b>Reentrant</b>	yes									

**Description**

HWI\_dispatchPlug fills the HWI dispatcher table with the function specified by the fxn parameter and the attributes specified by the attrs parameter.

HWI\_dispatchPlug also writes four instruction words into the Interrupt-Vector Table, at the address corresponding to vecid. The instructions written in the Interrupt-Vector Table create a call to the HWI dispatcher.

HWI\_dispatchPlug does not enable the interrupt. Use C54\_enableIMR or C55\_enableIER0/C55\_enableIER1 to enable specific interrupts.

If attrs is NULL, the HWI's dispatcher properties are assigned a default set of attributes. Otherwise, the HWI's dispatcher properties are specified by a structure of type HWI\_Attrs defined as follows.

```
typedef struct HWI_Attrs {
    Uns    ier0mask;    /* IER0 bitmask */
    Uns    ier1mask;    /* IER1 bitmask */
    Arg    arg;         /* fxn arg (default = 0) */
    LgUns  mirmask;    /* OMAP 2320/2420 only */
    LgUns  mir1mask;    /* OMAP 2320 only */
} HWI_Attrs;
```

The ier0mask is a bitmask that specifies the ier0 interrupts to mask while executing the HWI. The bit positions in ier0mask correspond to those of IER0.

The ier1mask is a bitmask that specifies the ier1 interrupts to mask while executing the HWI. The bit positions in ier1mask correspond to those of IER1. If ier0mask and ier1mask are both 1, then a mask to disable "self" is created.

The mirmask is a bitmask that specifies which level 2 interrupts to mask while executing the HWI. This field contains a 32-bit mask in which each bit corresponds to level 2 interrupts 0-31. The default value for each interrupt is to mask only the current level 2 interrupt. (OMAP 2320/2420 only)

The mir1mask is a bitmask that specifies which level 2 interrupts to mask while executing the HWI. This field contains a 32-bit mask in which each bit corresponds to level 2 interrupts 32-63. The default value for each interrupt is to mask only the current level 2 interrupt. (OMAP 2320 only)

The default values are defined as follows:

```
HWI_Attrs HWI_ATTRS = {
    1,          /* IER0 mask (1 => self) */
    1,          /* IER1 mask (1 => self) */
    0           /* argument to ISR */
};
```

The arg element is a generic argument that is passed to the plugged function as its only parameter. The default value is 0.

## Constraints and Calling Context

- ❑ vecid must be a valid interrupt ID in the range of 0-31 (0-95 for OMAP 2320, 0-63 for OMAP 2420).

## See Also

HWI\_enable  
 HWI\_restore  
 SWI\_disable  
 SWI\_enable

**HWI\_enable***Enable interrupts***C Interface****Syntax** HWI\_enable();**Parameters** Void**Return Value** Void**Reentrant** yes**Description** HWI\_enable enables hardware interrupts by clearing the intrm bit in the status register.

Hardware interrupts are enabled unless a call to HWI\_disable disables them. DSP/BIOS enables hardware interrupts after the program's main() function runs. Your main() function can enable individual interrupt mask bits, but it should not call HWI\_enable to globally enable interrupts.

Interrupts that occur while interrupts are disabled are postponed until interrupts are reenabled. However, if the same type of interrupt occurs several times while interrupts are disabled, the interrupt's function is executed only once when interrupts are reenabled. A context switch can occur when calling HWI\_enable/HWI\_restore if an enabled interrupt occurs while interrupts are disabled.

Any call to HWI\_enable enables interrupts, even if HWI\_disable has been called several times.

**Constraints and Calling Context**

- ❑ HWI\_enable cannot be called from the program's main() function.

**Example**

```
HWI_disable();
"critical processing takes place"
HWI_enable();
"non-critical processing"
```

**See Also**

HWI\_disable  
HWI\_restore  
SWI\_disable  
SWI\_enable

**HWI\_enter***Hardware ISR prolog***C Interface****Syntax** none**Parameters** none**Return Value** none**Assembly Interface**

**Syntax** HWI\_enter C55\_AR\_DR\_X\_MASK, C55\_ACC\_X\_MASK, \  
 C55\_MISC1\_X\_MASK, C55\_MISC2\_X\_MASK, C55\_MISC3\_X\_MASK, \  
 IER0DISABLEMASK, IER1DISABLEMASK

**OMAP 2320 only:**

HWI\_enter C55\_AR\_DR\_X\_MASK, C55\_ACC\_X\_MASK, \  
 C55\_MISC1\_X\_MASK, C55\_MISC2\_X\_MASK, C55\_MISC3\_X\_MASK, \  
 IER0DISABLEMASK, IER1DISABLEMASK, MIRDISABLEMASK, \  
 MIR1DISABLEMASK

**OMAP 2420 only:**

HWI\_enter C55\_AR\_DR\_X\_MASK, C55\_ACC\_X\_MASK, \  
 C55\_MISC1\_X\_MASK, C55\_MISC2\_X\_MASK, C55\_MISC3\_X\_MASK, \  
 IER0DISABLEMASK, IER1DISABLEMASK, MIRDISABLEMASK

**Preconditions** intm = 1

**Postconditions** intm=0, braf=0, cpl=1, m40=0, satd=0, sxmd=0, c16=0, frct=0, c54cm=0, arms=1, rdm=0, cdplc=0, ar[0...7]lc=0, sata=0, smul=0, sst=0  
 Both the user stack pointer (XSP) and the system stack pointer (XSSP) are left aligned to even address boundaries in compliance with standard C conventions.

**Modifies** xar0, xar1, ac0g, ac0h, ier0, ier1, ac1, ac2**Reentrant** yes

**Description** HWI\_enter is an API (assembly macro) used to save the appropriate context for a DSP/BIOS hardware interrupt (HWI).

The arguments to HWI\_enter are bitmasks that define the set of registers to be saved and bitmasks that define which interrupts are to be masked during the execution of the HWI.

HWI\_enter is used by HWIs that are user-dispatched, as opposed to HWIs that are handled by the HWI dispatcher. HWI\_enter must not be issued by HWIs that are handled by the HWI dispatcher.

If the HWI dispatcher is not used by an HWI object, HWI\_enter must be used in the HWI before any DSP/BIOS API calls that could trigger other DSP/BIOS objects, such as posting a SWI or semaphore. HWI\_enter is used in tandem with HWI\_exit to ensure that the DSP/BIOS SWI or TSK manager is called at the appropriate time. Normally, HWI\_enter and HWI\_exit must surround all statements in any DSP/BIOS assembly language HWIs that call C functions.

The following list shows the mask families available for the HWI\_enter and HWI\_exit API syntax. For each family, several masks are defined where the "X" indicates which registers are saved. (That is, "X" can be SAVE\_BY\_CALLER, SAVE\_BY\_CALLEE, or BIOS\_CONTEXT). For example, the "C55\_ACC\_SAVE\_BY\_CALLEE\_MASK" is in the C55\_ACC\_X\_MASK family. See the c55.h55 file for a complete list of masks and the example later in this section for a clearer understanding. Typically "SAVE\_BY\_CALLER" is used for ISRs written in C.

- ❑ **C55\_AR\_DR\_X\_MASK.** Mask of registers belonging to ar0-7, t0-3, sp-ssp
- ❑ **C55\_ACC\_X\_MASK.** Mask of registers belonging to ac0-3
- ❑ **C55\_MISC1\_X\_MASK.** Mask of registers ier0, ifr0, dbier0, ier1, ifr, dbier1, st0, st1, st2, st3, trn0, bk03, brc0
- ❑ **C55\_MISC2\_X\_MASK.** Mask of registers dp, cdp, mdp, mdp05, mdp67, pdp, bk47, bkc, bof01, bof23, bof45, bof67, bofc, ivpd, ivph, trn1
- ❑ **C55\_MISC3\_X\_MASK.** Mask of registers brc1, csr, rsa0\_h\_addr, rsa0, rea0\_h\_addr, rea0, rsa1\_h\_addr, rsa1, rea1\_h\_addr, rea1, rptc
- ❑ **IER0DISABLEMASK / IER0RESTOREMASK.** The IER0 and IER1 masks define which interrupts are to be masked while the HWI is executing and restored at the end of execution. These arguments mask ier0 bits to turn off (and to restore).
- ❑ **IER1DISABLEMASK / IER1RESTOREMASK.** These arguments mask ier1 bits to turn off (and to restore).
- ❑ **MIRDISABLEMASK / MIRRESTOREMASK.** These arguments mask level 2 interrupt bits (0-31) to turn off (and to restore). (OMAP 2320/2420 only)
- ❑ **MIR1DISABLEMASK / MIR1RESTOREMASK.** These arguments mask level 2 interrupt bits (32-63) to turn off (and to restore). (OMAP 2320 only)



See c55.h55 for constants defined for working with these masks. If your HWI is coded in C, it is recommended that you use the SAVE\_BY\_CALLER masks provided in c55.h55.

---

**Note:**

The C55\_saveCcontext, C55\_restoreCcontext C55\_saveBiosContext and C55\_restoreBiosContext macros preserve processor register context per C and DSP/BIOS requirements, respectively.

---

## Constraints and Calling Context

- ❑ This API should not be used in the NMI HWI function.
- ❑ This API must not be called if the HWI object that runs this function uses the HWI dispatcher.
- ❑ This API cannot be called from the program's main() function.
- ❑ This API cannot be called from a SWI, TSK, or IDL function.
- ❑ This API cannot be called from a CLK function.
- ❑ Unless the HWI dispatcher is used, this API must be called within any hardware interrupt function (except NMI's HWI function) before the first operation in an HWI that uses any DSP/BIOS API calls that might post or affect a SWI or semaphore. Such functions must be written in assembly language. Alternatively, the HWI dispatcher can be used instead of this API, allowing the function to be written completely in C and allowing you to reduce code size.
- ❑ If an interrupt function calls HWI\_enter, it must end by calling HWI\_exit.
- ❑ Do not use the interrupt keyword or the INTERRUPT pragma in C functions that run in the context of an HWI.
- ❑

## Examples

### Example #1:

Calling a C function from within an HWI\_enter/HWI\_exit block. Specify all registers in the C convention class, save-by-caller. Use the appropriate register save masks with the HWI\_enter macro. See the c55.h55 file for definitions of the masks used in this example.

```
HWI_enter C55_AR_DR_SAVE_BY_CALLER_MASK, \
C55_ACC_SAVE_BY_CALLER_MASK,          \
C55_MISC1_SAVE_BY_CALLER_MASK,        \
C55_MISC2_SAVE_BY_CALLER_MASK,        \
C55_MISC3_SAVE_BY_CALLER_MASK,        \
user_ier0_mask, user_ier1_mask
```

The HWI\_enter macro:

- ❑ preserves the specified set of registers that are being declared as trashable by the called function
- ❑ places the processor status register bit settings as required by C compiler conventions
- ❑ aligns stack pointers to even address boundaries, as well as remembering any such adjustments made to SP and SSP registers
- ❑ masks those interrupts defined by the interrupt masks
- ❑ enables interrupts

The user's C function must have a leading underscore as in this example:

```
call _myCfunction;
```

When exiting the hardware interrupt, you need to call HWI\_exit with the following macro:

```
HWI_exit C55_AR_DR_SAVE_BY_CALLER_MASK,  \
C55_ACC_SAVE_BY_CALLER_MASK,           \
C55_MISC1_SAVE_BY_CALLER_MASK,        \
C55_MISC2_SAVE_BY_CALLER_MASK,        \
C55_MISC3_SAVE_BY_CALLER_MASK,        \
user_ier0_mask, user_ier1_mask
```

The HWI\_exit macro restores the CPU state that was originally set by the HWI\_enter macro. It alerts the SWI scheduler to attend to any kernel scheduling activity that is required.

## See Also

HWI\_exit

**HWI\_exit***Hardware ISR epilog***C Interface**

<b>Syntax</b>	none
<b>Parameters</b>	none
<b>Return Value</b>	none

**Assembly Interface**

**Syntax** HWI\_exit C55\_AR\_DR\_X\_MASK, C55\_ACC\_X\_MASK, \  
C55\_MISC1\_X\_MASK, C55\_MISC2\_X\_MASK, \  
C55\_MISC3\_X\_MASK, \  
IER0RESTOREMASK, IER1RESTOREMASK

**OMAP 2320 only:**

HWI\_enter C55\_AR\_DR\_X\_MASK, C55\_ACC\_X\_MASK, \  
C55\_MISC1\_X\_MASK, C55\_MISC2\_X\_MASK, C55\_MISC3\_X\_MASK, \  
IER0RESTOREMASK, IER1RESTOREMASK, MIRRESTOREMASK, \  
MIR1RESTOREMASK

**OMAP 2420 only:**

HWI\_enter C55\_AR\_DR\_X\_MASK, C55\_ACC\_X\_MASK, \  
C55\_MISC1\_X\_MASK, C55\_MISC2\_X\_MASK, C55\_MISC3\_X\_MASK, \  
IER0RESTOREMASK, IER1RESTOREMASK, MIRRESTOREMASK

**Preconditions** none

**Postconditions** intm=0

**Modifies** Restores all registers saved with the HWI\_enter mask

**Reentrant** yes

**Description** HWI\_exit is an API (assembly macro) which is used to restore the context that existed before a DSP/BIOS hardware interrupt (HWI) was invoked.

HWI\_exit is used by HWIs that are user-dispatched, as opposed to HWIs that are handled by the HWI dispatcher. HWI\_exit must not be issued by HWIs that are handled by the HWI dispatcher.

If the HWI dispatcher is not used by an HWI object, HWI\_exit must be the last statement in an HWI that uses DSP/BIOS API calls which could trigger other DSP/BIOS objects, such as posting a SWI or semaphore.

HWI\_exit restores the registers specified by C55\_AR\_DR\_X\_MASK, C55\_ACC\_X\_MASK, C55\_MISC1\_X\_MASK, C55\_MISC2\_X\_MASK, and C55\_MISC3\_X\_MASK. These masks are used to specify the set of registers that were saved by HWI\_enter.

HWI\_enter and HWI\_exit must surround all statements in any DSP/BIOS assembly language HWIs that call C functions only for HWIs that are not dispatched by the HWI dispatcher.

HWI\_exit calls the DSP/BIOS SWI manager if DSP/BIOS itself is not in the middle of updating critical data structures, or if no currently interrupted HWI is also in a HWI\_enter/HWI\_exit region. The DSP/BIOS SWI manager services all pending SWI handlers (functions).

Of the interrupts in IER0[IER1]RESTOREMASK, HWI\_exit only restores those that were disabled upon entering the HWI. HWI\_exit does not affect the status of interrupt bits that are not in IER0[IER1]RESTOREMASK.

- If upon exiting an HWI you *do not* want to restore an interrupt that was disabled with HWI\_enter, do not set that interrupt bit in the IER0[IER1]RESTOREMASK in HWI\_exit.
- If upon exiting an HWI you *do* want to enable an interrupt that was disabled upon entering the HWI, set the corresponding bit in IER0[IER1]RESTOREMASK before calling HWI\_exit. (Setting bits in IER0[IER1]RESTOREMASK passed to HWI\_exit does not enable the corresponding interrupts if they were not originally disabled by the HWI\_enter macro.)

This same logic applies to the OMAP 2320/2420 MIRRESTOREMASK argument and the OMAP 2320 MIR1RESTOREMASK.

For a list of parameters and constants available for use with HWI\_exit, see the description of HWI\_enter. In addition, see the c55.h55 file.

## Constraints and Calling Context

- This API should not be used for the NMI HWI function.
- This API must not be called if the HWI object that runs the function uses the HWI dispatcher.
- If the HWI dispatcher is not used, this API must be the last operation in an HWI that uses any DSP/BIOS API calls that might post or affect a SWI or semaphore. The HWI dispatcher can be used instead of this API, allowing the function to be written completely in C and allowing you to reduce code size.
- For 'C55x, the C55\_AR\_DR\_X\_MASK, C55\_ACC\_X\_MASK, C55\_MISC1\_X\_MASK, C55\_MISC2\_X\_MASK, and C55\_MISC3\_X\_MASK parameters must match the corresponding parameters used for HWI\_enter.

- ❑ This API cannot be called from the program's main() function.
- ❑ This API cannot be called from a SWI, TSK, or IDL function.
- ❑ This API cannot be called from a CLK function.

## Examples

Example #1:

Calling a C function from within an HWI\_enter/HWI\_exit:

Specify all registers in the C convention class, save-by-caller. Use the appropriate register save masks with the HWI\_enter macro:

```
HWI_enter C55_AR_DR_SAVE_BY_CALLER_MASK, \
C55_ACC_SAVE_BY_CALLER_MASK,           \
C55_MISC1_SAVE_BY_CALLER_MASK,        \
C55_MISC2_SAVE_BY_CALLER_MASK,        \
C55_MISC3_SAVE_BY_CALLER_MASK,        \
user_ier0_mask, user_ier1_mask
```

The HWI\_enter macro:

- ❑ preserves the specified set of registers that are being declared as trashable by the called function
- ❑ places the processor status register bit settings as required by C compiler conventions
- ❑ aligns stack pointers to even address boundaries, as well as remembering any such adjustments made to SP and SSP registers

The user's C function must have a leading underscore as in this example:

```
call _myCfunction;
```

When exiting the hardware interrupt, you need to call HWI\_exit with the following macro:

```
HWI_exit C55_AR_DR_SAVE_BY_CALLER_MASK, \
C55_ACC_SAVE_BY_CALLER_MASK,           \
C55_MISC1_SAVE_BY_CALLER_MASK,        \
C55_MISC2_SAVE_BY_CALLER_MASK,        \
C55_MISC3_SAVE_BY_CALLER_MASK,        \
user_ier0_mask, user_ier1_mask
```

The HWI\_exit macro restores the CPU state that was originally set by the HWI\_enter macro. It alerts the SWI scheduler to attend to any kernel scheduling activity that is required.

## See Also

HWI\_enter

**HWI\_isHWI**

*Check to see if called in the context of an HWI*

**C Interface**

**Syntax**                    `result = HWI_isHWI(Void);`

**Parameters**                `Void`

**Return Value**              `Bool            result;    /* TRUE if in HWI context, FALSE otherwise */`

**Reentrant**                    `yes`

**Description**                This macro returns TRUE when it is called within the context of an HWI or CLK function. This macro returns FALSE in all other contexts.

In previous versions of DSP/BIOS, calling HWI\_isHWI() from main() resulted in TRUE. This is no longer the case; main() is identified as part of the TSK context.

**See Also**                    SWI\_isSWI  
                                  TSK\_isTSK

**HWI\_restore***Restore global interrupt enable state***C Interface****Syntax** HWI\_restore(oldST1);**Parameters** Uns oldST1;**Returns** Void**Reentrant** yes**Description**

HWI\_restore sets the intrm bit in the st1 register using bit 11 of the oldst1 parameter. If bit 11 is 1, the intrm bit is not modified. If bit 11 is 0, the intrm bit is set to 0, which enables interrupts.

When you call HWI\_disable, the previous contents of the st1 register are returned. You can use this returned value with HWI\_restore.

A context switch may occur when calling HWI\_restore if HWI\_restore reenables interrupts and if a higher-priority HWI occurred while interrupts were disabled.

HWI\_restore may be called from main(). However, since HWI\_enable cannot be called from main(), interrupts are always disabled in main(), and a call to HWI\_restore has no effect.

**Constraints and Calling Context**

- ❑ HWI\_restore must be called with interrupts disabled. The parameter passed to HWI\_restore must be the value returned by HWI\_disable.

**Example**

```
oldST1 = HWI_disable(); /* disable interrupts */
    'do some critical operation'
HWI_restore(oldST1);
    /* re-enable interrupts if they
       were enabled at the start of the
       critical section */
```

**See Also**

HWI\_enable  
HWI\_disable

## 2.11 IDL Module

The IDL module is the idle thread manager.

### Functions

- ❑ IDL\_run. Make one pass through idle functions.

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the IDL Manager Properties and IDL Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")
AUTOCALCULATE	Bool	true
LOOPINSTCOUNT	Int32	1000

#### Instance Configuration Parameters

Name	Type	Default
comment	String	"<add comments here>"
fxn	Extern	prog.extern("FXN_F_nop")
calibration	Bool	true
order	Int16	0

### Description

The IDL module manages the lowest-level threads in the application. In addition to user-created functions, the IDL module executes DSP/BIOS functions that handle host communication and CPU load calculation.

There are four kinds of threads that can be executed by DSP/BIOS programs: hardware interrupts (HWI Module), software interrupts (SWI Module), tasks (TSK Module), and background threads (IDL module). Background threads have the lowest priority, and execute only if no hardware interrupts, software interrupts, or tasks need to run.

An application's main() function must return before any DSP/BIOS threads can run. After the return, DSP/BIOS runs the idle loop. Once an application is in this loop, HWI hardware interrupts, SWI software interrupts, PRD periodic functions, TSK task functions, and IDL background threads are all enabled.

The functions for IDL objects registered with the configuration are run in sequence each time the idle loop runs. IDL functions are called from the



IDL context. IDL functions can be written in C or assembly and must follow the C calling conventions described in the compiler manual.

When RTA is enabled (see page 2–111), an application contains an IDL\_cpuLoad object, which runs a function that provides data about the CPU utilization of the application. In addition, the LNK\_dataPump function handles host I/O in the background, and the RTA\_dispatch function handles run-time analysis communication.

The IDL Function Manager allows you to insert additional functions that are executed in a loop whenever no other processing (such as HWIs or higher-priority tasks) is required.

## IDL Manager Properties

The following global properties can be set for the IDL module in the IDL Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- Object Memory.** The memory segment that contains the IDL objects.

Tconf Name: OBJMEMSEG Type: Reference

Example: `bios.IDL.OBJMEMSEG = prog.get("myMEM");`

- Auto calculate idle loop instruction count.** When this property is set to true, the program runs the IDL functions one or more times at system startup to get an approximate value for the idle loop instruction count. This value, saved in the global variable CLK\_D\_idletime, is read by the host and used in the CPU load calculation. By default, the instruction count includes all IDL functions, not just LNK\_dataPump, RTA\_dispatcher, and IDL\_cpuLoad. You can remove an IDL function from the calculation by setting the "Include in CPU load calibration" property for an IDL object to false.

Remember that functions included in the calibration are run before the main() function runs. These functions should not access data structures that are not initialized before the main() function runs. In particular, functions that perform any of the following actions should not be included in the idle loop calibration:

- enabling hardware interrupts or the SWI or TSK schedulers
- using CLK APIs to get the time
- accessing PIP objects
- blocking tasks
- creating dynamic objects

Tconf Name: AUTOCALCULATE Type: Bool

Example: `bios.IDL.AUTOCALCULATE = true;`

- ❑ **Idle Loop Instruction Count.** This is the number of instruction cycles required to perform the IDL loop and the default IDL functions (LNK\_dataPump, RTA\_dispatcher, and IDL\_cpuLoad) that communicate with the host. Since these functions are performed whenever no other processing is needed, background processing is subtracted from the CPU load before it is displayed.

Tconf Name: LOOPINSTCOUNT Type: Int32

Example: `bios.IDL.LOOPINSTCOUNT = 1000;`

## IDL Object Properties

Each idle function runs to completion before another idle function can run. It is important, therefore, to ensure that each idle function completes (that is, returns) in a timely manner.

To create an IDL object in a configuration script, use the following syntax. The Tconf examples assume the object is created as shown here.

```
var myIdl = bios.IDL.create("myIdl");
```

The following properties can be set for an IDL object:

- ❑ **comment.** Type a comment to identify this IDL object.

Tconf Name: comment Type: String

Example: `myIdl.comment = "IDL function";`

- ❑ **function.** The function to execute. If this function is written in C and you use the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. (The DSP/BIOS Configuration Tool generates assembly code, which must use leading underscores when referencing C functions or labels.) If you use Tconf, do not add an underscore before the function name; Tconf adds the underscore to call a C function from assembly internally.

Tconf Name: fxn Type: Extern

Example: `myIdl.fxn = prog.extern("myIDL");`

- ❑ **Include in CPU load calibration.** You can remove an individual IDL function from the CPU load calculation by setting this property to false. The CPU load calibration is performed only if the "Auto calculate idle loop instruction count" property is true in the IDL Manager Properties. You should remove a function from the calculation if it blocks or depends on variables or structures that are not initialized until the main() function runs.

Tconf Name: calibration Type: Bool

Example: `myIdl.calibration = true;`

- ❑ **order.** Set this property for all IDL objects so that the numbers match the sequence in which IDL functions should be executed.

Tconf Name: order Type: Int16

Example: `myIdl.order = 2;`

**IDL\_run***Make one pass through idle functions***C Interface****Syntax** IDL\_run();**Parameters** Void**Return Value** Void**Description**

IDL\_run makes one pass through the list of configured IDL objects, calling one function after the next. IDL\_run returns after all IDL functions have been executed one time. IDL\_run is not used by most DSP/BIOS applications since the IDL functions are executed in a loop when the application returns from main. IDL\_run is provided to allow easy integration of the real-time analysis features of DSP/BIOS (for example, LOG and STS) into existing applications.

IDL\_run must be called to transfer the real-time analysis data to and from the host computer. Though not required, this is usually done during idle time when no HWI or SWI threads are running.

**Note:**

BIOS\_init and BIOS\_start must be called before IDL\_run to ensure that DSP/BIOS has been initialized. For example, the DSP/BIOS boot file contains the following system calls around the call to main:

```
BIOS_init(); /* initialize DSP/BIOS */
main();
BIOS_start() /* start DSP/BIOS */
IDL_loop(); /* call IDL_run in an infinite loop */
```

**Constraints and Calling Context**

- ❑ IDL\_run cannot be called by an HWI or SWI function.

## 2.12 LCK Module

The LCK module is the resource lock manager.

### Functions

- ❑ LCK\_create. Create a resource lock
- ❑ LCK\_delete. Delete a resource lock
- ❑ LCK\_pend. Acquire ownership of a resource lock
- ❑ LCK\_post. Relinquish ownership of a resource lock

### Constants, Types, and Structures

```
typedef struct LCK_Obj *LCK_Handle; /* resource handle */

/* lock object */
typedef struct LCK_Attrs LCK_Attrs;

struct LCK_Attrs {
    Int dummy;
};

LCK_Attrs LCK_ATTRS = {0}; /* default attribute values */
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the LCK Manager Properties and LCK Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameter.

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

### Description

The lock module makes available a set of functions that manipulate lock objects accessed through handles of type LCK\_Handle. Each lock implicitly corresponds to a shared global resource, and is used to arbitrate access to this resource among several competing tasks.

The LCK module contains a pair of functions for acquiring and relinquishing ownership of resource locks on a per-task basis. These functions are used to bracket sections of code requiring mutually exclusive access to a particular resource.

LCK lock objects are semaphores that potentially cause the current task to suspend execution when acquiring a lock.

### LCK Manager Properties

The following global property can be set for the LCK module on the LCK Manager Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script:



**LCK\_create***Create a resource lock***C Interface**

**Syntax**                   lock = LCK\_create(attrs);

**Parameters**           LCK\_Attrs    attrs;     /\* pointer to lock attributes \*/

**Return Value**        LCK\_Handle lock;     /\* handle for new lock object \*/

**Description**

LCK\_create creates a new lock object and returns its handle. The lock has no current owner and its corresponding resource is available for acquisition through LCK\_pend.

If attrs is NULL, the new lock is assigned a default set of attributes. Otherwise the lock's attributes are specified through a structure of type LCK\_Attrs.

**Note:**

At present, no attributes are supported for lock objects.

All default attribute values are contained in the constant LCK\_ATTRS, which can be assigned to a variable of type LCK\_Attrs prior to calling LCK\_create.

LCK\_create calls MEM\_alloc to dynamically create the object's data structure. MEM\_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2–205.

**Constraints and Calling Context**

- ❑ LCK\_create cannot be called from a SWI or HWI.
- ❑ You can reduce the size of your application program by creating objects with Tconf rather than using the XXX\_create functions.

**See Also**

LCK\_delete  
LCK\_pend  
LCK\_post

**LCK\_delete***Delete a resource lock***C Interface**

<b>Syntax</b>	LCK_delete(lock);
<b>Parameters</b>	LCK_Handle lock;     /* lock handle */
<b>Return Value</b>	Void

**Description**

LCK\_delete uses MEM\_free to free the lock referenced by lock.

LCK\_delete calls MEM\_free to delete the LCK object. MEM\_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- ❑ LCK\_delete cannot be called from a SWI or HWI.
- ❑ No task should be awaiting ownership of the lock.
- ❑ No check is performed to prevent LCK\_delete from being used on a statically-created object. If a program attempts to delete a lock object that was created using Tconf, SYS\_error is called.

**See Also**

LCK\_create  
LCK\_pend  
LCK\_post

**LCK\_pend***Acquire ownership of a resource lock***C Interface**

**Syntax**                    status = LCK\_pend(lock, timeout);

**Parameters**                LCK\_Handle lock;        /\* lock handle \*/  
                               Uns                    timeout;        /\* return after this many system clock ticks \*/

**Return Value**            Bool                status;        /\* TRUE if successful, FALSE if timeout \*/

**Description**

LCK\_pend acquires ownership of lock, which grants the current task exclusive access to the corresponding resource. If lock is already owned by another task, LCK\_pend suspends execution of the current task until the resource becomes available.

The task owning lock can call LCK\_pend any number of times without risk of blocking, although relinquishing ownership of the lock requires a balancing number of calls to LCK\_post.

LCK\_pend results in a context switch if this LCK timeout is greater than 0 and the lock is already held by another thread.

LCK\_pend returns TRUE if it successfully acquires ownership of lock, returns FALSE if a timeout occurs before it can acquire ownership. LCK\_pend returns FALSE if it is called from the context of a SWI or HWI, even if the timeout is zero.

**Note: RTS Functions Callable from TSK Threads Only**

Many run-time support (RTS) functions use lock and unlock functions to prevent reentrancy. However, DSP/BIOS SWI and HWI threads cannot call LCK\_pend and LCK\_post. As a result, RTS functions that call LCK\_pend or LCK\_post *must not be called in the context of a SWI or HWI thread.*

To determine whether a particular RTS function uses LCK\_pend or LCK\_post, refer to the source code for that function shipped with Code Composer Studio. The following table lists some RTS functions that call LCK\_pend and LCK\_post in certain versions of Code Composer Studio:

fprintf	printf	vfprintf	sprintf
vprintf	vsprintf	clock	strftime
minit	malloc	realloc	free
calloc	rand	srand	getenv



The C++ new operator calls malloc, which in turn calls LCK\_pend. As a result, the new operator cannot be used in the context of a SWI or HWI thread.

**Constraints and  
Calling Context**

- ❑ The lock must be a handle for a resource lock object created through a prior call to LCK\_create.
- ❑ LCK\_pend should not be called from a SWI or HWI thread.
- ❑ LCK\_pend should not be called from main().

**See Also**

LCK\_create  
LCK\_delete  
LCK\_post

**LCK\_post***Relinquish ownership of a resource LCK***C Interface**

<b>Syntax</b>	LCK_post(lock);
<b>Parameters</b>	LCK_Handle lock;     /* lock handle */
<b>Return Value</b>	Void

**Description**

LCK\_post relinquishes ownership of lock, and resumes execution of the first task (if any) awaiting availability of the corresponding resource. If the current task calls LCK\_pend more than once with lock, ownership remains with the current task until LCK\_post is called an equal number of times.

LCK\_post results in a context switch if a higher priority thread is currently pending on the lock.

**Constraints and Calling Context**

- ❑ lock must be a handle for a resource lock object created through a prior call to LCK\_create.
- ❑ LCK\_post should not be called from a SWI or HWI thread.
- ❑ LCK\_post should not be called from main().

**See Also**

LCK\_create  
LCK\_delete  
LCK\_pend

## 2.13 LOG Module

The LOG module captures events in real time.

### Functions

- LOG\_disable. Disable the system log.
- LOG\_enable. Enable the system log.
- LOG\_error. Write a user error event to the system log.
- LOG\_event. Append unformatted message to message log.
- LOG\_message. Write a user message event to the system log.
- LOG\_printf. Append formatted message to message log.
- LOG\_reset. Reset the system log.

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the LOG Manager Properties and LOG Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

#### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
bufSeg	Reference	prog.get("DARAM")
bufLen	EnumInt	64 (0, 8, 16, 32, 64, ..., 32768)
logType	EnumString	"circular" ("fixed)
dataType	EnumString	"printf" ("raw data")
format	String	"0x%x, 0x%x, 0x%x"

### Description

The Event Log is used to capture events in real time while the target program executes. You can use the system log, or create user-defined logs. If the logtype is circular, the log buffer of size buflen contains the last buflen elements. If the logtype is fixed, the log buffer contains the first buflen elements.

The system log stores messages about system events for the types of log tracing you have enabled. See the TRC Module, page 2–467, for a list of events that can be traced in the system log.



- ❑ **bufseg.** The name of a memory segment to contain the log buffer.

Tconf Name: bufSeg Type: Reference

Example: `myLog.bufSeg = prog.get("myMEM");`
- ❑ **buflen.** The length of the log buffer (in words).

Tconf Name: bufLen Type: EnumInt

Options: 0, 8, 16, 32, 64, ..., 32768

Example: `myLog.bufLen = 64;`
- ❑ **logtype.** The type of the log: circular or fixed. Events added to a full circular log overwrite the oldest event in the buffer, whereas events added to a full fixed log are dropped.

  - **Fixed.** The log stores the first messages it receives and stops accepting messages when its message buffer is full.
  - **Circular.** The log automatically overwrites earlier messages when its buffer is full. As a result, a circular log stores the last events that occur.

Tconf Name: logType Type: EnumString

Options: "circular", "fixed"

Example: `myLog.logType = "circular";`
- ❑ **datatype.** Choose printf if you use LOG\_printf to write to this log and provide a format string.

Choose raw data if you want to use LOG\_event to write to this log and have the Event Log apply a printf-style format string to all records in the log.

Tconf Name: dataType Type: EnumString

Options: "printf", "raw data"

Example: `myLog.dataType = "printf";`
- ❑ **format.** If you choose raw data as the datatype, type a printf-style format string for this property. Provide up to three (3) conversion characters (such as %d) to format words two, three, and four in all records in the log. Do not put quotes around the format string. The format string can use %d, %u, %x, %o, %s, %r, and %p conversion characters; it cannot use other types of conversion characters. See LOG\_printf, page 2–191, and LOG\_event, page 2–189, for information about the structure of a log record.

Tconf Name: format Type: String

Example: `myLog.format = "0x%x, 0x%x, 0x%x";`

**LOG\_disable***Disable a message log***C Interface****Syntax**                    LOG\_disable(log);**Parameters**                LOG\_Handle log;            /\* log object handle \*/**Return Value**                Void**Reentrant**                    no**Description**                LOG\_disable disables the logging mechanism and prevents the log buffer from being modified.**Example**                      LOG\_disable(&trace);**See Also**                    LOG\_enable  
LOG\_reset

**LOG\_enable***Enable a message log***C Interface**

<b>Syntax</b>	LOG_enable(log);
<b>Parameters</b>	LOG_Handle log;      /* log object handle */
<b>Return Value</b>	Void
<b>Reentrant</b>	no
<b>Description</b>	LOG_enable enables the logging mechanism and allows the log buffer to be modified.
<b>Example</b>	LOG_enable(&trace);
<b>See Also</b>	LOG_disable LOG_reset

**LOG\_error***Write an error message to the system log***C Interface**

**Syntax** `LOG_error(format, arg0);`

**Parameters**      String      format;      /\* printf-style format string \*/  
                  Arg          arg0;      /\* copied to second word of log record \*/

**Return Value**      Void

**Reentrant**          yes

**Description**        LOG\_error writes a program-supplied error message to the system log, which is defined in the default configuration by the LOG\_system object. LOG\_error is not affected by any TRC bits; an error event is always written to the system log.

The format argument can contain any of the conversion characters supported for LOG\_printf. See LOG\_printf for details.

**Example**

```
Void UTL_doError(String s, Int errno)
{
    LOG_error("SYS_error called: error id = 0x%x", errno);
    LOG_error("SYS_error called: string = '%s'", s);
}
```

**See Also**

LOG\_event  
LOG\_message  
LOG\_printf  
TRC\_disable  
TRC\_enable



**LOG\_event***Append an unformatted message to a message log***C Interface**

**Syntax** LOG\_event(log, arg0, arg1, arg2);

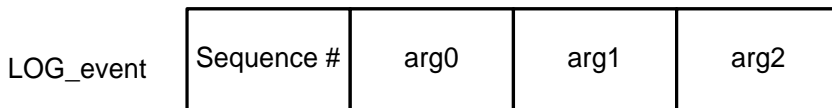
**Parameters**

LOG_Handle log;	/* log objecthandle */
Arg arg0;	/* copied to second word of log record */
Arg arg1;	/* copied to third word of log record */
Arg arg2;	/* copied to fourth word of log record */

**Return Value** Void

**Reentrant** yes

**Description** LOG\_event copies a sequence number and three arguments to the specified log buffer. Each log message uses four words (eight words for 'C55x large and huge models). The contents of the four words written by LOG\_event are shown here:



You can format the log by using LOG\_printf instead of LOG\_event.

If you want the Event Log to apply the same printf-style format string to all records in the log, use Tconf to choose raw data for the datatype property and type a format string for the format property (see "LOG Object Properties" on page 2-184).

If the logtype is circular, the log buffer of size buflen contains the last buflen elements. If the logtype is fixed, the log buffer contains the first buflen elements.

Any combination of threads can write to the same log. Internally, hardware interrupts are temporarily disabled during a call to LOG\_event. Log messages are never lost due to thread preemption.

**Example**

```
LOG_event(&trace, (Arg)value1, (Arg)value2,
         (Arg)CLK_gettime());
```

**See Also**

LOG\_error  
 LOG\_printf  
 TRC\_disable  
 TRC\_enable

**LOG\_message***Write a program-supplied message to the system log***C Interface****Syntax** LOG\_message(format, arg0);**Parameters** String format; /\* printf-style format string \*/  
Arg arg0; /\* copied to second word of log record \*/**Return Value** Void**Reentrant** yes**Description** LOG\_message writes a program-supplied message to the system log, provided that both the host and target trace bits are enabled.

The format argument passed to LOG\_message can contain any of the conversion characters supported for LOG\_printf. See LOG\_printf, page 2–191, for details.

**Example**

```
Void UTL_doMessage(String s, Int errno)
{
    LOG_message("SYS_error called: error id = 0x%x", errno);
    LOG_message("SYS_error called: string = '%s'", s);
}
```

**See Also**LOG\_error  
LOG\_event  
LOG\_printf  
TRC\_disable  
TRC\_enable

**LOG\_printf***Append a formatted message to a message log***C Interface**

<b>Syntax</b>	LOG_printf(log, format); or LOG_printf(log, format, arg0); or LOG_printf(log, format, arg0, arg1);
<b>Parameters</b>	LOG_Handle log; /* log object handle */ String format; /* printf format string */ Arg arg0; /* value for first format string token */ Arg arg1; /* value for second format string token */
<b>Return Value</b>	Void
<b>Reentrant</b>	yes

**Description**

As a convenience for C (as well as assembly language) programmers, the LOG module provides a variation of the ever-popular printf. LOG\_printf copies a sequence number, the format address, and two arguments to the specified log buffer.

To reduce execution time, log data is always formatted on the host. The format string is stored on the host and accessed by the Event Log.

The arguments passed to LOG\_printf must be integers, strings, or a pointer (if the special %r or %p conversion character is used).

Casting arg0 and arg1 using the Arg type causes an erroneous value to be printed. To print the value correctly, do not cast these parameters. This constraint applies even though the LOG\_printf function defines arg0 and arg1 as Arg type.

The format string can use any conversion character found in Table 2-4.

*Table 2-4. Conversion Characters for LOG\_printf*

<b>Conversion Character</b>	<b>Description</b>
%d	Signed integer
%u	Unsigned integer
%x	Unsigned hexadecimal integer
%o	Unsigned octal integer

Conversion Character	Description
%s	<p>Character string</p> <p>This character can only be used with constant string pointers. That is, the string must appear in the source and be passed to LOG_printf. For example, the following is supported:</p> <pre>char *msg = "Hello world!"; LOG_printf(&amp;trace, "%s", msg);</pre> <p>However, the following example is not supported:</p> <pre>char msg[100]; strcpy(msg, "Hello world!"); LOG_printf(&amp;trace, "%s", msg);</pre> <p>If the string appears in the COFF file and a pointer to the string is passed to LOG_printf, then the string in the COFF file is used by the Event Log to generate the output. If the string can not be found in the COFF file, the format string is replaced with <b>*** ERROR: 0x%x 0x%x ***\n</b>, which displays all arguments in hexadecimal.</p>
%r	<p>Symbol from symbol table</p> <p>This is an extension of the standard printf format tokens. This character treats its parameter as a pointer to be looked up in the symbol table of the executable and displayed. That is, %r displays the symbol (defined in the executable) whose value matches the value passed to %r. For example:</p> <pre>Int testval = 17; LOG_printf("%r = %d", &amp;testval, testval);</pre> <p>displays:</p> <pre>testval = 17</pre> <p>If no symbol is found for the value passed to %r, the Event Log uses the string &lt;unknown symbol&gt;.</p>
%p	data pointer

LOG\_printf does not provide a conversion character for code pointers. If you are using the 'C55x large model, you can use the %p character to print code pointers.

Since LOG\_printf does not provide a conversion character for long integers, you may want to use 0x%p instead. Another solution is to use bitwise shifting and ANDing to break a 32-bit number into its 16-bit counterparts. In following example, (Int)(maincount >> 16) is the upper 16 bits of maincount shifted into the 16-bits of an Int. And, (Int)(maincount & 0xffff) is the lower 16 bits of maincount.

```
LOG_printf(&trace, "total count = 0x%04x%04x",
          (Int)(maincount >> 16),
          (Int)(maincount & 0xffff));
```

The `0x%04x%04x` format string used in this example causes a literal string of "0x" to precede the value to indicate that it is a hex value. Then, each `%04x` tells `LOG_printf` to display the value as hex, padding to 4 characters with leading zeros.

If you want the Event Log to apply the same printf-style format string to all records in the log, use `Tconf` to choose raw data for the datatype property of this LOG object and typing a format string for the format property.

Each log message uses words (eight words for 'C55x large and huge models). The contents of the message written by `LOG_printf` are shown here:

LOG_printf	Sequence #	arg0	arg1	Format address
------------	------------	------	------	----------------

You configure the characteristics of a log in `Tconf`. If the logtype is circular, the log buffer of size `buflen` contains the last `buflen` elements. If the logtype is fixed, the log buffer contains the first `buflen` elements.

Any combination of threads can write to the same log. Internally, hardware interrupts are temporarily disabled during a call to `LOG_printf`. Log messages are never lost due to thread preemption.

### Constraints and Calling Context

- ❑ `LOG_printf` supports only 0, 1, or 2 arguments after the format string.
- ❑ No compilation error is reported if a call to `LOG_printf` casts an parameter as `Arg` or attempts to print a code pointer using a single parameter. These actions cause erroneous output on 'C55x.

### Example

```
LOG_printf(&trace, "hello world");
LOG_printf(&trace, "Size of Int is: %d", sizeof(Int));
```

### See Also

`LOG_error`  
`LOG_event`  
`TRC_disable`  
`TRC_enable`

**LOG\_reset***Reset a message log***C Interface**

**Syntax**                    LOG\_reset(log);

**Parameters**               LOG\_Handle log     /\* log object handle \*/

**Return Value**             Void

**Reentrant**                 no

**Description**              LOG\_reset enables the logging mechanism and allows the log buffer to be modified starting from the beginning of the buffer, with sequence number starting from 0.

LOG\_reset does not disable interrupts or otherwise protect the log from being modified by an HWI or other thread. It is therefore possible for the log to contain inconsistent data if LOG\_reset is preempted by an HWI or other thread that uses the same log.

**Example**                    LOG\_reset (&trace) ;

**See Also**                   LOG\_disable  
                              LOG\_enable

## 2.14 MBX Module

The MBX module is the mailbox manager.

### Functions

- ❑ MBX\_create. Create a mailbox
- ❑ MBX\_delete. Delete a mailbox
- ❑ MBX\_pend. Wait for a message from mailbox
- ❑ MBX\_post. Post a message to mailbox

### Constants, Types, and Structures

```
typedef struct MBX_Obj *MBX_Handle;
/* handle for mailbox object */

struct MBX_Attrs {          /* mailbox attributes */
    Int    segid;
};

MBX_Attrs MBX_ATTRS = { /* default attribute values */
    0,
};
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the MBX Manager Properties and MBX Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

#### Instance Configuration Parameters

Name	Type	Default
comment	String	"<add comments here>"
messageSize	Int16	1
length	Int16	1
elementSeg	Reference	prog.get("DARAM")

### Description

The MBX module makes available a set of functions that manipulate mailbox objects accessed through handles of type MBX\_Handle. Mailboxes can hold up to the number of messages specified by the Mailbox Length property in Tconf.

MBX\_pend waits for a message from a mailbox. Its timeout parameter allows the task to wait until a timeout. A timeout value of SYS\_FOREVER causes the calling task to wait indefinitely for a message. A timeout value of zero (0) causes MBX\_pend to return immediately. MBX\_pend's return value indicates whether the mailbox was signaled successfully.

MBX\_post is used to send a message to a mailbox. The timeout parameter to MBX\_post specifies the amount of time the calling task waits if the mailbox is full. If a task is waiting at the mailbox, MBX\_post removes the task from the queue and puts it on the ready queue. If no task is waiting and the mailbox is not full, MBX\_post simply deposits the message and returns.

## MBX Manager Properties

The following global property can be set for the MBX module on the MBX Manager Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **Object Memory.** The memory segment that contains the MBX objects created with Tconf.

Tconf Name: OBJMEMSEG Type: Reference

Example: `bios.MBX.OBJMEMSEG = prog.get("myMEM");`

## MBX Object Properties

To create an MBX object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var myMbx = bios.MBX.create("myMbx");
```

The following properties can be set for an MBX object in the MBX Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **comment.** Type a comment to identify this MBX object.

Tconf Name: comment Type: String

Example: `myMbx.comment = "my MBX";`

- ❑ **Message Size.** The size (in MADUs) of the messages this mailbox can contain.

Tconf Name: messageSize Type: Int16

Example: `myMbx.messageSize = 1;`

- ❑ **Mailbox Length.** The number of messages this mailbox can contain.

Tconf Name: length Type: Int16

Example: `myMbx.length = 1;`

- ❑ **Element memory segment.** The memory segment to contain the mailbox data buffers.

Tconf Name: elementSeg Type: Reference

Example: `myMbx.elementSeg = prog.get("myMEM");`



**MBX\_create***Create a mailbox***C Interface**

**Syntax** `mbx = MBX_create(msgsize, mbxlength, attrs);`

**Parameters**

```

size_t      msgsize; /* size of message */
Uns        mbxlength; /* length of mailbox */
MBX_Attrs  *attrs;   /* pointer to mailbox attributes */

```

**Return Value** `MBX_Handle mbx; /* mailbox object handle */`

**Description**

MBX\_create creates a mailbox object which is initialized to contain up to mbxlength messages of size msgsize. If successful, MBX\_create returns the handle of the new mailbox object. If unsuccessful, MBX\_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS\_error, and SYS\_error causes an abort).

If attrs is NULL, the new mailbox is assigned a default set of attributes. Otherwise, the mailbox's attributes are specified through a structure of type MBX\_Attrs.

All default attribute values are contained in the constant MBX\_ATTRS, which can be assigned to a variable of type MBX\_Attrs prior to calling MBX\_create.

MBX\_create calls MEM\_alloc to dynamically create the object's data structure. MEM\_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2–205.

**Constraints and Calling Context**

- ❑ MBX\_create cannot be called from a SWI or HWI.
- ❑ You can reduce the size of your application program by creating objects with Tconf rather than using the XXX\_create functions.

**See Also**

MBX\_delete  
SYS\_error

**MBX\_delete***Delete a mailbox***C Interface**

<b>Syntax</b>	MBX_delete(mbx);
<b>Parameters</b>	MBX_Handle mbx;     /* mailbox object handle */
<b>Return Value</b>	Void

**Description**

MBX\_delete frees the mailbox object referenced by mbx.

MBX\_delete calls MEM\_free to delete the MBX object. MEM\_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- ❑ No tasks should be pending on mbx when MBX\_delete is called.
- ❑ MBX\_delete cannot be called from a SWI or HWI.
- ❑ No check is performed to prevent MBX\_delete from being used on a statically-created object. If a program attempts to delete a mailbox object that was created using Tconf, SYS\_error is called.

**See Also**

MBX\_create



**MBX\_post***Post a message to mailbox***C Interface****Syntax**

```
status = MBX_post(mbx, msg, timeout);
```

**Parameters**

```
MBX_Handle mbx;    /* mailbox object handle */
Ptr          msg;  /* message pointer */
Uns         timeout; /* return after this many system clock ticks */
```

**Return Value**

```
Bool        status; /* TRUE if successful, FALSE if timeout */
```

**Description**

MBX\_post checks to see if there are any free message slots before copying msg into the mailbox. MBX\_post readies the first task (if any) waiting on mbx.

If the mailbox is full and timeout is SYS\_FOREVER, the task remains suspended until MBX\_pend is called on this mailbox. If timeout is 0, MBX\_post returns immediately. Otherwise, the task is suspended for timeout system clock ticks. The actual time of task suspension can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

If timeout expires (or timeout is 0) before the mailbox is available, MBX\_post returns FALSE. Otherwise MBX\_post returns TRUE.

A task switch occurs when calling MBX\_post if a higher priority task is made ready to run, or if there are no free message slots and timeout is not 0.

**Constraints and Calling Context**

- ❑ If you need to call MBX\_post within a TSK\_disable/TSK\_enable block, you must use a timeout of 0.
- ❑ This API can be called from a TSK with any timeout value, but if called from an HWI or SWI the timeout must be 0.
- ❑ MBX\_post can be called from the program's main() function. However, the number of calls should not be greater than the number of messages the mailbox can hold. Additional calls have no effect.

**See Also**

MBX\_pend

## 2.15 MEM Module

The MEM module is the memory segment manager.

### Functions

- ❑ MEM\_alloc. Allocate from a memory segment.
- ❑ MEM\_calloc. Allocate and initialize to 0.
- ❑ MEM\_define. Define a new memory segment.
- ❑ MEM\_free. Free a block of memory.
- ❑ MEM\_getBaseAddress. Get base address of memory heap.
- ❑ MEM\_increaseTableSize. Increase the internal MEM table size.
- ❑ MEM\_redefine. Redefine an existing memory segment.
- ❑ MEM\_stat. Return the status of a memory segment.
- ❑ MEM\_undefine. Undefine an existing memory segment.
- ❑ MEM\_valloc. Allocate and initialize to a value.

### Constants, Types, and Structures

```
MEM->MALLOCSEG = 0;    /* segid for malloc, free */

#define MEM_HEADERSIZE /* free block header size */
#define MEM_HEADERMASK /* mask to align on
                        MEM_HEADERSIZE */
#define MEM_ILLEGAL    /* illegal memory address */

MEM_Attrs MEM_ATTRS = { /* default attribute values */
    0
};

typedef struct MEM_Segment {
    Ptr      base;      /* base of the segment */
    MEM_sizep length;  /* size of the segment */
    Uns      space;    /* memory space */
} MEM_Segment;

typedef struct MEM_Stat {
    MEM_sizep size;    /* original size of segment */
    MEM_sizep used;   /* MADUs used in segment */
    size_t    length; /* largest contiguous block */
} MEM_Stat;

typedef unsigned long MEM_sizep;
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the MEM Manager Properties and MEM Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

## Module Configuration Parameters

C55x Name	Type	Default
REUSECODESPACE	Bool	false
ARGSSIZE	Numeric	x0008
STACKSIZE	Numeric	0x0400
SYSSTACKSIZE	Numeric	0x0100
NOMEMORYHEAPS	Bool	false
BIOSOBJSEG	Reference	prog.get("DARAM")
MALLOCSEG	Reference	prog.get("DARAM")
ARGSSEG	Reference	prog.get("DARAM")
STACKSEG	Reference	prog.get("DARAM")
SYSSTACKSEG	Reference	prog.get("DARAM")
GBLINITSEG	Reference	prog.get("SARAM")
TRCDATASEG	Reference	prog.get("SARAM")
SYSDATASEG	Reference	prog.get("DARAM")
OBJSEG	Reference	prog.get("DARAM")
BIOSSEG	Reference	prog.get("SARAM")
SYSINITSEG	Reference	prog.get("SARAM")
HWISEG	Reference	prog.get("SARAM")
HWIVCSEG	Reference	prog.get("VECT")
RTDXTEXTSEG	Reference	prog.get("SARAM")
USERCOMMANDFILE	Bool	false
TEXTSEG	Reference	prog.get("SARAM")
SWITCHSEG	Reference	prog.get("SARAM")
BSSSEG	Reference	prog.get("DARAM")
CINITSEG	Reference	prog.get("SARAM")
PINITSEG	Reference	prog.get("SARAM")
CONSTSEG	Reference	prog.get("DARAM")
DATASEG	Reference	prog.get("DARAM")
CIOSEG	Reference	prog.get("DARAM")
ENABLELOADADDR	Bool	false
LOADBIOSSEG	Reference	prog.get("SARAM")
LOADSYSINITSEG	Reference	prog.get("SARAM")
LOADGBLINITSEG	Reference	prog.get("SARAM")
LOADTRCDATASEG	Reference	prog.get("SARAM")
LOADTEXTSEG	Reference	prog.get("SARAM")
LOADSWITCHSEG	Reference	prog.get("SARAM")
LOADCINITSEG	Reference	prog.get("SARAM")
LOADPINITSEG	Reference	prog.get("SARAM")
LOADCONSTSEG	Reference	prog.get("DARAM")

C55x Name	Type	Default
LOADHWISEG	Reference	prog.get("SARAM")
LOADHWIVECSEG	Reference	prog.get("VECT")
LOADRTDXTEXTSEG	Reference	prog.get("SARAM")

### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
base	Numeric	0x000000
len	Numeric	0x000000
createHeap	Bool	true
heapSize	Numeric	0x03f80
enableHeapLabel	Bool	false
heapLabel	Extern	prog.extern("segment_name", "asm")
space	EnumString	"code/data" ("io")

## Description

The MEM module provides a set of functions used to allocate storage from one or more disjointed segments of memory. These memory segments are specified with Tconf.

MEM always allocates an even number of MADUs and always aligns buffers on an even boundary. This behavior is used to insure that free buffers are always at least two MADUs in length. This behavior does not preclude you from allocating two 512 buffers from a 1K region of on-device memory, for example. It does, however, mean that odd allocations consume one more MADU than expected.

If small code size is important to your application, you can reduce code size significantly by removing the capability to dynamically allocate and free memory. To do this, set the "No Dynamic Memory Heaps" property for the MEM manager to true. If you remove this capability, your program cannot call any of the MEM functions or any object creation functions (such as TSK\_create). You need to create all objects to be used by your program statically (with Tconf). You can also create or remove the dynamic memory heap from an individual memory segment in the configuration.

Software modules in DSP/BIOS that allocate storage at run-time use MEM functions; DSP/BIOS does not use the standard C function malloc. DSP/BIOS modules use MEM to allocate storage in the segment selected for that module with Tconf.





This size is shown as a hex value in Minimum Addressable Data Units (MADUs). An MADU is the smallest unit of data storage that can be read or written by the CPU. For the c5000 this is a 16-bit word.

Tconf Name: STACKSIZE Type: Numeric

Example: `bios.MEM.STACKSIZE = 0x0400;`

- ❑ **System Stack Size (MADUs).** The size of the system stack in MADUs, applicable only on the C55x device.

Tconf Name: SYSSTACKSIZE Type: Numeric

Example: `bios.MEM.SYSSTACKSIZE = 0x0100;`

- ❑ **No Dynamic Memory Heaps.** Put a checkmark in this box to completely disable the ability to dynamically allocate memory and the ability to dynamically create and delete objects. If this property is set to true, the program may not call the MEM\_alloc, MEM\_valloc, MEM\_calloc, and malloc or the XXX\_create function for any DSP/BIOS module. If this property is set to true, the Segment For DSP/BIOS Objects, Segment for malloc()/free(), and Stack segment for dynamic tasks properties are set to MEM\_NULL.

When you set this property to true, heaps already specified in MEM segments are removed from the configuration. If you later reset this property to false, recreate heaps by configuring properties for individual MEM objects as needed.

Tconf Name: NOMEMORYHEAPS Type: Bool

Example: `bios.MEM.NOMEMORYHEAPS = false;`

- ❑ **Segment For DSP/BIOS Objects.** The default memory segment to contain objects created at run-time with an XXX\_create function. The XXX\_Attrs structure passed to the XXX\_create function can override this default. If you select MEM\_NULL for this property, creation of DSP/BIOS objects at run-time via the XXX\_create functions is disabled.

Tconf Name: BIOSOBJSEG Type: Reference

Example: `bios.MEM.BIOSOBJSEG = prog.get("myMEM");`

- ❑ **Segment For malloc() / free().** The memory segment from which space is allocated when a program calls malloc and from which space is freed when a program calls free. If you select MEM\_NULL for this property, dynamic memory allocation at run-time is disabled.

Tconf Name: MALLOCSEG Type: Reference

Example: `bios.MEM.MALLOCSEG = prog.get("myMEM");`

**BIOS Data tab**

- ❑ **Argument Buffer Section (.args).** The memory segment containing the .args section.

Tconf Name: ARGSSSEG Type: Reference

Example: `bios.MEM.ARGSSSEG = prog.get("myMEM");`

- ❑ **Stack Section (.stack).** The memory segment containing the data stack. This segment should be located in RAM. The platform architecture requires that both the user and system stacks (pointed to by the XSP and XSSP registers, respectively) reside in the same 64K page of memory, that is, the upper 7 bits of the stack address (SPH) are shared.

Tconf Name: STACKSEG Type: Reference

Example: `bios.MEM.STACKSEG = prog.get("myMEM");`

- ❑ **System Stack Section (.sysstack).** The memory segment containing the system stack, applicable only on the C55x device.

Tconf Name: SYSSTACKSEG Type: Reference

Example: `bios.MEM.SYSSTACKSEG =  
prog.get("myMEM");`

- ❑ **DSP/BIOS Init Tables (.gblinit).** The memory segment containing the DSP/BIOS global initialization tables.

Tconf Name: GBLINITSEG Type: Reference

Example: `bios.MEM.GBLINITSEG = prog.get("myMEM");`

- ❑ **TRC Initial Value (.trcdata).** The memory segment containing the TRC mask variable and its initial value. This segment must be placed in RAM.

Tconf Name: TRCDATASEG Type: Reference

Example: `bios.MEM.TRCDATASEG = prog.get("myMEM");`

- ❑ **DSP/BIOS Kernel State (.sysdata).** The memory segment containing system data about the DSP/BIOS kernel state.

Tconf Name: SYSDATASEG Type: Reference

Example: `bios.MEM.SYSDATASEG = prog.get("myMEM");`

- ❑ **DSP/BIOS Conf Sections (.obj).** The memory segment containing configuration properties that can be read by the target program.

Tconf Name: OBJSEG Type: Reference

Example: `bios.MEM.OBJSEG = prog.get("myMEM");`

**BIOS Code tab**

- ❑ **BIOS Code Section (.bios).** The memory segment containing the DSP/BIOS code.

Tconf Name: BIOSSEG Type: Reference

Example: `bios.MEM.BIOSSEG = prog.get("myMEM");`

- ❑ **Startup Code Section (.sysinit).** The memory segment containing DSP/BIOS startup initialization code; this memory can be reused after main starts executing.

Tconf Name: SYSINITSEG Type: Reference

Example: `bios.MEM.SYSINITSEG = prog.get("myMEM");`

- ❑ **Function Stub Memory (.hwi).** The memory segment containing dispatch code for HWIs that are configured to be monitored in the HWI Object Properties.

Tconf Name: HWISEG Type: Reference

Example: `bios.MEM.HWISEG = prog.get("myMEM");`

- ❑ **Interrupt Service Table Memory (.hwi\_vec).** The memory segment containing the Interrupt Service Table (IST).

Tconf Name: HWIVCSEG Type: Reference

Example: `bios.MEM.HWIVCSEG = prog.get("myMEM");`

- ❑ **RTDX Text Segment (.rtdx\_text).** The memory segment containing the code sections for the RTDX module.

Tconf Name: RTDXTEXTSEG Type: Reference

Example: `bios.MEM.RTDXTEXTSEG =  
prog.get("myMEM");`

#### Compiler Sections tab

- ❑ **User .cmd File For Compiler Sections.** Put a checkmark in this box if you want to have full control over the memory used for the sections that follow. You must then create a linker command file that begins by including the linker command file created by the configuration. Your linker command file should then assign memory for the items normally handled by the following properties. See the *TMS320C54x Optimizing Compiler User's Guide*, (literature number SPRU103E) for more details.

Tconf Name: USERCOMMANDFILE Type: Bool

Example: `bios.MEM.USERCOMMANDFILE = false;`

- ❑ **Text Section (.text).** The memory segment containing the executable code, string literals, and compiler-generated constants. This segment can be located in ROM or RAM.

Tconf Name: TEXTSEG Type: Reference

Example: `bios.MEM.TEXTSEG = prog.get("myMEM");`

- ❑ **Switch Jump Tables (.switch).** The memory segment containing the jump tables for switch statements. This segment can be located in ROM or RAM.

Tconf Name: SWITCHSEG Type: Reference

Example: `bios.MEM.SWITCHSEG = prog.get("myMEM");`

- ❑ **C Variables Section (.bss).** The memory segment containing global and static C variables. At boot or load time, the data in the .cinit section is copied to this segment. This segment should be located in RAM.

Tconf Name: BSSSEG Type: Reference

Example: `bios.MEM.BSSSEG = prog.get("myMEM");`

- ❑ **Data Initialization Section (.cinit).** The memory segment containing tables for explicitly initialized global and static variables and constants. This segment can be located in ROM or RAM.

Tconf Name: CINITSEG Type: Reference

Example: `bios.MEM.CINITSEG = prog.get("myMEM");`

- ❑ **C Function Initialization Table (.pinit).** The memory segment containing the table of global object constructors. Global constructors must be called during program initialization. The C/C++ compiler produces a table of constructors to be called at startup. The table is contained in a named section called .pinit. The constructors are invoked in the order that they occur in the table. This segment can be located in ROM or RAM.

Tconf Name: PINITSEG Type: Reference

Example: `bios.MEM.PINITSEG = prog.get("myMEM");`

- ❑ **Constant Sections (.const, .printf).** These sections can be located in ROM or RAM. The .const section contains string constants and data defined with the const C qualifier. The DSP/BIOS .printf section contains other constant strings used by the Real-Time Analysis tools. The .printf section is not loaded onto the target. Instead, the (COPY) directive is used for this section in the .cmd file. The .printf section is managed along with the .const section, since it must be grouped with the .const section to make sure that no addresses overlap. If you specify these sections in your own .cmd file, you'll need to do something like the following:

```
GROUP {
    .const: {}
    .printf (COPY): {}
} > IRAM
```

Tconf Name: CONSTSEG Type: Reference

Example: `bios.MEM.CONSTSEG = prog.get("myMEM");`

- ❑ **Data Section (.data).** This memory segment contains program data. This segment can be located in ROM or RAM.

Tconf Name: DATASEG Type: Reference

Example: `bios.MEM.DATASEG = prog.get("myMEM");`

- Data Section (.cio).** This memory segment contains C standard I/O buffers.

Tconf Name: CIOSEG

Type: Reference

Example: `bios.MEM.CIOSEG = prog.get("myMEM");`

## Load Address tab

- Specify Separate Load Addresses.** If you put a checkmark in this box, you can select separate load addresses for the sections listed on this tab.

Load addresses are useful when, for example, your code must be loaded into ROM, but would run faster in RAM. The linker allows you to allocate sections twice: once to set a load address and again to set a run address.

If you do not select a separate load address for a section, the section loads and runs at the same address.

If you do select a separate load address, the section is allocated as if it were two separate sections of the same size. The load address is where raw data for the section is placed. References to items in the section refer to the run address. The application must copy the section from its load address to its run address. For details, see the topics on Runtime Relocation and the `.label` Directive in the Code Generation Tools help or manual.

Tconf Name: ENABLELOADADDR

Type: Bool

Example: `bios.MEM.ENABLELOADADDR = false;`

- Load Address - BIOS Code Section (.bios).** The memory segment containing the load allocation of the section that contains DSP/BIOS code.

Tconf Name: LOADBIOSSEG

Type: Reference

Example: `bios.MEM.LOADBIOSSEG =  
prog.get("myMEM");`

- Load Address - Startup Code Section (.sysinit).** The memory segment containing the load allocation of the section that contains DSP/BIOS startup initialization code.

Tconf Name: LOADSYSINITSEG

Type: Reference

Example: `bios.MEM.LOADSYSINITSEG =  
prog.get("myMEM");`

- Load Address - DSP/BIOS Init Tables (.gblinit).** The memory segment containing the load allocation of the section that contains the DSP/BIOS global initialization tables.

Tconf Name: LOADGBLINITSEG

Type: Reference

Example: `bios.MEM.LOADGBLINITSEG =  
prog.get("myMEM");`



- ❑ **Load Address - Function Stub Memory (.hwi).** The memory segment containing the load allocation of the section that contains dispatch code for HWIs configured to be monitored.

Tconf Name: LOADHWISEG Type: Reference

Example: `bios.MEM.LOADHWISEG = prog.get("myMEM");`

- ❑ **Load Address - Interrupt Service Table Memory (.hwi\_vec).** The memory segment containing the load allocation of the section that contains the Interrupt Service Table.

Tconf Name: LOADHWIVECSEG Type: Reference

Example: `bios.MEM.LOADHWIVECSEG =  
prog.get("myMEM");`

- ❑ **Load Address - RTDX Text Segment (.rtdx\_text).** The memory segment containing the load allocation of the section that contains the code sections for the RTDX module.

Tconf Name: LOADRTDXTEXTSEG Type: Reference

Example: `bios.MEM.LOADRTDXTEXTSEG =  
prog.get("myMEM");`

## MEM Object Properties

A memory segment represents a contiguous length of code or data memory in the address space of the processor.

To create a MEM object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var myMem = bios.MEM.create("myMem");
```

The following properties can be set for a MEM object in the MEM Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **comment.** Type a comment to identify this MEM object.  
Tconf Name: comment Type: String  
Example: `myMem.comment = "my MEM";`
- ❑ **base.** The address at which this memory segment begins. This value is shown in hex.  
Tconf Name: base Type: Numeric  
Example: `myMem.base = 0x000000;`
- ❑ **len.** The length of this memory segment in MADUs. This value is shown in hex.  
Tconf Name: len Type: Numeric  
Example: `myMem.len = 0x000000;`

- ❑ **create a heap in this memory.** If this property is set to true, a heap is created in this memory segment. Memory can be allocated dynamically from a heap. In order to remove the heap from a memory segment, you can select another memory segment that contains a heap for properties that dynamically allocate memory in this memory segment. The properties you should check are in the Memory Section Manager (the Segment for DSP/BIOS objects and Segment for malloc/free properties) and the Task Manager (the Default stack segment for dynamic tasks property). If you disable dynamic memory allocation in the Memory Section Manager, you cannot create a heap in any memory segment.

Tconf Name: createHeap

Type: Bool

Example: `myMem.createHeap = true;`

- ❑ **heap size.** The size of the heap in MADUs to be created in this memory segment. You cannot control the location of the heap within its memory segment except by making the segment and heap the same sizes. Note that if the base of the heap ends up at address 0x0, the base address of the heap is offset by MEM\_HEADERSIZE and the heap size is reduced by MEM\_HEADERSIZE.

A heap can potentially be sized to cross a 64K page boundary. See the MEM\_alloc topic for information about the effects of page boundaries on heaps.

Tconf Name: heapSize

Type: Numeric

Example: `myMem.heapSize = 0x03f80;`

- ❑ **enter a user defined heap identifier.** If this property is set to true, you can define your own identifier label for this heap.

Tconf Name: enableHeapLabel

Type: Bool

Example: `myMem.enableHeapLabel = false;`

- ❑ **heap identifier label.** If the property above is set to true, type a name for this segment's heap.

Tconf Name: heapLabel

Type: Extern

Example: `myMem.heapLabel =  
prog.extern("seg_name", "asm");`

- ❑ **space.** Type of memory segment. This is set to code for memory segments that store programs, and data for memory segments that store program data.

Tconf Name: space

Type: EnumString

Options: "code/data", "io"

Example: `myMem.space = "code/data";`



The predefined memory segments in a configuration file, particularly those for external memory, are dependent on the board template you select. In general, Table 2-5 lists segments that can be defined for the c5000:

*Table 2-5. Typical Memory Segments for C5000 Boards*

<b>Name</b>	<b>Memory Segment Type</b>
USERREGS	User scratchpad memory
BIOSREGS	Scratchpad memory reserved for use by DSP/BIOS
VECT	Interrupt vector table
IDATA	Internal data RAM
IPROG	Internal program RAM
EDATA	External data memory
EPROG	External program memory

**MEM\_alloc***Allocate from a memory segment***C Interface**

<b>Syntax</b>	<code>addr = MEM_alloc(segid, size, align);</code>		
<b>Parameters</b>	<code>Int</code>	<code>segid;</code>	<i>/* memory segment identifier */</i>
	<code>size_t</code>	<code>size;</code>	<i>/* block size in MADUs */</i>
	<code>size_t</code>	<code>align;</code>	<i>/* block alignment */</i>
<b>Return Value</b>	<code>Void</code>	<code>*addr;</code>	<i>/* address of allocated block of memory */</i>

**Description**

MEM\_alloc allocates a contiguous block of storage from the memory segment identified by segid and returns the address of this block.

The segid parameter identifies the memory segment to allocate memory from. This identifier can be an integer or a memory segment name defined in the configuration. Files created by the configuration define each configured segment name as a variable with an integer value.

The block contains size MADUs and starts at an address that is a multiple of align. If align is 0 or 1, there is no alignment constraint.

MEM\_alloc does not initialize the allocated memory locations.

If the memory request cannot be satisfied, MEM\_alloc calls SYS\_error with SYS\_EALLOC and returns MEM\_ILLEGAL.

MEM functions that allocate and deallocate memory internally lock the memory by calling the LCK\_pend and LCK\_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM\_alloc cannot be called from the context of a SWI or HWI. MEM\_alloc checks the context from which it is called. It calls SYS\_error and returns MEM\_ILLEGAL if it is called from the wrong context.

A number of other DSP/BIOS APIs call MEM\_alloc internally, and thus also cannot be called from the context of a SWI or HWI. See the "Function Callability Table" on page A-2 for a detailed list of calling contexts for each DSP/BIOS API.

**Page Boundary Issues on the 'C55x**

On the 'C55x using the large memory model, MEM objects can configure heaps larger than 64K MADUs (16-bit words for 'C55x). However, memory blocks that cross a 64K page boundary cause C compiler errors. (See the *TMS320C55x Optimizing C Compiler User's Guide* for details.)

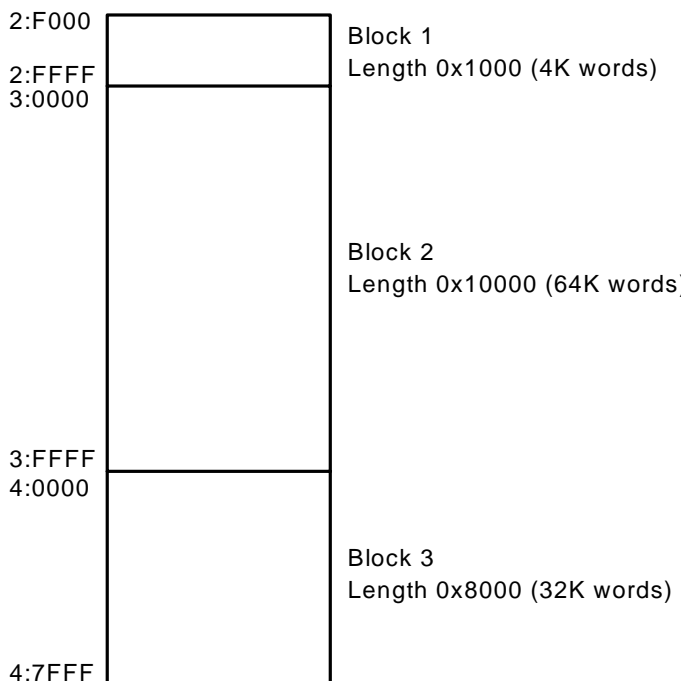
To prevent such errors, you can use the huge memory model. If you use the large memory model, the remainder of this section applies.

When using the large memory model, the MEM module divides heaps that cross page boundaries into memory blocks that do not cross boundaries. As a result, MEM\_alloc and MEM\_free can only allocate and free memory within a single memory block, and the largest block that MEM\_alloc can allocate in any case is 64K words (0x10000).

For example, suppose you create a RAM segment called MYRAM that is 100K words in length. MYRAM has a base address of 2:F000 and a length of 0x19000. The heap within MYRAM is also 100K words and has a heap identifier label of MYSEG. So this heap also has a base address of 2:F000 and ends at 4:7FFF.

To prevent a memory block from crossing a page boundary, the MEM Module separates this heap into the following memory blocks, which are aligned along 64K page boundaries:

Figure 2-1. MYSEG Heap Initial Memory Map



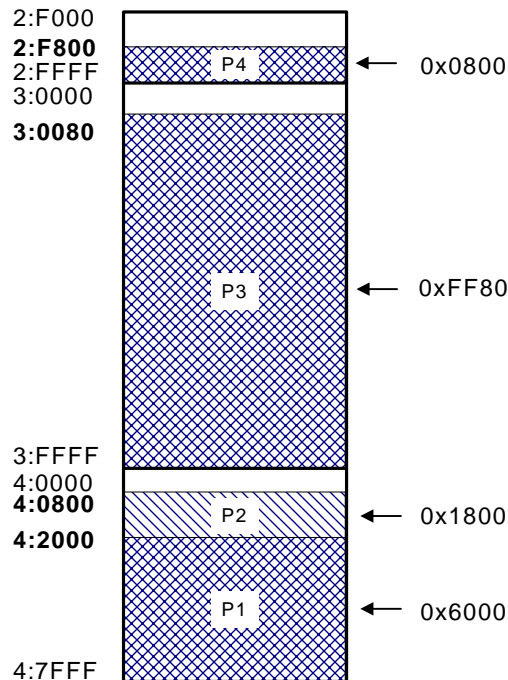
Suppose your program calls MEM\_alloc in the following sequence:

```
P3 = MEM_alloc(MYSEG, 0xFF80, 0);
P1 = MEM_alloc(MYSEG, 0x6000, 0);
P2 = MEM_alloc(MYSEG, 0x1800, 0);
P4 = MEM_alloc(MYSEG, 0x800, 0);
```

MEM\_alloc allocates memory from the first available memory block that is large enough. The memory block with the lowest address is the first available. In our example, the memory block with base address 2:F000 and length 0x1000 is the first available memory block. MEM\_alloc gets memory sections from the bottom of a memory block. If the heap does not have enough memory for a particular call to MEM\_alloc, that call returns an error and the next call to MEM\_alloc is executed.

The results of these calls to MEM\_alloc are shown in the figure and list that follow.

Figure 2-2. MYSEG Memory Map After Allocation



```
❑ P3 = MEM_alloc(MYSEG, 0xFF80, 0);
```

This call requests 0xFF80 words. The first available block (at 2:F000) has a size of 0x1000; it is too small for 0xFF80. The next block (at 3:0000) has a size of 0x10000; it is large enough to allocate 0xFF80 words. So, P3 points to a block from 3:0080 to 3:FFFF (because MEM\_alloc takes memory from the bottom of a memory block).

```
❑ P1 = MEM_alloc(MYSEG, 0x6000, 0);
```

This call requests 0x6000 words. The first block has a size of 0x1000, which is still too small. The next block now has only 0x80 words available because of the previous memory allocation. The last

memory block has a size of 0x8000, and is large enough for this allocation. So, P1 points to a block from 4:2000 to 4:7FFF.

```
❑ P2 = MEM_alloc(MYSEG, 0x1800, 0);
```

This call requests 0x1800 words. Blocks 1 and 2 are again too small. The last block has 0x2000 words remaining, and can accommodate this allocation. So, P2 points to a block from 4:0800 to 4:1FFF.

```
❑ P4 = MEM_alloc(MYSEG, 0x800, 0);
```

This call requests 0x800 words. This time, the first block is large enough. So, P4 points to a block from 2:F800 to 2:FFFF.

Consider how this memory map would change if the same MEM\_alloc calls were made in the following sequence:

```
P1 = MEM_alloc(MYSEG, 0x6000, 0);
```

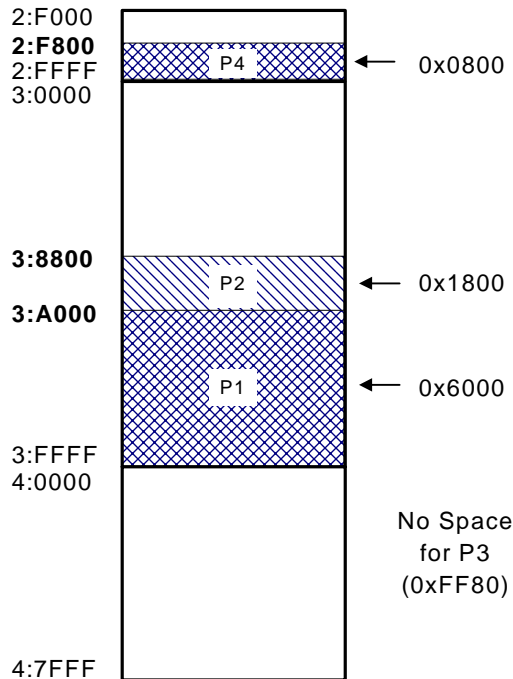
```
P2 = MEM_alloc(MYSEG, 0x1800, 0);
```

```
P3 = MEM_alloc(MYSEG, 0xFF80, 0);
```

```
P4 = MEM_alloc(MYSEG, 0x800, 0);
```

The results of this modified call sequence are as follows and are shown in Figure 2-3.

*Figure 2-3. MYSEG Memory Map After Modified Allocation*



```
❑ P1 is allocated from 3:A000 to 3:FFFF.
```

- ❑ P2 is allocated from 3:8800 to 3:9FFF.
- ❑ P3 is not allocated because no unallocated memory blocks are large enough to hold 0xFF80.
- ❑ P4 is allocated from 2:F800 to 2:FFFF.

As a result of page boundary limitations on MEM\_alloc, you should follow these guidelines when using large heaps and multiple MEM\_alloc calls:

- ❑ Create a memory segment specifically for a heap. Give the heap the same size as the memory segment so that the base of the memory segment is at the same location as the base of the heap. (You cannot specify the location of the heap within a memory segment if the memory segment is larger than the heap.) If possible, align the memory segment with a page boundary to maximize the size of memory blocks within the heap.
- ❑ If possible, allocate larger blocks of memory from the heap first. Previous allocations of small memory blocks can reduce the size of the memory blocks available for large memory allocations.
- ❑ Realize that MEM\_alloc can fail and call SYS\_error even if the heap contain a sufficient absolute amount of unallocated space. This is because the largest free memory block within the heap may be much smaller than the total amount of unallocated memory.
- ❑ If your application allocates memory in an unpredictable sequence, use a heap that is much larger than the amount of memory needed.
- ❑ segid must identify a valid memory segment.
- ❑ MEM\_alloc cannot be called from a SWI or HWI.
- ❑ MEM\_alloc cannot be called if the TSK scheduler is disabled.
- ❑ align must be 0, or a power of 2 (for example, 1, 2, 4, 8).

## Constraints and Calling Context

## See Also

MEM\_calloc  
MEM\_free  
MEM\_valloc

**MEM\_calloc***Allocate from a memory segment and set value to 0***C Interface**

<b>Syntax</b>	<code>addr = MEM_calloc(segid, size, align)</code>		
<b>Parameters</b>	<code>Int</code>	<code>segid;</code>	<code>/* memory segment identifier */</code>
	<code>size_t</code>	<code>size;</code>	<code>/* block size in MADUs */</code>
	<code>size_t</code>	<code>align;</code>	<code>/* block alignment */</code>
<b>Return Value</b>	<code>Void</code>	<code>*addr;</code>	<code>/* address of allocated block of memory */</code>

**Description**

MEM\_calloc is functionally equivalent to calling MEM\_valloc with value set to 0. MEM\_calloc allocates a contiguous block of storage from the memory segment identified by segid and returns the address of this block.

The segid parameter identifies the memory segment from which memory is to be allocated. This identifier can be an integer or a memory segment name defined in the configuration. The files created by the configuration define each configured segment name as a variable with an integer value.

The block contains size MADUs and starts at an address that is a multiple of align. If align is 0 or 1, there is no alignment constraint.

If the memory request cannot be satisfied, MEM\_calloc calls SYS\_error with SYS\_EALLOC and returns MEM\_ILLEGAL.

MEM functions that allocate and deallocate memory internally lock the memory by calling the LCK\_pend and LCK\_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM\_calloc cannot be called from the context of a SWI or HWI.

**Constraints and Calling Context**

- ❑ segid must identify a valid memory segment.
- ❑ MEM\_calloc cannot be called from a SWI or HWI.
- ❑ MEM\_calloc cannot be called if the TSK scheduler is disabled.
- ❑ align must be 0, or a power of 2 (for example, 1, 2, 4, 8).

**See Also**

MEM\_alloc  
MEM\_free  
MEM\_valloc  
SYS\_error  
std.h and stdlib.h functions

**MEM\_define***Define a new memory segment***C Interface**

**Syntax**                                `segid = MEM_define(base, length, attrs);`

**Parameters**

Ptr	base;	/* base address of new segment */
MEM_sizep	length;	/* length (in MADUs) of new segment */
MEM_Attrs	*attrs;	/* segment attributes */

**Return Value**                        `Int                segid;        /* ID of new segment */`

**Reentrant**                             `yes`

**Description**                         `MEM_define` defines a new memory segment for use by the DSP/BIOS MEM Module.

The new segment contains length MADUs starting at base. A new table entry is allocated to define the segment, and the entry's index into this table is returned as the segid.

The new block should be aligned on a MEM\_HEADERSIZE boundary, and the length should be a multiple of MEM\_HEADERSIZE.

If attrs is NULL, the new segment is assigned a default set of attributes. Otherwise, the segment's attributes are specified through a structure of type MEM\_Attrs.

**Note:**

No attributes are supported for segments, and the type MEM\_Attrs is defined as a dummy structure.

If there are undefined slots available in the internal table of memory segment identifiers, one of those slots is (re)used for the new segment. If there are no undefined slots available in the internal table, the table size is increased via MEM\_alloc. See MEM\_increaseTableSize to manage performance in this situation.

**Constraints and Calling Context**

- At least one segment must exist at the time MEM\_define is called.
- MEM\_define internally locks the memory by calling LCK\_pend and LCK\_post. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM\_define cannot be called from the context of a SWI or HWI. It can be called from main() or a TSK. The duration that the API holds the memory lock is variable.



- ❑ The length parameter must be a multiple of MEM\_HEADERSIZE and must be at least equal to MEM\_HEADERSIZE.
- ❑ The base Ptr cannot be NULL.

**See Also**

MEM\_redefine  
MEM\_undefine

**MEM\_free***Free a block of memory***C Interface**

<b>Syntax</b>	status = MEM_free(segid, addr, size);		
<b>Parameters</b>	Int	segid;	/* memory segment identifier */
	Ptr	addr;	/* block address pointer */
	size_t	size;	/* block length in MADUs*/
<b>Return Value</b>	Bool	status;	/* TRUE if successful */

**Description**

MEM\_free places the memory block specified by addr and size back into the free pool of the segment specified by segid. The newly freed block is combined with any adjacent free blocks. This space is then available for further allocation by MEM\_alloc. The segid can be an integer or a memory segment name defined in the configuration.

MEM functions that allocate and deallocate memory internally lock the memory by calling the LCK\_pend and LCK\_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM\_free cannot be called from the context of a SWI or HWI.

Although MEM\_free combines newly freed blocks with adjacent free blocks, it does not combine blocks that cross a 64K page boundary. See the MEM\_alloc topic for information about the effects of page boundaries on heaps.

**Constraints and Calling Context**

- addr must be a valid pointer returned from a call to MEM\_alloc.
- segid and size are those values used in a previous call to MEM\_alloc.
- MEM\_free cannot be called by HWI or SWI functions.
- MEM\_free cannot be called if the TSK scheduler is disabled.

**See Also**

MEM\_alloc  
std.h and stdlib.h functions

**MEM\_getBaseAddress***Get base address of a memory heap***C Interface****Syntax**

```
addr = MEM_getBaseAddress(segid);
```

**Parameters**

```
Int      segid;    /* memory segment identifier */
```

**Return Value**

```
Ptr      addr;     /* heap base address pointer */
```

**Description**

MEM\_getBaseAddress returns the base address of the memory heap with the segment ID specified by the segid parameter.

**Constraints and Calling Context**

- ❑ The segid can be an integer or a memory segment name defined in the configuration.

**See Also**

MEM Object Properties



**MEM\_redefine***Redefine an existing memory segment***C Interface**

**Syntax** MEM\_redefine(segid, base, length);

**Parameters**

Int	segid;	/* segment to redefine */
Ptr	base;	/* base address of new block */
MEM_sizep	length;	/* length (in MADUs) of new block */

**Return Value** Void

**Reentrant** yes

**Description** MEM\_redefine redefines an existing memory segment managed by the DSP/BIOS MEM Module. All pointers in the old segment memory block are automatically freed, and the new segment block is completely available for allocations.

The new block should be aligned on a MEM\_HEADERSIZE boundary, and the length should be a multiple of MEM\_HEADERSIZE.

**Constraints and Calling Context**

- ❑ MEM\_redefine internally locks the memory by calling LCK\_pend and LCK\_post. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM\_redefine cannot be called from the context of a SWI or HWI. It can be called from main() or a TSK. The duration that the API holds the memory lock is variable.
- ❑ The length parameter must be a multiple of MEM\_HEADERSIZE and must be at least equal to MEM\_HEADERSIZE.
- ❑ The base Ptr cannot be NULL.

**See Also** MEM\_define  
MEM\_undefine

**MEM\_stat***Return the status of a memory segment***C Interface**

**Syntax**                    `status = MEM_stat(segid, statbuf);`

**Parameters**                `Int            segid;    /* memory segment identifier */`  
                               `MEM_Stat    *statbuf; /* pointer to stat buffer */`

**Return Value**              `Bool           status;   /* TRUE if successful */`

**Description**

MEM\_stat returns the status of the memory segment specified by segid in the status structure pointed to by statbuf.

```
typedef struct MEM_Stat {
    MEM_sizep  size;   /* original size of segment */
    MEM_sizep  used;   /* MADUs used in segment */
    size_t     length; /* largest contiguous block */
} MEM_Stat;
```

All values are expressed in terms of minimum addressable units (MADUs).

MEM\_stat returns TRUE if segid corresponds to a valid memory segment, and FALSE otherwise. If MEM\_stat returns FALSE, the contents of statbuf are undefined. If the segment has been undefined with MEM\_undefine, this function returns FALSE.

MEM functions that access memory internally lock the memory by calling the LCK\_pend and LCK\_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM\_stat cannot be called from the context of a SWI or HWI.

**Constraints and Calling Context**

- ❑ MEM\_stat cannot be called from a SWI or HWI.
- ❑ MEM\_stat cannot be called if the TSK scheduler is disabled.

**MEM\_undefine***Undefine an existing memory segment***C Interface**

**Syntax** MEM\_undefine(segid);

**Parameters** Int segid; /\* segment to undefine \*/

**Return Value** Void

**Reentrant** yes

**Description** MEM\_undefine removes a memory segment from the internal memory tables. Once a memory segment has been undefined, the segid cannot be used in any of the MEM APIs (except MEM\_stat). Note: The undefined segid might later be returned by a subsequent MEM\_define call.

MEM\_undefine internally locks the memory by calling LCK\_pend and LCK\_post. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM\_undefine cannot be called from the context of a SWI or HWI. It can be called from main() or a TSK. The duration that the API holds the memory lock is variable.

**Constraints and Calling Context**

- ❑ Do not call from the context of a SWI or HWI.
- ❑ MEM\_undefine does not free the actual memory buffer managed by the memory segment.

**See Also** MEM\_define  
MEM\_redefine

**MEM\_valloc***Allocate from a memory segment and set value***C Interface****Syntax**

```
addr = MEM_valloc(segid, size, align, value);
```

**Parameters**

```
Int          segid;    /* memory segment identifier */
size_t       size;     /* block size in MADUs */
size_t       align;    /* block alignment */
Char         value;    /* character value */
```

**Return Value**

```
Void         *addr;    /* address of allocated block of memory */
```

**Description**

MEM\_valloc uses MEM\_alloc to allocate the memory before initializing it to value.

The segid parameter identifies the memory segment from which memory is to be allocated. This identifier can be an integer or a memory segment name defined in the configuration. The files created by the configuration define each configured segment name as a variable with an integer value.

The block contains size MADUs and starts at an address that is a multiple of align. If align is 0 or 1, there is no alignment constraint.

If the memory request cannot be satisfied, MEM\_valloc calls SYS\_error with SYS\_EALLOC and returns MEM\_ILLEGAL.

MEM functions that allocate and deallocate memory internally lock the memory by calling the LCK\_pend and LCK\_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM\_valloc cannot be called from the context of a SWI or HWI.

**Constraints and Calling Context**

- segid must identify a valid memory segment.
- MEM\_valloc cannot be called from a SWI or HWI.
- MEM\_valloc cannot be called if the TSK scheduler is disabled.
- align must be 0, or a power of 2 (for example, 1, 2, 4, 8).

**See Also**

```
MEM_alloc
MEM_calloc
MEM_free
SYS_error
std.h and stdlib.h functions
```



## 2.16 MSGQ Module

The MSGQ module allows for the structured sending and receiving of variable length messages. This module can be used for homogeneous or heterogeneous multi-processor messaging.

### Functions

- ❑ MSGQ\_alloc. Allocate a message. Performed by writer.
- ❑ MSGQ\_close. Closes a message queue. Performed by reader.
- ❑ MSGQ\_count. Return the number of messages in a message queue.
- ❑ MSGQ\_free. Free a message. Performed by reader.
- ❑ MSGQ\_get. Receive a message from the message queue. Performed by reader.
- ❑ MSGQ\_getAttrs: Returns the attributes of a local message queue.
- ❑ MSGQ\_getDstQueue. Get destination message queue.
- ❑ MSGQ\_getMsgId. Return the message ID from a message.
- ❑ MSGQ\_getMsgSize. Return the message size from a message.
- ❑ MSGQ\_getSrcQueue. Extract the reply destination from a message.
- ❑ MSGQ\_isLocalQueue. Returns TRUE if local message queue.
- ❑ MSGQ\_locate. Synchronously find a message queue. Performed by writer.
- ❑ MSGQ\_locateAsync. Asynchronously find a message queue. Performed by writer.
- ❑ MSGQ\_open. Opens a message queue. Performed by reader.
- ❑ MSGQ\_put. Place a message on a message queue. Performed by writer.
- ❑ MSGQ\_release. Release a located message queue. Performed by writer.
- ❑ MSGQ\_setErrorHandler. Set up handling of internal MSGQ errors.
- ❑ MSGQ\_setMsgId. Sets the message ID in a message.
- ❑ MSGQ\_setSrcQueue. Sets the reply destination in a message.

### Constants, Types, and Structures

```
/* Attributes used to open message queue */
typedef struct MSGQ_Attrs {
    Ptr        notifyHandle;
    MSGQ_Pend  pend;
    MSGQ_Post  post;
} MSGQ_Attrs;
```

```

MSGQ_Attrs MSGQ_ATTRS = {
    NULL,                /* notifyHandle */
    (MSGQ_Pend)SYS_zero, /* NOP pend */
    FXN_F_nop           /* NOP post */
};

/* Attributes for message queue location */
typedef struct MSGQ_LocateAttrs {
    Uns        timeout;
} MSGQ_LocateAttrs;

MSGQ_LocateAttrs  MSGQ_LOCATEATTRS = {SYS_FOREVER};

/* Attrs for asynchronous message queue location */
typedef struct MSGQ_LocateAsyncAttrs {
    Uint16      poolId;
    Arg         arg;
} MSGQ_LocateAttrs;

MSGQ_LocateAsyncAttrs  MSGQ_LOCATEASYNCATTRS = {0, 0};

/* Configuration structure */
typedef struct MSGQ_Config {
    MSGQ_Obj      *msgqQueues;        /* Array of MSGQ handles */
    MSGQ_TransportObj *transports;    /* Transport array */
    Uint16        numMsgqQueues;      /* Number of MSGQ handles */
    Uint16        numProcessors;      /* Number of processors */
    Uint16        startUninitialized; /* 1st MSGQ to init */
    MSGQ_Queue    errorQueue;         /* Receives transport err */
    Uint16        errorPoolId;        /* Alloc errors from poolId */
} MSGQ_Config;

/* Asynchronous locate message */
typedef struct MSGQ_AsyncLocateMsg {
    MSGQ_MsgHeader header;
    MSGQ_Queue      msgqQueue;
    Arg             arg;
} MSGQ_AsyncLocateMsg;

/* Asynchronous error message */
typedef struct MSGQ_AsyncErrorMsg {
    MSGQ_MsgHeader header;
    MSGQ_MqtError  errorType;
    Uint16         mqtId;
    Uint16         parameter;
} MSGQ_AsyncErrorMsg;

```

```

/* Transport object */
typedef struct MSGQ_TransportObj {
    MSGQ_MqtInit  initFxn;    /* Transport init func */
    MSGQ_TransportFxn *fxns; /* Interface funcs */
    Ptr          params; /* Setup parameters */
    Ptr          object; /* Transport-specific object */
    Uint16       procId; /* Processor Id talked to */
} MSGQ_TransportObj;

```

## Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the MSGQ Manager Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

### Module Configuration Parameters

Name	Type	Default (Enum Options)
ENABLEMSGQ	Bool	false

## Description

The MSGQ module allows for the structured sending and receiving of variable length messages. This module can be used for homogeneous or heterogeneous multi-processor messaging. The MSGQ module with a substantially similar API is implemented in DSP/BIOS Link for certain TI general-purpose processors (GPPs), particularly those used in OMAP devices.

MSGQ provides more sophisticated messaging than other modules. It is typically used for complex situations such as multi-processor messaging. The following are key features of the MSGQ module:

- ❑ Writers and readers can be relocated to another processor with no runtime code changes.
- ❑ Timeouts are allowed when receiving messages.
- ❑ Readers can determine the writer and reply back.
- ❑ Receiving a message is deterministic when the timeout is zero.
- ❑ Sending a message is non-blocking.
- ❑ Messages can reside on any message queue.
- ❑ Supports zero-copy transfers.
- ❑ Can send and receive from HWIs, SWIs and TSKs.
- ❑ Notification mechanism is specified by application.
- ❑ Allows QoS (quality of service) on message buffer pools. For example, using specific buffer pools for specific message queues.

Messages are sent and received via a *message queue*. A reader is a thread that gets (reads) messages from a message queue. A writer is a thread that puts (writes) a message to a message queue. Each message queue has one reader and can have many writers. A thread may read from or write to multiple message queues.

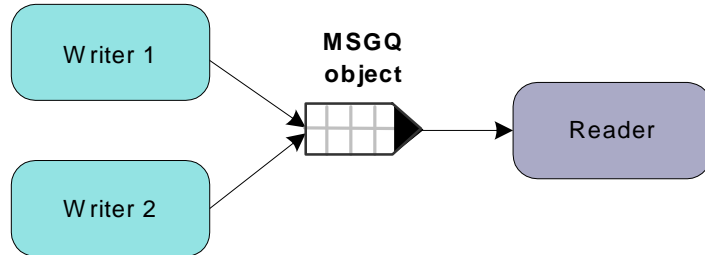


Figure 2-4. Writers and Reader of a Message Queue

Conceptually, the reader thread owns a message queue. The processor where the reader resides opens a message queue. Writer threads locate existing message queues to get access to them.

Messages must be allocated from the MSGQ module. Once a message is allocated, it can be sent on any message queue. Once a message is sent, the writer loses ownership of the message and should not attempt to modify the message. Once the reader receives the message, it owns the message. It may either free the message or re-use the message.

Messages in a message queue can be of variable length. The only requirement is that the first field in the definition of a message must be a `MSGQ_MsgHeader` element.

```
typedef struct MyMsg {
    MSGQ_MsgHeader header;
    ...
} MyMsg;
```

The MSGQ API uses the `MSGQ_MsgHeader` internally. Your application should not modify or directly access the fields in the `MSGQ_MsgHeader`.

The MSGQ module has the following components:

- ❑ **MSGQ API.** Applications call the MSGQ functions to open and use a message queue object to send and receive messages. For an overview, see “MSGQ APIs” on page 2-233. For details, see the sections on the individual APIs.

- ❑ **Allocators.** Messages sent via MSGQ must be allocated by an allocator. The allocator determines where and how the memory for the message is allocated. For more about allocators, see the *DSP/BIOS User's Guide* (SPRU423F).
- ❑ **Transports.** Transports are responsible for locating and sending messages with other processors. For more about transports, see the *DSP/BIOS User's Guide* (SPRU423F).

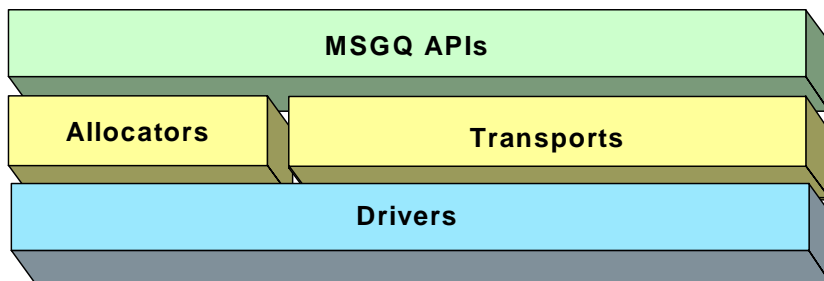


Figure 2-5. Components of the MSGQ Architecture

For more about using the MSGQ module—including information about multi-processor issues and a comparison of data transfer modules—see the *DSP/BIOS User's Guide* (SPRU423F).

## MSGQ APIs

The MSGQ APIs are used to open and close message queues and to send and receive messages. The MSGQ APIs shield the application from having to contain any knowledge about transports and allocators.

The following figure shows the call sequence of the main MSGQ functions:

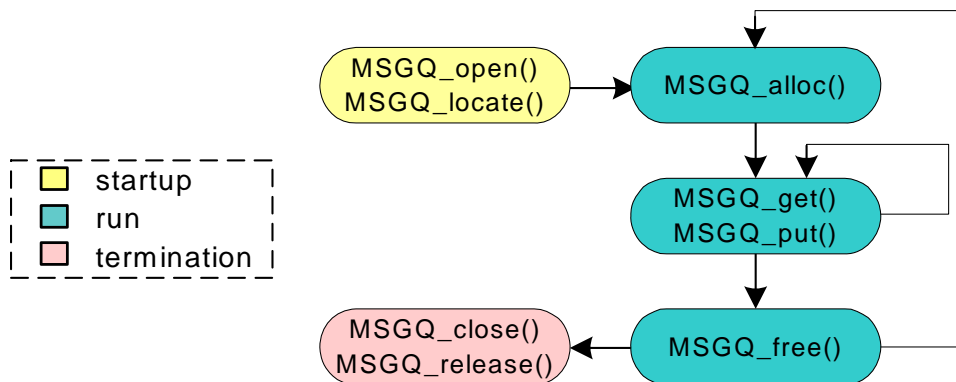


Figure 2-6. MSGQ Function Calling Sequence

The reader calls the following APIs:

- ❑ MSGQ\_open
- ❑ MSGQ\_get
- ❑ MSGQ\_free
- ❑ MSGQ\_close

A writer calls the following APIs:

- ❑ MSGQ\_locate or MSGQ\_locateAsync
- ❑ MSGQ\_alloc
- ❑ MSGQ\_put
- ❑ MSGQ\_release

Wherever possible, the MSGQ APIs have been written to have a deterministic execution time. This allows application designers to be certain that messaging will not consume an unknown number of cycles.

In addition, the MSGQ functions support use of message queues from all types of DSP/BIOS threads: HWIs, SWIs, and TSKs. That is, calls that may be synchronous (blocking) have an asynchronous (non-blocking) alternative.

## Static Configuration

In order to use the MSGQ module and the allocators it depends upon, you must statically configure the following:

- ❑ ENABLEMSGQ property of the MSGQ module using Tconf (see “MSGQ Manager Properties” on page 2-238)
- ❑ MSGQ\_config variable in application code (see below)
- ❑ PROCID property of the GBL module using Tconf (see “GBL Module Properties” on page 2-109)
- ❑ ENABLEPOOL property of the POOL module using Tconf (see “POOL Manager Properties” on page 2-289)
- ❑ POOL\_config variable in application code (see “Static Configuration” on page 2-286)

An application must provide a filled in MSGQ\_config variable in order to use the MSGQ module.

```
MSGQ_Config MSGQ_config;
```

The MSGQ\_Config type has the following structure:

```

typedef struct MSGQ_Config {
    MSGQ_Obj      *msgqQueues;      /* Array of message queue handles */
    MSGQ_TransportObj *transports;  /* Array of transports */
    Uint16        numMsgqQueues;    /* Number of message queue handles*/
    Uint16        numProcessors;    /* Number of processors */
    Uint16        startUninitialized; /* First msgq to init */
    MSGQ_Queue    errorQueue;      /* Receives async transport errors*/
    Uint16        errorPoolId;     /* Alloc error msgs from poolId */
} MSGQ_Config;

```

The fields in the MSGQ\_Config structure are described in the following table:

Field	Type	Description
msgqQueues	MSGQ_Obj *	Array of message queue objects. The fields of each object do not need to be initialized.
transports	MSGQ_TransportObj *	Array of transport objects. The fields of each object must be initialized.
numMsgqQueues	Uint16	Length of the msgqQueues array.
numProcessors	Uint16	Length of the transports array.
startUninitialized	Uint16	Index of the first message queue to initialize in the msgq-Queue array. This should be set to 0.
errorQueue	MSGQ_Queue	Message queue to receive transport errors. Initialize to MSGQ_INVALIDMSGQ.
errorPoolId	Uint16	Allocator to allocate transport errors. Initialize to POOL_INVALIDID.

Internally, MSGQ references its configuration via the MSGQ\_config variable. If the MSGQ module is enabled (via Tconf) but the application does not provide the MSGQ\_config variable, the application cannot be linked successfully.

In the MSGQ\_Config structure, an array of MSGQ\_TransportObj items defines transport objects with the following structure:

```

typedef struct MSGQ_TransportObj {
    MSGQ_MqtInit  initFxn;      /* Transport init func */
    MSGQ_TransportFxn *fxns; /* Interface funcs */
    Ptr           params;      /* Setup parameters */
    Ptr           object;      /* Transport-specific object */
    Uint16        procId;     /* Processor Id talked to */
} MSGQ_TransportObj;

```

The following table describes the fields in the MSGQ\_TransportObj structure:

Field	Type	Description
initFxn	MSGQ_MqtlNit	Initialization function for this transport. This function is called during DSP/BIOS startup. More explicitly it is called before main().
fxns	MSGQ_TransportFxn *	Pointer to the transport's interface functions.
params	Ptr	Pointer to the transport's parameters. This field is transport-specific. Please see documentation provided with your transport for a description of this field.
info	Ptr	State information needed by the transport. This field is initialized and managed by the transport. Refer to the specific transport implementation to determine how to use this field
proclD	Uint16	Numeric ID of the processor that this transport communicates with. The current processor must have a proclD field that matches the GBL.PROCID property.

If no parameter structure is specified (that is, NULL is used) for the MSGQ\_TransportObj, the transport uses its default parameters.

The order of the transports array is by processor. The first entry communicates with processor 0, the next entry with processor 1, and so on. On processor n, the nth entry in the transport array should be MSGQ\_NOTTRANSPORT, since there is no transport to itself. The following example shows a configuration for a single-processor application (that is, processor 0). Note that the 0th entry is MSGQ\_NOTTRANSPORT

```
#define NUMMSGQUEUES 4 /* # of local message queues*/
#define NUMPROCESSORS 1 /* Single processor system */

static MSGQ_Obj      msgQueues [NUMMSGQUEUES] ;
static MSGQ_TransportObj transports [NUMPROCESSOR] =
                    {MSGQ_NOTTRANSPORT};

MSGQ_Config MSGQ_config = {
    msgQueues,
    transports,
    NUMMSGQUEUES,
    NUMPROCESSORS,
    0,
    MSGQ_INVALIDMSGQ,
    POOL_INVALIDID
};
```



## Managing Transports at Run-Time

As described in the previous section, MSGQ uses an array of transports of type MSGQ\_TransportObj in the MSGQ\_config variable. This array is processor ID based. For example, MSGQ\_config->transports[0] is the transport to processor 0. Therefore, if a single binary is used on multiple processors, the array must be changed at run-time.

As with the GBL\_setProclD API, the transports array can be managed in the User Init Function (see GBL Module Properties). DSP/BIOS only uses MSGQ\_config and the transports array after the User Init Function returns.

There are several ways to manage the transports array. Two common ways are as follows:

- ❑ **Create a static two-dimensional transports array and select the correct one.** Assume a single image will be used for two processors (proclD 0 and 1) in a system with NUMPROCESSORS (3 in this example) processors. The transports array in the single image might look like this:

```
MSGQ_TransportObj transports[2][NUMPROCESSORS] =
{ { MSGQ_NOTRANSPORT, // proc 0 talk to proc 0
  { ... }, // proc 0 talk to proc 1
  { ... }, // proc 0 talk to proc 2
},
  { { ... }, // proc 1 talk to proc 0
    MSGQ_NOTRANSPORT, // proc 1 talk to proc 1
    { ... }, // proc 1 talk to proc 2
  }
}
```

In the User Init Function, the application would call GBL\_setProclD with the correct processor ID. Then it would assign the correct transport array to MSGQ\_config. For example, for processor 1, it would do the following:

```
MSGQ_config.transports = transports[1];
```

Note that this approach does not scale well as the number of processors in the system increases.

- ❑ **Fill in the transports array in the User Init Function.** In the User Init Function, you can fill in the contents of the transports array. You would still statically define a 1-dimensional transports array as follows:

```
MSGQ_TransportObj transports[NUMPROCESSORS];
```

This array would not be initialized. The initialization would occur in the User Init Function. For example on processor 1, it would fill in the transports array as follows.



**MSGQ\_alloc***Allocate a message***C Interface**

**Syntax**                    `status = MSGQ_alloc(poolId, msg, size);`

**Parameters**                `UInt16        poolId;    /* allocate the message from this allocator */`  
                              `MSGQ_Msg *msg;   /* pointer to the returned message */`  
                              `UInt16        size;       /* size of the requested message */`

**Return Value**              `Int            status;    /* status */`

**Reentrant**                 `yes`

**Description**              `MSGQ_alloc` returns a message from the specified allocator. The size is in minimum addressable data units (MADUs).

This function is performed by a writer. This call is non-blocking and can be called from a HWI, SWI or TSK.

All messages must be allocated from an allocator. Once a message is allocated it can be sent. Once a message is received, it must either be freed or re-used.

The `poolId` must correspond to one of the allocators specified by the `allocators` field of the `POOL_Config` structure specified by the application. (See "Static Configuration" on page 2-286.)

If a message is allocated, `SYS_OK` is returned. Otherwise, `SYS_EINVAL` is returned if the `poolId` is invalid, and `SYS_EALLOC` is returned if no memory is available to meet the request.

**Constraints and Calling Context**

- ❑ All message definitions must have `MSGQ_MsgHeader` as its first field. For example:

```
struct MyMsg {
    MSGQ_MsgHeader header; /* Required field */
    ...                    /* User fields */
}
```

**Example**

```
/* Allocate a message */
status = MSGQ_alloc(STATICPOOLID, (MSGQ_Msg *)&msg,
    sizeof(MyMsg));
if (status != SYS_OK) {
    SYS_abort("Failed to allocate a message");
}
```

**See Also**                    `MSGQ_free`

**MSGQ\_close***Close a message queue***C Interface****Syntax**                    `status = MSGQ_close(msgqQueue);`**Parameters**                `MSGQ_Queue    msgqQueue;    /* Message queue to close */`**Return Value**             `Int                status;            /* status */`**Reentrant**                 `yes`**Description**             `MSGQ_close` closes a message queue. If any messages are in the message queue, they are deleted.

This function is performed by the reader.

Threads that have located (with `MSGQ_locate` or `MSGQ_locateAsync`) the message queue being closed are not notified about the closure.

If successful, this function returns `SYS_OK`.

**Constraints and Calling Context**

- ❑ The message queue must have been returned from `MSGQ_open`.

**See Also**                    `MSGQ_open`

**MSGQ\_count***Return the number of messages in a message queue***C Interface**

**Syntax** `status = MSGQ_count(msgqQueue, count);`

**Parameters** `MSGQ_Queue msgqQueue; /* Message queue to count */`  
`Uns *count; /* Pointer to returned count */`

**Return Value** `Int status; /* status */`

**Reentrant** yes

**Description** This API determines the number of messages in a specific message queue. Only the processor that opened the message queue should call this API to determine the number of messages in the reader's message queue. This API is not thread safe with MSGQ\_get when accessing the same message queue, so the caller of MSGQ\_count must prevent any calls to MSGQ\_get.

If successful, this function returns SYS\_OK.

**Constraints and Calling Context**

- ❑ The message queue must have been returned from a MSGQ\_open call.

**Example**

```
status = MSGQ_count(readerMsgQueue, &count);
if (status != SYS_OK) {
    return;
}
LOG_printf(&trace, "There are %d messages.", count);
```

**See Also** MSGQ\_open

**MSGQ\_free***Free a message***C Interface**

**Syntax**                    `status = MSGQ_free(msg);`

**Parameters**                `MSGQ_Msg msg;     /* Message to be freed */`

**Return Value**               `Int                status;   /* status */`

**Reentrant**                    `yes`

**Description**                `MSGQ_free` frees a message back to the allocator.

If successful, this function returns `SYS_OK`.

This call is non-blocking and can be called from a HWI, SWI or TSK.

**Constraints and Calling Context**

- ❑ The message must have been allocated via `MSGQ_alloc`.

**Example**

```
status = MSGQ_get(readerMsgQueue, (MSGQ_Msg *)msg,
                  SYS_FOREVER);
if (status != SYS_OK) {
    SYS_printf("MSGQ_get call failed.");
}
// process message

MSGQ_free(msg);
```

**See Also**                    `MSGQ_alloc`

**MSGQ\_get***Receive a message from the message queue***C Interface**

<b>Syntax</b>	<code>status = MSGQ_get(msgqQueue, msg, timeout);</code>		
<b>Parameters</b>	<code>MSGQ_Queue</code>	<code>msgqQueue;</code>	<code>/* Message queue */</code>
	<code>MSGQ_Msg</code>	<code>*msg;</code>	<code>/* Pointer to the returned message */</code>
	<code>Uns</code>	<code>timeout;</code>	<code>/* Duration to block if no message */</code>
<b>Return Value</b>	<code>Int</code>	<code>status;</code>	<code>/* status */</code>

**Reentrant** yes**Description** MSGQ\_get returns a message sent via MSGQ\_put. The order of retrieval is FIFO.

This function is performed by the reader. Once a message has been received, the reader is responsible for freeing or re-sending the message.

If no messages are present, the `pend()` function specified in the `MSGQ_Attrs` passed to `MSGQ_open` for this message queue is called. The `pend()` function blocks up to the timeout value (`SYS_FOREVER = forever`). The timeout units are system clock ticks.

This function is deterministic if timeout is zero. `MSGQ_get` can be called from a TSK with any timeout. It can be called from a HWI or SWI if the timeout is zero.

If successful, this function returns `SYS_OK`. Otherwise, `SYS_ETIMEOUT` is returned if the timeout expires before the message is received.

**Constraints and Calling Context**

- ❑ Only one reader of a message queue is allowed concurrently.
- ❑ The message queue must have been returned from a `MSGQ_open` call.

**Example**

```
status = MSGQ_get(readerMsgQueue, (MSGQ_Msg *)&msg, 0);
if (status != SYS_OK) {
    /* No messages to process */
    return;
}
```

**See Also**

MSGQ\_put  
MSGQ\_open

**MSGQ\_getAttrs***Returns the attributes of a message queue***C Interface**

**Syntax** `status = MSGQ_getAttrs(msgqQueue, attrs);`

**Parameters**

MSGQ_Queue	msgqQueue;	/* Message queue */
MSGQ_Attrs	*attrs;	/* Attributes of message queue */

**Return Value** `Int status /* status */`

**Reentrant** yes

**Description** MSGQ\_getAttrs fills in the attrs structure passed to it with the attributes of a local message queue. These attributes are set by MSGQ\_open.

The API returns SYS\_OK unless the message queue is not local (that is, it was opened on another processor). If the message queue is not local, the API returns SYS\_EINVAL and does not change the contents of the passed in attrs structure.

**Example**

```
status = MSGQ_getAttrs (msgqQueue, &attrs);
if (status != SYS_OK) {
    return;
}
notifyHandle = attrs.notifyHandle;
```

**Constraints and Calling Context**

- ❑ The message queue must have been returned from a MSGQ\_open call and must be valid.
- ❑ This function can be called from a HWI, SWI or TSK.

**See Also** MSGQ\_open



**MSGQ\_getDstQueue***Get destination message queue field in a message***C Interface**

**Syntax** MSGQ\_getDstQueue(msg, msgQueue);

**Parameters** MSGQ\_Msg msg; /\* Message \*/  
MSGQ\_Queue \*msgQueue; /\* Message queue \*/

**Return Value** Void

**Reentrant** yes

**Description** This API allows the application to determine the destination message queue of a message. This API is generally used by transports to determine the final destination of a message. This API can also be used by the application once the message is received.

This function can be called from a HWI, SWI or TSK.

**Constraints and Calling Context**

- ❑ The message must have been sent via MSGQ\_put.

**MSGQ\_getMsgId***Return the message ID from a message***C Interface**

**Syntax**                   msgId = MSGQ\_getMsgId(msg);

**Parameters**               MSGQ\_Msg msg;     /\* Message \*/

**Return Value**            Uint16        msgId;   /\* Message ID \*/

**Reentrant**                yes

**Description**            MSGQ\_getMsgId returns the message ID from a received message. This message ID is specified via the MSGQ\_setMsgId function.

This function can be called from a HWI, SWI or TSK.

**Example**                 /\* Make sure the message is the one expected \*/  
if (MSGQ\_getMsgId((MSGQ\_Msg)msg) != MESSAGEID) {  
    SYS\_abort("Unexpected message");  
}

**See Also**                MSGQ\_setMsgId

**MSGQ\_getMsgSize***Return the message size from a message***C Interface**

**Syntax**                   size = MSGQ\_getMsgSize(msg);

**Parameters**           MSGQ\_Msg msg;       /\* Message \*/

**Return Value**        Uint16        size;       /\* Message size \*/

**Reentrant**            yes

**Description**        MSGQ\_getMsgSize returns the size of the message buffer out of the received message. The size is in minimum addressable data units (MADUs).

This function can be used to determine if a message can be re-used.

This function can be called from a HWI, SWI or TSK.

**See Also**            MSGQ\_alloc

**MSGQ\_getSrcQueue***Extract the reply destination from a message***C Interface**

**Syntax** `status = MSGQ_getSrcQueue(msg, msgqQueue);`

**Parameters**

MSGQ_Msg	msg;	/* Received message */
MSGQ_Queue	*msgqQueue;	/* Message queue */

**Return Value** Int `status;` /\* status \*/

**Reentrant** yes

**Description**

Many times a receiver of a message wants to reply to the sender of the message (for example, to send an acknowledgement). When a valid msgqQueue is specified in MSGQ\_setSrcQueue, the receiver of the message can extract the message queue via MSGQ\_getSrcQueue.

This is basically the same as a MSGQ\_locate function without knowing the name of the message queue. This function can be used even if the queueName used with MSGQ\_open was NULL or non-unique.

Note: The msgqQueue may not be the sender's message queue handle. The sender is free to use any created message queue handle.

This function can be called from a HWI, SWI or TSK.

If successful, this function returns SYS\_OK.

**Example**

```
/* Get the handle and send the message back. */
status = MSGQ_getSrcQueue((MSGQ_Msg)msg, &replyQueue);
if (status != SYS_OK) {
    /* Free the message and abort */
    MSGQ_free((MSGQ_Msg)msg);
    SYS_abort("Failed to get handle from message");
}
status = MSGQ_put(replyQueue, (MSGQ_Msg)msg);
```

**See Also**

MSGQ\_getAttrs  
MSGQ\_setSrcQueue

---

**MSGQ\_isLocalQueue** *Return whether message queue is local or on other processor***C Interface**

**Syntax** `flag = MSGQ_isLocalQueue(msgqQueue);`

**Parameters** `MSGQ_Queue msgqQueue; /* Message queue */`

**Return Value** `Bool flag; /* status */`

**Reentrant** `yes`

**Description** This API determines whether the message queue is local (that is, opened on this processor) or remote (that is, opened on a different processor).  
  
If the message queue is local, the flag returned is TRUE. Otherwise, it is FALSE.

**Constraints and Calling Context**  This function can be called from a HWI, SWI or TSK.

**Example**

```
flag = MSGQ_isLocalQueue(readerMsgQueue);
if (flag == TRUE) {
    /* Message queue is local */
    return;
}
```

**See Also** `MSGQ_open`

**MSGQ\_locate***Synchronously find a message queue***C Interface**

**Syntax** `status = MSGQ_locate(queueName, msgqQueue, locateAttrs);`

**Parameters** `String queueName; /* Name of message queue to locate */`  
`MSGQ_Queue *msgqQueue; /* Return located message queue here */`  
`MSGQ_LocateAttrs *locateAttrs; /* Locate attributes */`

**Return Value** `Int status; /* status */`

**Reentrant** `yes`

**Description** The MSGQ\_locate function is used to locate an opened message queue. This function is synchronous (that is, it can block if timeout is non-zero).

This function is performed by a writer. The reader must have already called MSGQ\_open for this queueName.

MSGQ\_locate firsts searches the local message queues for a name match. If a match is found, that message queue is returned. If no match is found, the transports are queried one at a time. If a transport locates the queueName, that message queue is returned. If the transport does not locate the message queue, the next transport is queried. If no transport can locate the message queue, an error is returned.

In a multiple-processor environment, transports can block when they are queried if you call MSGQ\_locate. The timeout in the MSGQ\_LocateAttrs structure specifies the maximum time each transport can block. The default is SYS\_FOREVER (that is, each transport can block forever). Remember that if you specify 1000 clock ticks as the timeout, the total blocking time could be 1000 \* number of transports.

Note that timeout is not a fixed amount of time to wait. It is the maximum time each transport waits for a positive or negative response. For example, suppose your timeout is 1000, but the response (found or not found) comes back in 600 ticks. The transport returns the response then; it does not wait for another 400 ticks to recheck for a change.

If you do not want to allow blocking, call MSGQ\_locateAsync instead of MSGQ\_locate.

The locateAttrs parameter is of type MSGQ\_LocateAttrs. This type has the following structure:

```
typedef struct MSGQ_LocateAttrs {
    Uns          timeout;
} MSGQ_LocateAttrs;
```

The timeout is the maximum time a transport can block on a synchronous locate in system clock ticks. The default attributes are as follows:

```
MSGQ_LocateAttrs  MSGQ_LOCATEATTRS = {SYS_FOREVER};
```

If successful, this function returns SYS\_OK. Otherwise, it returns SYS\_ENOTFOUND to indicate that it could not locate the specified message queue.

### Constraints and Calling Context

- ❑ Cannot be called from main().
- ❑ Cannot be called in a SWI or HWI context.

### Example

```
status = MSGQ_locate("reader", &readerMsgQueue, NULL);
if (status != SYS_OK) {
    SYS_abort("Failed to locate reader message queue");
}
```

### See Also

MSGQ\_locateAsync  
MSGQ\_open

**MSGQ\_locateAsync***Asynchronously find a message queue***C Interface**

**Syntax** `status = MSGQ_locateAsync(queueName, replyQueue, locateAsyncAttrs);`

**Parameters** `String queueName; /* Name of message queue to locate */`  
`MSGQ_Queue replyQueue; /* Msgq to send locate message */`  
`MSGQ_LocateAsyncAttrs *locateAsyncAttrs; /* Locate attributes */`

**Return Value** `Int status; /* status */`

**Reentrant** `yes`

**Description** MSGQ\_locateAsync firsts searches the local message queues for a name match. If one is found, an asynchronous locate message is sent to the specified message queue (in the replyQueue parameter). If it is not, all transports are asked to start an asynchronous locate search. After all transports have been asked to start the search, the API returns.

If a transport locates the message queue, an asynchronous locate message is sent to the specified replyQueue. If no transport can locate the message queue, no message is sent.

This function is performed by a writer. The reader must have already called MSGQ\_open for this queueName. An asynchronous locate can be performed from a SWI or TSK. It cannot be performed in main().

The message ID for an asynchronous locate message is:

```
/* Asynchronous locate message ID */
#define MSGQ_ASYNCLOCATEMSGID 0xFF00
```

The MSGQ\_LocateAsyncAttrs structure has the following fields:

```
typedef struct MSGQ_LocateAsyncAttrs {
    Uint16 poolId;
    Arg arg;
} MSGQ_LocateAttrs;
```

The default attributes are as follows:

```
MSGQ_LocateAsyncAttrs MSGQ_LOCATEASYNCATTRS = {0, 0};
```

The locate message is allocated from the allocator specified by the locateAsyncAttrs->poolId field.

The locateAsyncAttrs->arg value is included in the asynchronous locate message. This field allows you to correlate requests with the responses.



Once the application receives an asynchronous locate message, it is responsible for freeing the message. The asynchronous locate message received by the replyQueue has the following structure:

```
typedef struct MSGQ_AsyncLocateMsg {
    MSGQ_MsgHeader  header;
    MSGQ_Queue      msgqQueue;
    Arg             arg;
} MSGQ_AsyncLocateMsg;
```

Field	Type	Description
header	MSGQ_MsgHeader	Required field for every message.
msgqQueue	MSGQ_Queue	Located message queue handle.
Arg	Arg	Value specified in MSGQ_LocateAttrs for this asynchronous locate.

This function returns SYS\_OK to indicate that an asynchronous locate was started. This status does not indicate whether or not the locate will be successful. The SYS\_EALLOC status is returned if the message could not be allocated.

### Constraints and Calling Context

- ❑ The allocator must be able to allocate an asynchronous locate message.
- ❑ Cannot be called in the context of main().

### Example

The following example shows an asynchronous locate performed in a task. Time spent blocking is dictated by the timeout specified in the MSGQ\_get call. (Error handling statements were omitted for brevity.)

```
status = MSGQ_open("myMsgQueue", &myQueue, &msgqAttrs);

locateAsyncAttrs          = MSGQ_LOCATEATTRS;
locateAsyncAttrs.poolId  = STATICPOOLID;

MSGQ_locateAsync("msgQ1", myQueue, &locateAsyncAttrs);
status = MSGQ_get(myQueue, &msg, SYS_FOREVER);
if (MSGQ_getMsgId((MSGQ_Msg)msg) ==
    MSGQ_ASYNCLOCATEMSGID) {
    readerQueue = msg->msgqQueue;
}
MSGQ_free((MSGQ_Msg)msg);
```

### See Also

MSGQ\_locate  
MSGQ\_free  
MSGQ\_open

**MSGQ\_open***Open a message queue***C Interface**

**Syntax**                    `status = MSGQ_open(queueName, msgqQueue, attrs);`

**Parameters**                `String                queueName; /* Unique name of the message queue */`  
                               `MSGQ_Queue        *msgqQueue; /* Pointer to returned message queue */`  
                               `MSGQ_Attrs        *attrs;        /* Attributes of the message queue */`

**Return Value**                `Int                    status;                /* status */`

**Reentrant**                    `yes`

**Description**                MSGQ\_open is the function to open a message queue. This function selects and returns a message queue from the array provided in the static configuration (that is, MSGQ\_config->msgqQueues).

This function is on the processor where the reader resides. The reader then uses this message queue to receive messages.

If successful, this function returns SYS\_OK. Otherwise, it returns SYS\_ENOTFOUND to indicate that no empty spot was available in the message queue array.

If the application will use MSGQ\_locate or MSGQ\_locateAsync to find this message queue, the queueName must be unique. If the application will never need to use the locate APIs, the queueName may be NULL or a non-unique name.

Instead of using a fixed notification mechanism, such as SEM\_pend and SEM\_post, the MSGQ notification mechanism is supplied in the attrs parameter, which is of type MSGQ\_Attrs. If attrs is NULL, the new message queue is assigned a default set of attributes. The structure for MSGQ\_Attrs is as follows:

```
typedef struct MSGQ_Attrs {
    Ptr                notifyHandle;
    MSGQ_Pend        pend;
    MSGQ_Post        post;
} MSGQ_Attrs;
```

The MSGQ\_Attrs fields are as follows:

Field	Type	Description
notifyHandle	Ptr	Handle to use in the pend() and post() functions.

---

Pend	MSGQ_Pend	Function pointer to a user-specified pend function.
Post	MSGQ_Post	Function pointer to a user-specified post function.

---

The default attributes are:

```
MSGQ_Attrs MSGQ_ATTRS = {
    NULL,                /* notifyHandle */
    (MSGQ_Pend)SYS_zero, /* NOP pend */
    FXN_F_nop           /* NOP post */
};
```

The following typedefs are provided by the MSGQ module to allow easier casting of the pend and post functions:

```
typedef Bool (*MSGQ_Pend)(Ptr notifyHandle, Uns timeout);
typedef Void (*MSGQ_Post)(Ptr notifyHandle);
```

The post() function you specify is always called within MSGQ\_put when a writer sends a message.

A reader calls MSGQ\_get to receive a message. If there is a message, it returns that message, and the pend() function is not called. The pend() function is only called if there are no messages to receive.

The pend() and post() functions must act in a binary manner. For instance, SEM\_pend and SEM\_post treat the semaphore as a counting semaphore instead of binary. So SEM\_pend and SEM\_post are an invalid pend/post pair. The following example, in which the reader calls MSGQ\_get with a timeout of SYS\_FOREVER, shows why:

- 1) A writer sends 10 messages, making the count 10 in the semaphore.
- 2) The reader then calls MSGQ\_get 10 times. Each call returns a message without calling the pend() function.
- 3) The reader then calls MSGQ\_get again. Since there are no messages, the pend() function is called. Since the semaphore count was 10, SEM\_pend returns TRUE immediately from the pend(). MSGQ would check for messages and there would still be none, so pend() would be called again. This would repeat 9 more times until the count was zero.

If the pend() function were binary (for example, a binary semaphore), the pend() function would be called at most two times in step 3.

So instead of using SEM\_pend and SEM\_post for synchronous (blocking) opens, you should use SEM\_pendBinary and SEM\_postBinary.

The following notification attributes could be used if the reader is a SWI function (which cannot block):

```
MSGQ_Attrs attrs = MSGQ_ATTRS; // default attributes
// leave attrs.pend as a NOP
attrs.notifyHandle = (Ptr)swiHandle;
attrs.post         = (MSGQ_Pend)SWI_post;
```

The following notification attributes could be used if the reader is a TSK function (which can block):

```
MSGQ_Attrs attrs = MSGQ_ATTRS; // default attributes
attrs.notifyHandle = (Ptr)semHandle;
attrs.pend         = (MSGQ_Pend)SEM_pendBinary;
attrs.post         = (MSGQ_Post)SEM_postBinary;
```

## Constraints and Calling Context

- ❑ The message queue returned is to be used by the caller of `MSGQ_get`. It should not be used by writers to that message queue (that is, callers of `MSGQ_put`). Writers should use the message queue returned by `MSGQ_locate`, `MSGQ_locateAsync`, or `MSGQ_getSrcQueue`.
- ❑ If a `post()` function is specified, the function must be non-blocking.
- ❑ If a `pend()` function is specified, the function must be non-blocking when timeout is zero.
- ❑ Each message queue must have a unique name if the application will use `MSGQ_locate` or `MSGQ_locateAsync`.
- ❑ The `queueName` must be persistent. The `MSGQ` module references this name internally; that is, it does not make a copy of the name.

## Example

```
/* Open the reader message queue.
 * Using semaphores as notification mechanism */
msgqAttrs = MSGQ_ATTRS;
msgqAttrs.notifyHandle = (Ptr)readerSemHandle;
msgqAttrs.pend         = (MSGQ_Pend)SEM_pendBinary;
msgqAttrs.post         = (MSGQ_Post)SEM_postBinary;
status = MSGQ_open("reader", &readerMsgQueue,
                  &msgqAttrs);

if (status != SYS_OK) {
    SYS_abort("Failed to open the reader message queue");
}
```

## See Also

MSGQ\_close  
 MSGQ\_locate  
 MSGQ\_locateAsync  
 SEM\_pendBinary  
 SEM\_postBinary

**MSGQ\_put***Place a message on a message queue***C Interface**

<b>Syntax</b>	status = MSGQ_put(msgqQueue, msg);		
<b>Parameters</b>	MSGQ_Queue	msgqQueue;	/* Destination message queue */
	MSGQ_Msg	msg;	/* Message */
<b>Return Value</b>	Int	status;	/* status */

**Reentrant** yes**Description** MSGQ\_put places a message into the specified message queue.

This function is performed by a writer. This function is non-blocking, and can be called from a HWI, SWI or TSK.

The post() function for the destination message queue is called as part of the MSGQ\_put. The post() function is specified MSGQ\_open call in the MSGQ\_Attrs parameter.

If successful, this function returns SYS\_OK. Otherwise, it may return an error code returned by the transport.

There are several features available when sending a message.

- ❑ A msgId passed to MSGQ\_setMsgId can be used to indicate the type of message it is. Such a type is completely application-specific, except for IDs defined for MSGQ\_setMsgId. The reader of a message can use MSGQ\_getMsgId to get the ID from the message.
- ❑ The source message queue parameter to MSGQ\_setSrcQueue allows the sender of the message to specify a source message queue. The receiver of the message can use MSGQ\_getSrcQueue to extract the embedded message queue from the message. A client/server application might use this mechanism because it allows the server to reply to a message without first locating the sender. For example, each client would have its own message queue that it specifies as the source message queue when it sends a message to the server. The server can use MSGQ\_getSrcQueue to get the message queue to reply back to.

If MSGQ\_put returns an error, the user still owns the message and is responsible for freeing the message (or re-sending it).

**Constraints and Calling Context**

- ❑ The msgqQueue must have been returned from MSGQ\_locate, MSGQ\_locateAsync or MSGQ\_getSrcQueue (or MSGQ\_open if the reader of the message queue wants to send themselves a message).

- ❑ If MSGQ\_put does not return SYS\_OK, the message is still owned by the caller and must either be freed or re-used.

**Example**

```
/* Send the message back. */
status = MSGQ_put(replyMsgQueue, (MSGQ_Msg)msg);
if (status != SYS_OK) {
    /* Need to free the message */
    MSGQ_free((MSGQ_Msg)msg);
    SYS_abort("Failed to send the message");
}
```

**See Also**

MSGQ\_get  
MSGQ\_open  
MSGQ\_setMsgId  
MSGQ\_getMsgId  
MSGQ\_setSrcQueue  
MSGQ\_getSrcQueue

**MSGQ\_release***Release a located message queue***C Interface**

**Syntax**                    `status = MSGQ_release(msgqQueue);`

**Parameters**                `MSGQ_Queue    msgqQueue;    /* Message queue to release */`

**Return Value**             `Int                status;            /* status */`

**Reentrant**                 `yes`

**Description**              This function releases a located message queue. That is, it releases a message queue returned from `MSGQ_locate` or `MSGQ_locateAsync`.

This function is performed by a writer.

If successful, this function returns `SYS_OK`. Otherwise, it may return an error code returned by the transport.

**Constraints and Calling Context**             The handle must have been returned from `MSGQ_locate` or `MSGQ_locateAsync`.

**See Also**                    `MSGQ_locate`  
`MSGQ_locateAsync`

**MSGQ\_setErrorHandler** *Set up handling of internal MSGQ errors***C Interface**

**Syntax**                    `status = MSGQ_setErrorHandler(errorQueue, poolId);`

**Parameters**                `MSGQ_Queue errorQueue; /* Message queue to receive errors */`  
                               `UInt16        poolId;        /* Allocator to allocate error messages */`

**Return Value**             `Int            status;        /* status */`

**Reentrant**                 `yes`

**Description**             Asynchronous errors that need to be communicated to the application may occur in a transport. If an application calls `MSGQ_setErrorHandler`, all asynchronous errors are then sent to the message queue specified.

The specified message queue receives asynchronous error messages (if they occur) via `MSGQ_get`.

`poolId` specifies the allocator the transport should use to allocate error messages. If the transports cannot allocate a message, no action is performed.

If this function is not called or if `errorHandler` is set to `MSGQ_INVALIDMSGQ`, no error messages will be allocated and sent.

This function can be called multiple times with only the last handler being active.

If successful, this function returns `SYS_OK`.

The message ID for an asynchronous error message is:

```
/* Asynchronous error message ID */
#define MSGQ_ASYNCERRORMSGID 0xFF01
```

The following is the structure for an asynchronous error message:

```
typedef struct MSGQ_AsyncErrorMsg {
    MSGQ_MsgHeader header;
    MSGQ_MqtError  errorType;
    UInt16         mqtId;
    UInt16         parameter;
} MSGQ_AsyncErrorMsg;
```



The following table describes the fields in the MSGQ\_AsyncErrorMsg structure:

Field	Type	Description
header	MSGQ_MsgHeader	Required field for every message
errorType	MSGQ_MqtError	Error ID
mqtId	Uint16	ID of the transport that sent the error message
parameter	Uint16	Error-specific field

The following table lists the valid errorType values and the meanings of their arg fields:

errorType	mqtId	parameter
MSGQ_MQTERRorexIT	ID of the transport that is exiting.	Not used.
MSGQ_MQTFAILEDPUT	ID of the transport that failed to send a message.	ID of destination queue. The parameter is 16 bits, so only the lower 16 bits of the msgQueue is logged. The top 16 bits of the msgQueue contain the destination processor ID, which is also the mqtId. You can OR the mqtId shifted over by 16 bits with the parameter to get the full destination msgQueue.
MSGQ_MQTERRORINTERNAL	Generic internal error.	Transport defined.
MSGQ_MQTERRORPHYSICAL	Problem with the physical link.	Transport defined.
MSGQ_MQTERRORALLOC	Transport could not allocate memory.	Size of the requested memory.

MSGQ\_open  
MSGQ\_get

**MSGQ\_setMsgId***Set the message ID in a message***C Interface**

**Syntax**                   MSGQ\_setMsgId(msg, msgId);

**Parameters**               MSGQ\_MSG     msg;     /\* Message \*/  
                   uint16     msgId;   /\* Message id \*/

**Return Value**            Void

**Reentrant**                yes

**Description**            Inside each message is a message id field. This API sets this field. The value of msgId is application-specific. MSGQ\_getMsgId can be used to extract this field from a message.

When a message is allocated, the value of this field is MSGQ\_INVALIDMSGID. When MSGQ\_setMsgId is called, it updates the field accordingly. This API can be called multiple times on a message.

If a message is sent to another processor, the message Id field is converted by the transports accordingly (for example, endian conversion is performed).

The message IDs used when sending messages are application-specific. They can have any value except values in the following ranges:

- Reserved for the MSGQ module messages: 0xFF00 - 0xFF7F
- Reserved for internal transport usage: 0xFF80 - 0xFFFE
- Used to signify an invalid message ID: 0xFFFF

The following table lists the message IDs currently used by the MSGQ module.

Constant Defined in msgq.h	Value	Description
MSGQ_ASYNCLOCATEMSGID	0xFF00	Used to denote an asynchronous locate message.
MSGQ_ASYNCERRORMSGID	0xFF01	Used to denote an asynchronous transport error.
MSGQ_INVALIDMSGID	0xFFFF	Used as initial value when message is allocated.

**Constraints and Calling Context**            Message must have been allocated originally from MSGQ\_alloc.

**Example**

```
/* Fill in the message */
msg->sequenceNumber = 0;
MSGQ_setMsgId((MSGQ_Msg)msg, MESSAGEID);

/* Send the message */
status = MSGQ_put(readerMsgQueue, (MSGQ_Msg)msg);
    if (status != SYS_OK) {
        SYS_abort("Failed to send the message");
    }
```

**See Also**

MSGQ\_getMsgId  
MSGQ\_setErrorHandler

**MSGQ\_setSrcQueue***Set the reply destination in a message***C Interface****Syntax** MSGQ\_setSrcQueue(msg, msgQueue);**Parameters** MSGQ\_MSG msg; /\* Message \*/  
MSGQ\_Queue msgQueue; /\* Message queue \*/**Return Value** Void**Reentrant** yes**Description**

This API allows the sender to specify a message queue that the receiver of the message can reply back to (via MSGQ\_getSrcQueue). The msgQueue must have been returned by MSGQ\_open.

Inside each message is a source message queue field. When a message is allocated, the value of this field is MSGQ\_INVALIDMSGQ. When this API is called, it updates the field accordingly. This API can be called multiple times on a message.

If a message is sent to another processor, the source message queue field is managed by the transports accordingly.

**Constraints and Calling Context**

- ❑ Message must have been allocated originally from MSGQ\_alloc.
- ❑ msgQueue must have been returned from MSGQ\_open.

**Example**

```
/* Fill in the message */  
msg->sequenceNumber = 0;  
MSGQ_setSrcQueue((MSGQ_Msg)msg, writerMsgQueue);  
  
/* Send the message */  
status = MSGQ_put(readerMsgQueue, (MSGQ_Msg)msg);  
    if (status != SYS_OK) {  
        SYS_abort("Failed to send the message");  
    }  
}
```

**See Also**

MSGQ\_getSrcQueue

## 2.17 PIP Module

---

**Important Note:** The PIP module is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

The PIP module is the buffered pipe manager.

### Functions

- ❑ **PIP\_alloc.** Get an empty frame from the pipe.
- ❑ **PIP\_free.** Recycle a frame back to the pipe.
- ❑ **PIP\_get.** Get a full frame from the pipe.
- ❑ **PIP\_getReaderAddr.** Get the value of the readerAddr pointer of the pipe.
- ❑ **PIP\_getReaderNumFrames.** Get the number of pipe frames available for reading.
- ❑ **PIP\_getReaderSize.** Get the number of words of data in a pipe frame.
- ❑ **PIP\_getWriterAddr.** Get the value of the writerAddr pointer of the pipe.
- ❑ **PIP\_getWriterNumFrames.** Get the number of pipe frames available to write to.
- ❑ **PIP\_getWriterSize.** Get the number of words that can be written to a pipe frame.
- ❑ **PIP\_peek.** Get the pipe frame size and address without actually claiming the pipe frame.
- ❑ **PIP\_put.** Put a full frame into the pipe.
- ❑ **PIP\_reset.** Reset all fields of a pipe object to their original values.
- ❑ **PIP\_setWriterSize.** Set the number of valid words written to a pipe frame.

### PIP\_Obj Structure Members

- ❑ **Ptr readerAddr.** Pointer to the address to begin reading from after calling PIP\_get.
- ❑ **Uns readerSize.** Number of words of data in the frame read with PIP\_get.
- ❑ **Uns readerNumFrames.** Number of frames available to be read.
- ❑ **Ptr writerAddr.** Pointer to the address to begin writing to after calling PIP\_alloc.

## Configuration Properties

- ❑ **Uns writerSize.** Number of words available in the frame allocated with PIP\_alloc.
- ❑ **Uns writerNumFrames.** Number of frames available to be written to.

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the PIP Manager Properties and PIP Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
bufSeg	Reference	prog.get("DARAM")
bufAlign	Int16	1
frameSize	Int16	8
numFrames	Int16	2
monitor	EnumString	"reader" ("writer", "none")
notifyWriterFxn	Extern	prog.extern("FXN_F_nop")
notifyWriterArg0	Arg	0
notifyWriterArg1	Arg	0
notifyReaderFxn	Extern	prog.extern("FXN_F_nop")
notifyReaderArg0	Arg	0
notifyReaderArg1	Arg	0

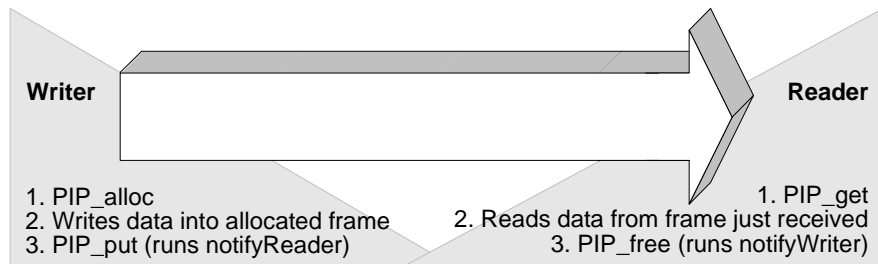
## Description

The PIP module manages data pipes, which are used to buffer streams of input and output data. These data pipes provide a consistent software data structure you can use to drive I/O between the DSP device and all kinds of real-time peripheral devices.

Each pipe object maintains a buffer divided into a fixed number of fixed length frames, specified by the numframes and framesize properties. All I/O operations on a pipe deal with one frame at a time; although each frame has a fixed length, the application can put a variable amount of data in each frame up to the length of the frame.

A pipe has two ends, as shown in Figure 2-7. The writer end (also called the producer) is where your program writes frames of data. The reader end (also called the consumer) is where your program reads frames of data

*Figure 2-7. Pipe Schematic*



Internally, pipes are implemented as a circular list; frames are reused at the writer end of the pipe after PIP\_free releases them.

The notifyReader and notifyWriter functions are called from the context of the code that calls PIP\_put or PIP\_free. These functions can be written in C or assembly. To avoid problems with recursion, the notifyReader and notifyWriter functions normally should not directly call any of the PIP module functions for the same pipe. Instead, they should post a SWI that uses the PIP module functions. However, PIP calls may be made from the notifyReader and notifyWriter functions if the functions have been protected against re-entrancy.





The following properties can be set for a PIP object in the PIP Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **comment.** Type a comment to identify this PIP object.  
 Tconf Name: comment Type: String  
 Example: `myPip.comment = "my PIP";`
- ❑ **bufseg.** The memory segment that the buffer is allocated within; all frames are allocated from a single contiguous buffer (of size framesize x numframes).  
 Tconf Name: bufSeg Type: Reference  
 Example: `myPip.bufSeg = prog.get("myMEM");`
- ❑ **bufalign.** The alignment (in words) of the buffer allocated within the specified memory segment.  
 Tconf Name: bufAlign Type: Int16  
 Example: `myPip.bufAlign = 1;`
- ❑ **framesize.** The length of each frame (in words)  
 Tconf Name: frameSize Type: Int16  
 Example: `myPip.frameSize = 8;`
- ❑ **numframes.** The number of frames  
 Tconf Name: numFrames Type: Int16  
 Example: `myPip.numFrames = 2;`
- ❑ **monitor.** The end of the pipe to be monitored by a hidden STS object. Can be set to reader, writer, or nothing. In the Statistics View analysis tool, your choice determines whether the STS display for this pipe shows a count of the number of frames handled at the reader or writer end of the pipe.  
 Tconf Name: monitor Type: EnumString  
 Options: "reader", "writer", "none"  
 Example: `myPip.monitor = "reader";`
- ❑ **notifyWriter.** The function to execute when a frame of free space is available. This function should notify (for example, by calling SWI\_andnHook) the object that writes to this pipe that an empty frame is available.

The notifyWriter function is performed as part of the thread that called PIP\_free or PIP\_alloc. To avoid problems with recursion, the

notifyWriter function should not directly call any of the PIP module functions for the same pipe.

Tconf Name: notifyWriterFxn Type: Extern

Example: `myPip.notifyWriterFxn =  
          prog.extern("writerFxn");`

- ❑ **nwarg0, nwarg1.** Two Arg type arguments for the notifyWriter function.

Tconf Name: notifyWriterArg0 Type: Arg

Tconf Name: notifyWriterArg1 Type: Arg

Example: `myPip.notifyWriterArg0 = 0;`

- ❑ **notifyReader.** The function to execute when a frame of data is available. This function should notify (for example, by calling SWI\_andnHook) the object that reads from this pipe that a full frame is ready to be processed.

The notifyReader function is performed as part of the thread that called PIP\_put or PIP\_get. To avoid problems with recursion, the notifyReader function should not directly call any of the PIP module functions for the same pipe.

Tconf Name: notifyReaderFxn Type: Extern

Example: `myPip.notifyReaderFxn =  
          prog.extern("readerFxn");`

- ❑ **nrarg0, nrarg1.** Two Arg type arguments for the notifyReader function.

Tconf Name: notifyReaderArg0 Type: Arg

Tconf Name: notifyReaderArg1 Type: Arg

Example: `myPip.notifyReaderArg0 = 0;`

**PIP\_alloc***Allocate an empty frame from a pipe*


---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface**

<b>Syntax</b>	PIP_alloc(pipe);
<b>Parameters</b>	PIP_Handle pipe; /* pipe object handle */
<b>Return Value</b>	Void
<b>Reentrant</b>	no
<b>Description</b>	PIP_alloc allocates an empty frame from the pipe you specify. You can write to this frame and then use PIP_put to put the frame into the pipe.

If empty frames are available after PIP\_alloc allocates a frame, PIP\_alloc runs the function specified by the notifyWriter property of the PIP object. This function should notify (for example, by calling SWI\_andnHook) the object that writes to this pipe that an empty frame is available. The notifyWriter function is performed as part of the thread that calls PIP\_free or PIP\_alloc. To avoid problems with recursion, the notifyWriter function should not directly call any PIP module functions for the same pipe.

**Constraints and Calling Context**

- ❑ Before calling PIP\_alloc, a function should check the writerNumFrames member of the PIP\_Obj structure by calling PIP\_getWriterNumFrames to make sure it is greater than 0 (that is, at least one empty frame is available).
- ❑ PIP\_alloc can only be called one time before calling PIP\_put. You cannot operate on two frames from the same pipe simultaneously.

**Example**

```
Void copy(HST_Obj *input, HST_Obj *output)
{
    PIP_Obj      *in, *out;
    Uns          *src, *dst;
    Uns          size;

    in = HST_getpipe(input);
    out = HST_getpipe(output);

    if (PIP_getReaderNumFrames(in) == 0 ||
        PIP_getWriterNumFrames(out) == 0) {
        error;
    }
}
```

```
    /* get input data and allocate output frame */
    PIP_get(in);
    PIP_alloc(out);

    /* copy input data to output frame */
    src = PIP_getReaderAddr(in);
    dst = PIP_getWriterAddr(out);
    size = PIP_getReaderSize(in);
    PIP_setWriterSize(out, size);
    for (; size > 0; size--) {
        *dst++ = *src++;
    }

    /* output copied data and free input frame */
    PIP_put(out);
    PIP_free(in);
}
```

The example for `HST_getpipe`, page 2–147, also uses a pipe with host channel objects.

**See Also**

PIP\_free  
PIP\_get  
PIP\_put  
HST\_getpipe

**PIP\_free***Recycle a frame that has been read to a pipe*


---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface**

<b>Syntax</b>	PIP_free(pipe);
<b>Parameters</b>	PIP_Handle pipe; /* pipe object handle */
<b>Return Value</b>	Void
<b>Reentrant</b>	no
<b>Description</b>	<p>PIP_free releases a frame after you have read the frame with PIP_get. The frame is recycled so that PIP_alloc can reuse it.</p> <p>After PIP_free releases the frame, it runs the function specified by the notifyWriter property of the PIP object. This function should notify (for example, by calling SWI_andnHook) the object that writes to this pipe that an empty frame is available. The notifyWriter function is performed as part of the thread that called PIP_free or PIP_alloc. To avoid problems with recursion, the notifyWriter function should not directly call any of the PIP module functions for the same pipe.</p>
<b>Constraints and Calling Context</b>	<ul style="list-style-type: none"> <li>❑ When called within an HWI, the code sequence calling PIP_free must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.</li> </ul>
<b>Example</b>	See the example for PIP_alloc, page 2–271. The example for HST_getpipe, page 2–147, also uses a pipe with host channel objects.
<b>See Also</b>	<ul style="list-style-type: none"> <li>PIP_alloc</li> <li>PIP_get</li> <li>PIP_put</li> <li>HST_getpipe</li> </ul>

**PIP\_get***Get a full frame from the pipe*


---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

PIP\_get(pipe);

**Parameters**

PIP\_Handle pipe; /\* pipe object handle \*/

**Return Value**

Void

**Reentrant**

no

**Description**

PIP\_get gets a frame from the pipe after some other function puts the frame into the pipe with PIP\_put.

If full frames are available after PIP\_get gets a frame, PIP\_get runs the function specified by the notifyReader property of the PIP object. This function should notify (for example, by calling SWI\_andnHook) the object that reads from this pipe that a full frame is available. The notifyReader function is performed as part of the thread that calls PIP\_get or PIP\_put. To avoid problems with recursion, the notifyReader function should not directly call any PIP module functions for the same pipe.

**Constraints and Calling Context**

- ❑ Before calling PIP\_get, a function should check the readerNumFrames member of the PIP\_Obj structure by calling PIP\_getReaderNumFrames to make sure it is greater than 0 (that is, at least one full frame is available).
- ❑ PIP\_get can only be called one time before calling PIP\_free. You cannot operate on two frames from the same pipe simultaneously.

**Example**

See the example for PIP\_alloc, page 2–271. The example for HST\_getpipe, page 2–147, also uses a pipe with host channel objects.

**See Also**

PIP\_alloc  
 PIP\_free  
 PIP\_put  
 HST\_getpipe

**PIP\_getReaderAddr***Get the value of the readerAddr pointer of the pipe*


---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

```
readerAddr = PIP_getReaderAddr(pipe);
```

**Parameters**

```
PIP_Handle pipe;    /* pipe object handle */
```

**Return Value**

```
Ptr          readerAddr
```

**Reentrant**

```
yes
```

**Description**

PIP\_getReaderAddr is a C function that returns the value of the readerAddr pointer of a pipe object. The readerAddr pointer is normally used following a call to PIP\_get, as the address to begin reading from.

**Example**

```
Void audio(PIP_Obj *in, PIP_Obj *out)
{
    Uns          *src, *dst;
    Uns          size;

    if (PIP_getReaderNumFrames(in) == 0 ||
        PIP_getWriterNumFrames(out) == 0) {
        error;
    }
    PIP_get(in);    /* get input data */
    PIP_alloc(out); /* allocate output buffer */

    /* copy input data to output buffer */
    src = PIP_getReaderAddr(in);
    dst = PIP_getWriterAddr(out);
    size = PIP_getReaderSize(in);
    PIP_setWriterSize(out, size);
    for (; size > 0; size--) {
        *dst++ = *src++;
    }

    /* output copied data and free input buffer */
    PIP_put(out);
    PIP_free(in);
}
```

**PIP\_getReaderNumFrames***Get the number of pipe frames available for reading*

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

**C Interface**

**Syntax** num = PIP\_getReaderNumFrames(pipe);

**Parameters** PIP\_Handle pipe; /\* pip object handle \*/

**Return Value** Uns num; /\* number of filled frames to be read \*/

**Reentrant** yes

**Description** PIP\_getReaderNumFrames is a C function that returns the value of the readerNumFrames element of a pipe object.

Before a function attempts to read from a pipe it should call PIP\_getReaderNumFrames to ensure at least one full frame is available.

**Example** See the example for PIP\_getReaderAddr, page 2–275.



**PIP\_getReaderSize**

*Get the number of words of data in a pipe frame*

---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

```
num = PIP_getReaderSize(pipe);
```

**Parameters**

```
PIP_Handle pipe;    /* pipe object handle*/
```

**Return Value**

```
Uns      num;    /* number of words to be read from filled frame */
```

**Reentrant**

yes

**Description**

PIP\_getReaderSize is a C function that returns the value of the readerSize element of a pipe object.

As a function reads from a pipe it should use PIP\_getReaderSize to determine the number of valid words of data in the pipe frame.

**Example**

See the example for PIP\_getReaderAddr, page 2–275.

**PIP\_getWriterAddr***Get the value of the writerAddr pointer of the pipe*

---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

```
writerAddr = PIP_getWriterAddr(pipe);
```

**Parameters**

```
PIP_Handle pipe;    /* pipe object handle */
```

**Return Value**

```
Ptr          writerAddr;
```

**Reentrant**

yes

**Description**

PIP\_getWriterAddr is a C function that returns the value of the writerAddr pointer of a pipe object.

The writerAddr pointer is normally used following a call to PIP\_alloc, as the address to begin writing to.

**Example**

See the example for PIP\_getReaderAddr, page 2–275.

**PIP\_getWriterNumFrames***Get number of pipe frames available to be written to*


---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

```
num = PIP_getWriterNumFrames(pipe);
```

**Parameters**

```
PIP_Handle pipe;    /* pipe object handle*/
```

**Return Value**

```
Uns      num;    /* number of empty frames to be written */
```

**Reentrant**

```
yes
```

**Description**

PIP\_getWriterNumFrames is a C function that returns the value of the writerNumFrames element of a pipe object.

Before a function attempts to write to a pipe, it should call PIP\_getWriterNumFrames to ensure at least one empty frame is available.

**Example**

See the example for PIP\_getReaderAddr, page 2–275.

**PIP\_getWriterSize**

*Get the number of words that can be written to a pipe frame*

---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

```
num = PIP_getWriterSize(pipe);
```

**Parameters**

```
PIP_Handle pipe;    /* pipe object handle*/
```

**Return Value**

```
Uns      num;    /* num of words to be written in empty frame */
```

**Reentrant**

```
yes
```

**Description**

PIP\_getWriterSize is a C function that returns the value of the writerSize element of a pipe object.

As a function writes to a pipe, it can use PIP\_getWriterSize to determine the maximum number words that can be written to a pipe frame.

**Example**

```
if (PIP_getWriterNumFrames(rxPipe) > 0) {  
    PIP_alloc(rxPipe);  
    DSS_rxPtr = PIP_getWriterAddr(rxPipe);  
    DSS_rxCnt = PIP_getWriterSize(rxPipe);  
}
```

**PIP\_peek**

*Get pipe frame size and address without actually claiming pipe frame*

---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

```
framesize = PIP_peek(pipe, addr, rw);
```

**Parameters**

```
PIP_Handle pipe;    /* pipe object handle */
Ptr        *addr;   /* address of variable with frame address */
Uns        rw;      /* flag to indicate the reader or writer side */
```

**Return Value**

```
Int        framesize; /* the frame size */
```

**Description**

PIP\_peek can be used before calling PIP\_alloc or PIP\_get to get the pipe frame size and address without actually claiming the pipe frame.

The pipe parameter is the pipe object handle, the addr parameter is the address of the variable that keeps the retrieved frame address, and the rw parameter is the flag that indicates what side of the pipe PIP\_peek is to operate on. If rw is PIP\_READER, then PIP\_peek operates on the reader side of the pipe. If rw is PIP\_WRITER, then PIP\_peek operates on the writer side of the pipe.

PIP\_getReaderNumFrames or PIP\_getWriterNumFrames can be called to ensure that a frame exists before calling PIP\_peek, although PIP\_peek returns -1 if no pipe frame exists.

PIP\_peek returns the frame size, or -1 if no pipe frames are available. If the return value of PIP\_peek in frame size is not -1, then \*addr is the location of the frame address.

**See Also**

```
PIP_alloc
PIP_free
PIP_get
PIP_put
PIP_reset
```

**PIP\_put***Put a full frame into the pipe*


---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

PIP\_put(pipe);

**Parameters**

PIP\_Handle pipe; /\* pipe object handle \*/

**Return Value**

Void

**Reentrant**

no

**Description**

PIP\_put puts a frame into a pipe after you have allocated the frame with PIP\_alloc and written data to the frame. The reader can then use PIP\_get to get a frame from the pipe.

After PIP\_put puts the frame into the pipe, it runs the function specified by the notifyReader property of the PIP object. This function should notify (for example, by calling SWI\_andnHook) the object that reads from this pipe that a full frame is ready to be processed. The notifyReader function is performed as part of the thread that called PIP\_get or PIP\_put. To avoid problems with recursion, the notifyReader function should not directly call any of the PIP module functions for the same pipe.

**Constraints and Calling Context**

- ❑ When called within an HWI, the code sequence calling PIP\_put must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

**Example**

See the example for PIP\_alloc, page 2–271. The example for HST\_getpipe, page 2–147, also uses a pipe with host channel objects.

**See Also**

PIP\_alloc  
 PIP\_free  
 PIP\_get  
 HST\_getpipe

**PIP\_reset***Reset all fields of a pipe object to their original values*


---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

PIP\_reset(pipe);

**Parameters**

PIP\_Handle pipe; /\* pipe object handle \*/

**Return Value**

Void

**Description**

PIP\_reset resets all fields of a pipe object to their original values.

The pipe parameter specifies the address of the pipe object that is to be reset.

**Constraints and Calling Context**

- ❑ PIP\_reset should not be called between the PIP\_alloc call and the PIP\_put call or between the PIP\_get call and the PIP\_free call.
- ❑ PIP\_reset should be called when interrupts are disabled to avoid the race condition.

**See Also**

PIP\_alloc  
 PIP\_free  
 PIP\_get  
 PIP\_peek  
 PIP\_put

**PIP\_setWriterSize***Set the number of valid words written to a pipe frame*

---

**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface****Syntax**

PIP\_setWriterSize(pipe, size);

**Parameters**PIP\_Handle pipe; /\* pipe object handle \*/  
Uns size; /\* size to be set \*/**Return Value**

Void

**Reentrant**

no

**Description**

PIP\_setWriterSize is a C function that sets the value of the writerSize element of a pipe object.

As a function writes to a pipe, it can use PIP\_setWriterSize to indicate the number of valid words being written to a pipe frame.

**Example**

See the example for PIP\_getReaderAddr, page 2–275.



## 2.18 POOL Module

The POOL module describes the interface that allocators must provide.

### Functions

None; this module describes an interface to be implemented by allocators

### Constants, Types, and Structures

```
POOL_Config POOL_config;

typedef struct POOL_Config {
    POOL_Obj *allocators; /* Array of allocators */
    Uint16    numAllocators; /* Num of allocators */
} POOL_Config;

typedef struct POOL_Obj {
    POOL_Init  initFxn; /* Allocator init function */
    POOL_Fxns *fxns; /* Interface functions */
    Ptr       params; /* Setup parameters */
    Ptr       object; /* Allocator's object */
} POOL_Obj, *POOL_Handle;
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the POOL Manager Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default (Enum Options)
ENABLEPOOL	Bool	false

### Description

The POOL module describes standard interface functions that allocators must provide. The allocator interface functions are called internally by the MSGQ module and not by user applications. A simple static allocator, called STATICPOOL, is provided with DSP/BIOS. Other allocators can be implemented by following the standard interface.

---

**Note:** This document does not discuss how to write an allocator. Information about designing allocators will be provided in a future document.

---

All messages sent via the MSGQ module must be allocated by an allocator. The allocator determines where and how the memory for the message is allocated.

An allocator is an instance of an implementation of the allocator interface. An application may instantiate one or more instances of an allocator.

An application can use multiple allocators. The purpose of having multiple allocators is to allow an application to regulate its message usage. For example, an application can allocate critical messages from one pool of fast on-chip memory and non-critical messages from another pool of slower external memory.

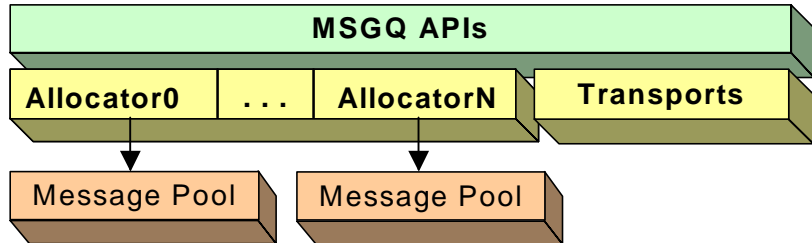


Figure 2-8. Allocators and Message Pools

### Static Configuration

In order to use an allocator and the POOL module, you must statically configure the following:

- ❑ ENABLEPOOL property of the POOL module using Tconf (see “POOL Manager Properties” on page 2-289)
- ❑ POOL\_config variable in application code (see below)

An application must provide a filled in POOL\_config variable if it uses one or more allocators.

```
POOL_Config POOL_config;
```

Where the POOL\_Config structure has the following structure:

```
typedef struct POOL_Config {
    POOL_Obj *allocators; /* Array of allocators */
    Uint16    numAllocators; /* Num of allocators */
} POOL_Config;
```

The fields in this structure are as follows:

Field	Type	Description
allocators	POOL_Obj	Array of allocator objects
numAllocators	Uint16	Number of allocators in the allocator array.

If the POOL module is enabled via Tconf and the application does not provide the POOL\_config variable, the application cannot be linked successfully.

The following is the POOL\_Obj structure:

```
typedef struct POOL_Obj {
    POOL_Init  initFxn; /* Allocator init function */
    POOL_Fxns *fxns;   /* Interface functions */
    Ptr        params; /* Setup parameters */
    Ptr        object; /* Allocator's object */
} POOL_Obj, *POOL_Handle;
```

The fields in the POOL\_Obj structure are as follows:

Field	Type	Description
initFxn	POOL_Init	Initialization function for this allocator. This function will be called during DSP/BIOS initialization. More explicitly it is called before main().
fxns	POOL_Fxns *	Pointer to the allocator's interface functions.
params	Ptr	Pointer to the allocator's parameters. This field is allocator-specific. Please see the documentation provided with your allocator for a description of this field.
object	Ptr	State information needed by the allocator. This field is initialized and managed by the allocator. See the allocator documentation to determine how to specify this field.

One allocator implementation (STATICPOOL) is shipped with DSP/BIOS. Additional allocator implementations can be created by application writers.

### STATICPOOL Allocator

The STATICPOOL allocator takes a user-specified buffer and allocates fixed-size messages from the buffer. The following are its configuration parameters:

```
typedef struct STATICPOOL_Params {
    Ptr        addr;
    size_t     length;
    size_t     bufferSize;
} STATICPOOL_Params;
```

The following table describes the fields in this structure:

Field	Type	Description
addr	Ptr	User supplied block of memory for allocating messages from. The address will be aligned on an 8 MADU boundary for correct structure alignment on all ISAs. If there is a chance the buffer is not aligned, allow at least 7 extra MADUs of space to allow room for the alignment. You can use the DATA_ALIGN pragma to force alignment yourself.
length	size_t	Size of the block of memory pointed to by addr.
bufferSize	size_t	Size of the buffers in the block of memory. The bufferSize must be a multiple of 8 to allow correct structure alignment.

The following figure shows how the fields in STATICPOOL\_Params define the layout of the buffer:

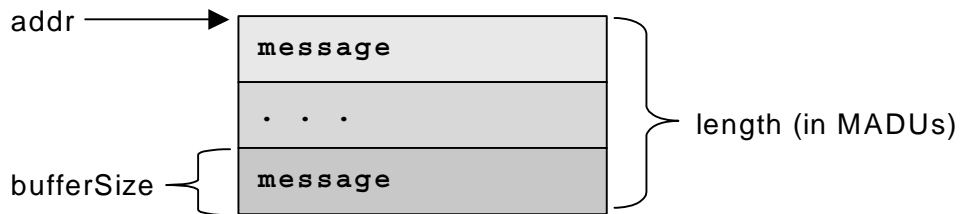


Figure 2-9. Buffer Layout as Defined by STATICPOOL\_Params

Since the STATICPOOL buffer is generally used in static systems, the application must provide the memory for the STATICPOOL\_Obj. So the object field of the POOL\_Obj must be set to STATICPOOL\_Obj instead of NULL.

The following is an example of an application that has two allocators (two instances of the STATICPOOL implementation).

```
#define NUMMSGS 8 /* Number of msgs per allocator */

/* Size of messages in the two allocators. Must be a
 * multiple of 8 as required by static allocator. */
#define MSGSIZE0 64
#define MSGSIZE1 128

enum { /* Allocator ID and number of allocators */
    MQASTATICID0 = 0,
    MQASTATICID1,
    NUMALLOCATORS
};
```

```

#pragma DATA_ALIGN(staticBuf0, 8) /* As required */
#pragma DATA_ALIGN(staticBuf1, 8) /* As required */
static Char staticBuf0[MSGSIZE0 * NUMMSGs];
static Char staticBuf1[MSGSIZE1 * NUMMSGs];

static MQASTATIC_Params poolParams0 = {staticBuf0,
    sizeof(staticBuf0), MSGSIZE0};
static MQASTATIC_Params poolParams1 = {staticBuf1,
    sizeof(staticBuf1), MSGSIZE1};

static STATICPOOL_Obj poolObj0, poolObj1;

static POOL_Obj allocators[NUMALLOCATORS] =
    {{STATICPOOL_init, (POOL_Fxns *)&STATICPOOL_FXNS,
    &poolParams0, &poolObj0}
    {{STATICPOOL_init, (POOL_Fxns *)&STATICPOOL_FXNS,
    &poolParams1, &poolObj1}}};

POOL_Config POOL_config=
    {allocators, NUMALLOCATORS};

```

## POOL Manager Properties

To configure the POOL manager, the POOL\_Config structure must be defined in the application code. See “Static Configuration” on page 2-286.

The following global property must also be set in order to use the POOL module:

- ❑ **Enable POOL Manager.** If ENABLEPOOL is TRUE, each allocator specified in the POOL\_config structure (see “Static Configuration” on page 2-286) is initialized and opened.

Tconf Name: ENABLEPOOL

Type: Bool

Example: bios.POOL.ENABLEPOOL = true;

## 2.19 PRD Module

The PRD module is the periodic function manager.

### Functions

- PRD\_getticks. Get the current tick count.
- PRD\_start. Arm a periodic function for one-time execution.
- PRD\_stop. Stop a periodic function from execution.
- PRD\_tick. Advance tick counter, dispatch periodic functions.

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the PRD Manager Properties and PRD Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")
USECLK	Bool	true
MICROSECONDS	Int16	1000.0

#### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
period	Int16	32767
mode	EnumString	"continuous" ("one-shot")
fxn	Extern	prog.extern("FXN_F_nop")
arg0	Arg	0
arg1	Arg	0
order	Int16	0

### Description

While some applications can schedule functions based on a real-time clock, many applications need to schedule functions based on I/O availability or some other programmatic event.

The PRD module allows you to create PRD objects that schedule periodic execution of program functions. The period can be driven by the CLK module or by calls to PRD\_tick whenever a specific event occurs.

There can be several PRD objects, but all are driven by the same period counter. Each PRD object can execute its functions at different intervals based on the period counter.

- ❑ **To schedule functions based on a real-time clock.** Set the clock interrupt rate you want to use in the CLK Object Properties. Set the "Use On-chip Clock (CLK)" property of the PRD Manager Properties to true. Set the frequency of execution (in number of clock interrupt ticks) in the period property for the individual period object.
- ❑ **To schedule functions based on I/O availability or some other event.** Set the "Use On-chip Clock (CLK)" property of the PRD Manager Properties to false. Set the frequency of execution (in number of ticks) in the period property for the individual period object. Your program should call PRD\_tick to increment the tick counter.

The function executed by a PRD object is statically defined in the configuration. PRD functions are called from the context of the function run by the PRD\_swi SWI object. PRD functions can be written in C or assembly and must follow the C calling conventions described in the compiler manual.

The PRD module uses a SWI object (called PRD\_swi by default) which itself is triggered on a periodic basis to manage execution of period objects. Normally, this SWI object should have the highest SWI priority to allow this SWI to be performed once per tick. This SWI is automatically created (or deleted) by the configuration if one or more (or no) PRD objects exist. The total time required to perform all PRD functions must be less than the number of microseconds between ticks. Any more lengthy processing should be scheduled as a separate SWI, TSK, or IDL thread.

See the *Code Composer Studio* online tutorial for an example that demonstrates the interaction between the PRD module and the SWI module.

When the PRD\_swi object runs its function, the following actions occur:

```
for ("Loop through period objects") {
    if ("time for a periodic function")
        "run that periodic function";
}
```

## PRD Manager Properties

The DSP/BIOS Periodic Function Manager allows the creation of an arbitrary number of objects that encapsulate a function, two arguments, and a period specifying the time between successive invocations of the function. The period is expressed in ticks, and a tick is defined as a single invocation of the PRD\_tick operation. The time between successive invocations of PRD\_tick defines the period represented by a tick.

The following global properties can be set for the PRD module in the PRD Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- Object Memory.** The memory segment containing the PRD objects.  
 Tconf Name: OBJMEMSEG Type: Reference  
 Example: `bios.PRD.OBJMEMSEG = prog.get("myMEM");`
- Use CLK Manager to drive PRD.** If this property is set to true, the on-device timer hardware (managed by the CLK Module) is used to advance the tick count; otherwise, the application must invoke PRD\_tick on a periodic basis. If the CLK module is used to drive PRDs, the ticks are equal to the low-resolution time increment rate.  
 Tconf Name: USECLK Type: Bool  
 Example: `bios.PRD.USECLK = true;`
- Microseconds/Tick.** The number of microseconds between ticks. If the "Use CLK Manager to drive PRD field" property above is set to true, this property is automatically set by the CLK module; otherwise, you must explicitly set this property. The total time required to perform all PRD functions must be less than the number of microseconds between ticks.  
 Tconf Name: MICROSECONDS Type: Int16  
 Example: `bios.PRD.MICROSECONDS = 1000.0;`

## PRD Object Properties

To create a PRD object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var myPrd = bios.PRD.create("myPrd");
```

If you cannot create a new PRD object (an error occurs or the Insert PRD item is inactive in the DSP/BIOS Configuration Tool), increase the Stack Size property in the MEM Manager Properties before adding a PRD object.

The following properties can be set for a PRD object in the PRD Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- comment.** Type a comment to identify this PRD object.  
 Tconf Name: comment Type: String  
 Example: `myPrd.comment = "my PRD";`
- period (ticks).** The function executes after this number of ticks have elapsed.  
 Tconf Name: period Type: Int16  
 Example: `myPrd.period = 32767;`



- ❑ **mode.** If "continuous" is used, the function executes every "period" number of ticks. If "one-shot" is used, the function executes just once after "period" ticks.

Tconf Name: mode Type: EnumString

Options: "continuous", "one-shot"

Example: `myPrd.mode = "continuous";`
- ❑ **function.** The function to be executed. The total time required to perform all PRD functions must be less than the number of microseconds between ticks.

Tconf Name: fxn Type: Extern

Example: `myPrd.fxn = prog.extern("prdFxn");`
- ❑ **arg0, arg1.** Two Arg type arguments for the user-specified function above.

Tconf Name: arg0 Type: Arg

Tconf Name: arg1 Type: Arg

Example: `myPrd.arg0 = 0;`
- ❑ **period (ms).** The number of milliseconds represented by the period specified above. This is an informational property only.

Tconf Name: N/A
- ❑ **order.** Set this property to all PRD objects so that the numbers match the sequence in which PRD functions should be executed.

Tconf Name: order Type: Int16

Example: `myPrd.order = 2;`

**PRD\_getticks***Get the current tick count***C Interface**

**Syntax**                    num = PRD\_getticks();

**Parameters**                Void

**Return Value**              LgUns        num        /\* current tick counter \*/

**Reentrant**                 yes

**Description**              PRD\_getticks returns the current period tick count as a 32-bit value.

If the periodic functions are being driven by the on-device timer, the tick value is the number of low resolution clock ticks that have occurred since the program started running. When the number of ticks reaches the maximum value that can be stored in 32 bits, the value wraps back to 0. See the CLK Module, page 2–39, for more details.

If the periodic functions are being driven programmatically, the tick value is the number of times PRD\_tick has been called.

**Example**

```
/* ===== showTicks ===== */
Void showTicks
{
    LOG_printf(&trace, "ticks = %d", PRD_getticks());
}
```

**See Also**

PRD\_start  
PRD\_tick  
CLK\_geththime  
CLK\_getltime  
STS\_delta

**PRD\_start***Arm a periodic function for one-shot execution***C Interface**

<b>Syntax</b>	PRD_start(prd);
<b>Parameters</b>	PRD_Handle prd;     /* prd object handle*/
<b>Return Value</b>	Void
<b>Reentrant</b>	no

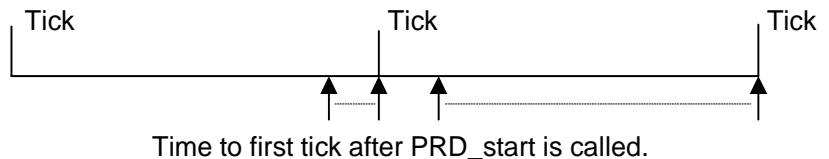
**Description**

PRD\_start starts a period object that has its mode property set to one-shot in the configuration. Unlike PRD objects that are configured as continuous, one-shot PRD objects do not automatically continue to run. A one-shot PRD object runs its function only after the specified number of ticks have occurred after a call to PRD\_start.

For example, you might have a function that should be executed a certain number of periodic ticks after some condition is met.

When you use PRD\_start to start a period object, the exact time the function runs can vary by nearly one tick cycle. As Figure 2-10 shows, PRD ticks occur at a fixed rate and the call to PRD\_start can occur at any point between ticks

*Figure 2-10. PRD Tick Cycles*



If PRD\_start is called again before the period for the object has elapsed, the object's tick count is reset. The PRD object does not run until its "period" number of ticks have elapsed.

**Example**

```
/* ===== startPRD ===== */
Void startPrd(Int periodID)
{
    if ("condition met") {
        PRD_start(&periodID);
    }
}
```

**See Also**

PRD\_tick  
PRD\_getticks

**PRD\_stop***Stop a period object to prevent its function execution***C Interface**

<b>Syntax</b>	PRD_stop(prd);
<b>Parameters</b>	PRD_Handle prd;     /* prd object handle*/
<b>Return Value</b>	Void

<b>Reentrant</b>	no
------------------	----

<b>Description</b>	PRD_stop stops a period object to prevent its function execution. In most cases, PRD_stop is used to stop a period object that has its mode property set to one-shot in the configuration.
--------------------	--

Unlike PRD objects that are configured as continuous, one-shot PRD objects do not automatically continue to run. A one-shot PRD object runs its function only after the specified numbers of ticks have occurred after a call to PRD\_start.

PRD\_stop is the way to stop those one-shot PRD objects once started and before their period counters have run out.

<b>Example</b>	PRD_stop(&prd);
----------------	-----------------

<b>See Also</b>	PRD_getticks PRD_start PRD_tick
-----------------	---------------------------------------

**PRD\_tick***Advance tick counter, enable periodic functions***C Interface****Syntax** PRD\_tick();**Parameters** Void**Return Value** Void**Reentrant** no**Description**

PRD\_tick advances the period counter by one tick. Unless you are driving PRD functions using the on-device clock, PRD objects execute their functions at intervals based on this counter.

For example, an HWI could perform PRD\_tick to notify a periodic function when data is available for processing.

**Constraints and Calling Context**

- ❑ All the registers that are modified by this API should be saved and restored, before and after the API is invoked, respectively.
- ❑ When called within an HWI, the code sequence calling PRD\_tick must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.
- ❑ Interrupts need to be disabled before calling PRD\_tick.

**See Also**

PRD\_start  
PRD\_getticks

## 2.20 PWRM Module

The PWRM module lets you reduce the power consumption of your DSP/BIOS application.

The PWRM module is currently available for the 'C5509A EVM. Partial support for other 'C55x devices is also available. See the DSP/BIOS release notes to determine which features are supported on different 'C55x devices.

### Functions

- ❑ `PWRM_changeSetpoint`. Initiate a change to the V/F setpoint.
- ❑ `PWRM_configure`. Set new configuration parameters for PWRM.
- ❑ `PWRM_getCapabilities`. Get information on PWRM's capabilities on the current platform.
- ❑ `PWRM_getCurrentSetpoint`. Get the current V/F setpoint in effect.
- ❑ `PWRM_getDependencyCount`. Get count of dependencies currently declared on a resource.
- ❑ `PWRM_getNumSetpoints`. Get the number of V/F setpoints supported for the current platform.
- ❑ `PWRM_getSetpointInfo`. Get the corresponding frequency and CPU core voltage for a setpoint.
- ❑ `PWRM_getTransitionLatency`. Get the latency to scale from one setpoint to another setpoint.
- ❑ `PWRM_idleClocks`. Immediately idle clock domains.
- ❑ `PWRM_registerNotify`. Register a `pwrMNotifyFxn` function to be called on a specific power event.
- ❑ `PWRM_releaseDependency`. Release a dependency that has been previously declared.
- ❑ `PWRM_setDependency`. Declare a dependency upon a resource.
- ❑ `PWRM_sleepDSP`. Transition the DSP to a new sleep state.
- ❑ `PWRM_unregisterNotify`. Unregister for an event notification from PWRM.

**Description**

The DSP/BIOS Power Manager, PWRM, is a DSP/BIOS module that lets you reduce the power consumption of your application in the following ways:

- ❑ You can idle specific clock domains to reduce active power consumption.
- ❑ You can specify a power-saving function to be called automatically at boot time. This function can idle power-using peripherals and subsystems as desired.
- ❑ You can dynamically change the operating voltage and frequency of the CPU. This is called V/F scaling. Since power usage is linearly proportional to the frequency and quadratically proportional to the voltage, using the PWRM module can result in significant power savings.
- ❑ You can set custom sleep modes to save power during inactivity. These can be set statically or at run-time.
- ❑ You can coordinate sleep modes and V/F scaling using registration and notification mechanisms provided by the PWRM module.
- ❑ PWRM functions are designed to save and restore the users environment where appropriate. For example, interrupt masks are saved before and restored after going to deep sleep.

For further description of these features in DSP/BIOS, see the *TMS320 DSP/BIOS User's Guide* (SPRU423). For information about the Power Scaling Library, see *Using the Power Scaling Library on the TMS320C5509* (SPRA848).

**Constants, Types, and Structures**

```
typedef Void * PWRM_NotifyHandle;

typedef Uns PWRM_Status;

typedef struct PWRM_Config {
    Bool scaleVoltage;
    Bool waitForVoltageScale;
    Uns idleMask;
} PWRM_Config;

typedef struct PWRM_Attrs {
    Bool scaleVoltage; /* scale voltage */
    Bool waitForVoltageScale; /* wait on volt change */
    Uns idleMask; /* domains to idle */
} PWRM_Attrs;
```

The following constants are used as return codes by various PWRM functions:

<b>Name</b>	<b>Usage</b>
PWRM_SOK	The operation succeeded.
PWRM_EFAIL	A general failure occurred.
PWRM_EINVALIDEVENT	The specified PWRM event type is invalid.
PWRM_EINVALIDHANDLE	The specified handle is invalid.
PWRM_EINVALIDPOINTER	A pointer is invalid.
PWRM_EINVALIDVALUE	A value is invalid.
PWRM_ENOTIMPLEMENTED	The operation is not implemented by PWRM on this platform.
PWRM_ENOTSUPPORTED	The requested setting is not supported. For example, a client has registered with PWRM indicating that it cannot support the requested V/F setpoint.
PWRM_EOUTOFRANGE	The operation could not be completed because a parameter was out of the range supported by PWRM.
PWRM_ETIMEOUT	A timeout occurred while trying to complete the operation.
PWRM_ETOOMANYCALLS	Indicates PWRM_releaseDependency has been called more times for a resource than PWRM_setDependency was called.
PWRM_EBUSY	The requested operation cannot be performed at this time; PWRM is busy processing a previous request.
PWRM_EINITFAILURE	A failure occurred while initializing V/F scaling support; V/F scaling is unavailable.

The PWRM\_configure and PWRM\_idleClocks functions use the following constants to identify clock domains to be idled:

<b>Name</b>	<b>Usage</b>
PWRM_IDLECPU	Idle the CPU clock domain
PWRM_IDLEDMA	Idle the DMA clock domain
PWRM_IDLECACHE	Idle the CACHE clock domain
PWRM_IDLEPERIPH	Idle the PERIPH clock domain
PWRM_IDLECLKGEN	Idle the CLKGEN clock domain
PWRM_IDLEEMIF	Idle the EMIF clock domain



Name	Usage
PWRM_IDLEIPORT	Idle the IPORT clock domain (OMAP 2420 only)
PWRM_IDLEHWA	Idle the HWA clock domain (OMAP 2420 only)
PWRM_IDLEMPORT	Idle the MPORT clock domain (OMAP 2420 only)
PWRM_IDLEXPOR	Idle the XPORT clock domain (OMAP 2420 only)

## Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the PWRM Manager Properties topic. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

### Module Configuration Parameters

Name	Type	Default (Enum Options)
ENABLE	Bool	false
BOOTHOOK	Bool	false
BOOTHOOKFXN	Extern	prog.extern("FXN_F_nop")
ADAPTCLK	Bool	false
DEVICEINIT	Bool	false
RESOURCETRACKING	Bool	false
DEVICEDBMEMSEG	Bool	prog.get("DARAM")
IDLEDOMAINS	Bool	false
IDLEIPORT	Bool	false (OMAP 2420 only)
IDLEHWA	Bool	false (OMAP 2420 only)
IDLEMPORT	Bool	false (OMAP 2420 only)
IDLEXPOR	Bool	false (OMAP 2420 only)
IDLEEMIF	Bool	false
IDLECLKGEN	Bool	false
IDLEPERIPH	Bool	false
IDLECACHE	Bool	true
IDLEDMA	Bool	false
IDLECPU	Bool	true
SCALING	Bool	false
INITIALFREQ	Numeric	15
INITVOLTS	Numeric	1.6
SCALEVOLT	Bool	false
WAITVOLT	Bool	true

Name	Type	Default (Enum Options)
PSLCONFIGLIB	String	"PSL_cfg_c5509a.a55L"
ENABLESLEEP	Bool	true
SLEEPIPORT	Bool	true (OMAP 2420 only)
SLEEPHWA	Bool	true (OMAP 2420 only)
SLEEPMPORT	Bool	true (OMAP 2420 only)
SLEEPXPORT	Bool	true (OMAP 2420 only)
SLEEPEMIF	Bool	true
SLEEPCLKGEN	Bool	true
SLEPPERIPH	Bool	true
SLEEPCACHE	Bool	true
SLEEPDMA	Bool	true
SLEEPCPU	Bool	true
WKUPIER0	Numeric	0
WKUPIER1	Numeric	0
SLEEPUNTILRESTART	Bool	true
ENABLESNOOZE	Bool	false
TIMERFORSNOOZE	EnumString	"Timer 1" ("Timer 0")

## Examples

An example demonstrating the use of the V/F scaling APIs of PWRM is located in the `<bios_install_dir>/ti/bios/examples/advanced/vfscale` folder.

An example demonstrating the use of PWRM's boot hook to call a developer-defined function to implement power savings on boot, idle DSP clock domains to reduce active power consumption, and invoke deep sleep is in the `<bios_install_dir>/ti/bios/examples/advanced/sleep` folder.

## PWRM Manager Properties

The following global properties can be set for the PWRM module in the PWRM Manager Properties dialog of Gconf or in a Tconf script:

### General tab

- Enable PWRM Manager.** Check this box if you want to enable the power manager. If you do not plan to use the power manager, you should leave it disabled to reduce the size of your application.

Tconf Name: ENABLE

Type: Bool

Example: `bios.PWRM.ENABLE = false;`

- ❑ **Call user hook function at boot time.** Check this box if you want to specify a function to be called during application startup. Such a function is called before the main() function runs.

Tconf Name: BOOTHOOK Type: Bool

Example: `bios.PWRM.BOOTHOOK = false;`

- ❑ **Function.** Specify the function to be called during application startup if you set the property above to true. The function may be used, for example to idle clock domains or to turn off or idle powered resources.

Tconf Name: BOOTHOOKFXN Type: Extern

Example: `bios.PWRM.BOOTHOOKFXN =  
prog.extern("FXN_F_nop");`

- ❑ **Reprogram BIOS clock after frequency scaling.** This property specifies whether the DSP/BIOS clock module should be reprogrammed after frequency scaling operations. If it is set to true (the default), the CLK module registers for V/F frequency setpoint change notifications and is reprogrammed after a setpoint change. If you do not use DSP timers for CLK functionality (that is, if you use an external clock trigger), set this property to false to save code space and eliminate unnecessary steps. If you set this property to true, do not use the CLK\_reconfig, CLK\_stop, or CLK\_start APIs in your application.

Tconf Name: ADAPTCLK Type: Bool

Example: `bios.PWRM.ADAPTCLK = false;`

- ❑ **Enable device initialization by PWRM.** Set this to true if you want PWRM to initialize the DSP device to a low power state at boot time. This initialization happens before the main() function runs. If PWRM does not support initialization for the device, this property is not writeable.

Tconf Name: DEVICEINIT Type: Bool

Example: `bios.PWRM.DEVICEINIT = false;`

- ❑ **Enable resource tracking by PWRM.** Set this to true if you want to enable the resource tracking feature of PWRM. When enabled, calls to PWRM\_setDependency and PWRM\_releaseDependency track application and OS dependencies on power-manageable resources, and appropriately power them up or down as needed. If PWRM does not support resource tracking for the device, this property is not writeable.

Tconf Name: RESOURCETRACKING Type: Bool

Example: `bios.PWRM.RESOURCETRACKING = false;`



- ❑ **XPORT.** Checking this box causes the XPORT clock domain to be idled during the DSP/BIOS idle loop. The DMA and CPU domains must be idled before you can choose to idle the XPORT domain. This setting can be modified at runtime using the PWRM\_configure function. (OMAP 2420 only)

Tconf Name: IDLEXPOR Type: Bool

Example: `bios.PWRM.IDLEXPOR = false;`

- ❑ **EMIF.** Checking this box causes the EMIF clock domain to be idled during the DSP/BIOS idle loop. This setting can be modified at runtime using the PWRM\_configure function.

Tconf Name: IDLEEMIF Type: Bool

Example: `bios.PWRM.IDLEEMIF = false;`

- ❑ **CLKGEN.** Checking this box causes the CLKGEN clock domain to be idled during the DSP/BIOS idle loop. The CACHE, DMA, and CPU domains must be idled before you can choose to idle the CLKGEN domain. This setting can be modified at runtime using the PWRM\_configure function.

Tconf Name: IDLECLKGEN Type: Bool

Example: `bios.PWRM.IDLECLKGEN = false;`

- ❑ **PERIPHS.** Checking this box causes the PERIPH clock domain to be idled during the DSP/BIOS idle loop. This setting can be modified at runtime using the PWRM\_configure function.

Checking this box does not ensure that every peripheral is idled during the idle loop. Several peripherals can specify whether to idle when the peripheral domain is idled. For example, on the 'C5509A, the McBSP is specified via the IDLE\_EN bit in the PCRs, timers via the IDLE\_EN bit in the TCRs, the ADC module via the IdleEn bit in the ADCCR, the I2C module via the IDLEEN bit in ICMDR, USB via the IDLEEN bit in USBIDLECTL, and the MMC controller via the IDLEEN bit in the MMCFCLK. Code that manages such peripherals may set the corresponding idle enable bit to ensure the peripheral idles when the top-level peripheral domain is idled. For details, see the *TMS320C55x DSP Peripherals Reference Guide* (SPRU317).

Tconf Name: IDLEPERIPH Type: Bool

Example: `bios.PWRM.IDLEPERIPH = false;`

- ❑ **CACHE.** Checking this box causes the CACHE clock domain to be idled during the DSP/BIOS idle loop. The CACHE domain must remain idled if the CLKGEN domain is idled. This setting can be modified at runtime using the PWRM\_configure function.

Tconf Name: IDLECACHE Type: Bool

Example: `bios.PWRM.IDLECACHE = true;`

- ❑ **DMA.** Checking this box causes the DMA clock domain to be idled during the DSP/BIOS idle loop. The DMA domain must remain idled if the CLKGEN domain is idled. This setting can be modified at runtime using the PWRM\_configure function.

Tconf Name: IDLEDMA

Type: Bool

Example: `bios.PWRM.IDLEDMA = false;`

- ❑ **CPU.** Checking this box causes the CPU clock domain to be idled during the DSP/BIOS idle loop. The CPU domain must remain idled if the CLKGEN domain is idled. This setting can be modified at runtime using the PWRM\_configure function.

Tconf Name: IDLECPU

Type: Bool

Example: `bios.PWRM.IDLECPU = true;`

## V/F Scaling tab

- ❑ **Enable Voltage and Frequency Scaling.** This property specifies whether voltage and frequency scaling are to be enabled for the application. Setting this property to true causes the Power Scaling Library (PSL) library specified by the PSLCONFIGLIB property to be linked with the application.

Tconf Name: SCALING

Type: Bool

Example: `bios.PWRM.SCALING = false;`

- ❑ **Initial frequency (index to frequency table).** Specify the initial frequency of the DSP after booting. This value is a setpoint from the Frequency Setpoint Table. For details, see “PWRM\_changeSetpoint” on page 2-310.

Tconf Name: INITIALFREQ

Type: Numeric

Example: `bios.PWRM.INITIALFREQ = 15;`

- ❑ **Initial voltage (volts).** Specify the initial voltage of the DSP after it has been booted.

Tconf Name: INITVOLTS

Type: Numeric

Example: `bios.PWRM.INITVOLTS = 1.6;`

- ❑ **Scale voltage along with frequency.** This property specifies whether voltage should be scaled along with frequency. You may want to disable voltage scaling to reduce latency when changing the frequency. If this property is set to true, a change to the frequency (via PWRM\_changeSetpoint) results in a voltage change when possible. For example, changing from setpoint 15 to setpoint 0 results in a frequency change from 200 to 6 MHz, as well as a voltage change from 1.6 to 1.1. If this property is set to false, voltage is not scaled down along with frequency. The voltage is always scaled up

if the new setpoint frequency is higher than that supported at the current voltage. This setting can be modified at runtime using the PWRM\_configure function.

Tconf Name: SCALEVOLT Type: Bool

Example: `bios.PWRM.SCALEVOLT = false;`

- Wait while voltage is being scaled down.** This property specifies whether PWRM functions should wait during down-voltage transitions. Such transition times can be long, as they typically depend upon power supply load. Currently, it is recommended that this property remain set to false. (Note that the PWRM module always waits during up-voltage transitions; this is required to avoid over-clocking the DSP.) This setting can be modified at runtime using the PWRM\_configure function.

Tconf Name: WAITVOLT Type: Bool

Example: `bios.PWRM.WAITVOLT = true;`

- PSL Configuration Library.** Specify the PSL configuration library to link with. Specify only the filename of the library to link with for this property. The include path to the PSL Configuration Library should be added to the linker command file if it is not in the default path. An example library filename is PSL\_cfg\_c5509a.a55L.

Tconf Name: PSLCONFIGLIB Type: String

Example: `bios.PWRM.PSLCONFIGLIB =  
"PSL_cfg_c5509a.a55L"`

## Sleep tab

- Enable deep sleep.** This property specifies whether to enable deep sleep. If it is set to false, you cannot select the remaining items in this tab.

Tconf Name: ENABLESLEEP Type: Bool

Example: `bios.PWRM.ENABLESLEEP = true;`

- HWA.** Checking this box causes the HWA clock domain to be idled during deep sleep. (OMAP 2420 only)

Tconf Name: SLEEPHWA Type: Bool

Example: `bios.PWRM.SLEEPHWA = true;`

- IPOINT.** Checking this box causes the IPOINT clock domain to be idled during deep sleep. The CACHE and CPU domains must be idled for deep sleep before you can choose to idle the IPOINT domain. (OMAP 2420 only)

Tconf Name: SLEEPPOINT Type: Bool

Example: `bios.PWRM.SLEEPPOINT = true;`

- MPORT.** Checking this box causes the MPORT clock domain to be idled during deep sleep. The DMA domain must be idled for deep sleep before you can choose to idle the MPORT domain. (OMAP 2420 only)  
Tconf Name: SLEEPMPORT Type: Bool  
Example: `bios.PWRM.SLEEPMPORT = true;`
- XPORT.** Checking this box causes the XPORT clock domain to be idled during deep sleep. The DMA and CPU domains must be idled for deep sleep before you can choose to idle the XPORT domain. (OMAP 2420 only)  
Tconf Name: SLEEPXPORT Type: Bool  
Example: `bios.PWRM.SLEEPXPORT = true;`
- EMIF.** Setting this property to true causes the EMIF clock domain to be idled during deep sleep.  
Tconf Name: SLEEPEMIF Type: Bool  
Example: `bios.PWRM.SLEEPEMIF = true;`
- CLKGEN.** Checking this box causes the CLKGEN clock domain to be idled during deep sleep. The CACHE, DMA, and CPU domains must be idled for deep sleep before you can choose to idle the CLKGEN domain.  
Tconf Name: SLEEPCLKGEN Type: Bool  
Example: `bios.PWRM.SLEEPCLKGEN = true;`
- PERIPHS.** Checking this box causes the PERIPH clock domain to be idled during deep sleep. See the description of the PERIPHS box in the Idling tab for details on idling various peripherals when the PERIPH clock domain is idled.  
Tconf Name: SLEEPPERIPH Type: Bool  
Example: `bios.PWRM.SLEEPPERIPH = true;`
- CACHE.** Checking this box causes the CACHE clock domain to be idled during deep sleep. The CACHE domain must remain idled if the CLKGEN domain is idled.  
Tconf Name: SLEEPCACHE Type: Bool  
Example: `bios.PWRM.SLEEPCACHE = true;`
- DMA.** Checking this box causes the DMA clock domain to be idled during deep sleep. The DMA domain must remain idled if the CLKGEN domain is idled.  
Tconf Name: SLEEPDMA Type: Bool  
Example: `bios.PWRM.SLEEPDMA = true;`



- ❑ **CPU.** Checking this box causes the CPU clock domain to be idled during deep sleep. The CPU domain must remain idled if the CLKGEN domain is idled.

Tconf Name: SLEEPCPU

Type: Bool

Example: `bios.PWRM.SLEEPCPU = true;`

- ❑ **Wakeup interrupt mask, IER0.** Specifies the wakeup interrupt mask for IER0. This mask is loaded into the DSP's Interrupt Enable Register 0 (IER0) before the PWRM module causes the DSP to sleep. The bits in IER0 and IER1 determine which interrupts are enabled. You can use these bits to enable interrupts that can wake the DSP. For example, a button press by the user might cause an interrupt that is enabled. The IER mappings for each DSP are defined in that DSP's data sheet.

Tconf Name: WKUPIER0

Type: Numeric

Example: `bios.PWRM.WKUPIER0 = 0;`

- ❑ **Wakeup interrupt mask, IER1.** Specifies the wakeup interrupt mask for IER1. This mask is loaded into the DSP's Interrupt Enable Register 1 (IER1) before the PWRM module causes the DSP to sleep.

Tconf Name: WKUPIER1

Type: Numeric

Example: `bios.PWRM.WKUPIER1 = 0;`

- ❑ **Enable sleep until restart.** This property specifies whether "sleep until restart" mode is enabled. In this mode, the only way to wake the DSP is to perform a DSP reset.

Tconf Name: SLEEPUNTILRESTART

Type: Bool

Example: `bios.PWRM.SLEEPUNTILRESTART = true;`

- ❑ **Enable snooze mode.** Because of the limited DSP timer resolution, this feature is not currently implemented.

Tconf Name: ENABLESNOOZE

Type: Bool

Example: `bios.PWRM.ENABLESNOOZE = false;`

- ❑ **Timer to be used for snooze mode.** Because of the limited DSP timer resolution, this feature is not currently implemented.

Tconf Name: TIMERFORSNOOZE

Type: EnumString

Options: "Timer 0", "Timer 1"

Example: `bios.PWRM.TIMERFORSNOOZE = "Timer 1";`

**PWRM\_changeSetpoint***Initiate a change to the V/F setpoint***C Interface**

**Syntax** status = PWRM\_changeSetpoint(newSetpoint, notifyTimeout);

**Parameters** Uns newSetpoint; /\* new V/F setpoint \*/  
 Uns notifyTimeout; /\* maximum time to wait for notification \*/

**Return Value** PWRM\_Status status; /\* returned status \*/

**Reentrant** yes

**Description**

PWRM\_changeSetpoint changes the voltage and frequency of the DSP CPU. Reducing the clock rate (frequency) results in a linear decrease in power consumption. Reducing the operating voltage results in a quadratic reduction in power consumption. Note that there are issues you should be aware of when reducing the clock frequency. For a discussion of these issues, see the *TMS320 DSP/BIOS User's Guide* (SPRA423).

The newSetpoint parameter is a numeric value that indexes into a table of frequency/voltage pairs, as defined by the underlying PSL library. For example, the following table shows the setpoints for the 'C5509A EVM.

Setpoint	'C5509A EVM Frequency (MHz)	'C5509A EVM Voltage (volts)
15	192	1.6
14	180	1.6
13	168	1.6
12	156	1.6
11	144	1.4
10	132	1.4
9	120	1.4
8	108	1.2
7	96	1.2
6	84	1.2
5	72	1.2
4	60	1.2
3	48	1.2
2	12	1.2
1	6	1.2
0	3	1.2

The notifyTimeout parameter is the maximum amount of time (in system clock ticks) to wait for registered notification functions (set by PWRM\_registerNotify) to respond to a delayed completion, before declaring failure and returning PWRM\_ETIMEOUT.

For example, if notifyTimeout is set to 200, PWRM\_changeSetpoint waits up to 200 ticks (typically 200 milliseconds) before declaring that a function has failed to respond. PWRM uses notifyTimeout for each notification. For example, if notification functions are registered for both before and after setpoint changes, PWRM\_changeSetpoint waits up to notifyTimeout on each notification. All registered notification functions are called from the context of PWRM\_changeSetpoint.

PWRM\_changeSetpoint returns one of the following constants as a status value of type PWRM\_Status:

Name	Usage
PWRM_SOK	The operation succeeded and the new setpoint is in effect.
PWRM_EFAIL	A general failure occurred. The requested setpoint transition did not occur.
PWRM_ENOTIMPLEMENTED	V/F scaling is not implemented by PWRM on this platform.
PWRM_ENOTSUPPORTED	The operation could not be completed because a client registered with PWRM indicating that it cannot support the requested setpoint.
PWRM_EOUTOFRANGE	The operation could not be completed because newSetpoint is not a valid value for the platform.
PWRM_ETIMEOUT	A registered notification function did not respond within the specified notifyTimeout.
PWRM_EBUSY	The requested operation cannot be performed at this time; PWRM is busy processing a previous request.
PWRM_EINITFAILURE	A failure occurred while initializing V/F scaling support; V/F scaling is unavailable.

The application should treat return values of PWRM\_ETIMEOUT or PWRM\_EFAIL as critical system failures. These values indicate the notification client is unresponsive, and the system is in an unknown state.

PWRM\_changeSetpoint disables SWI and TSK scheduling when it begins making a change. However, HWIs may run during the notification process. After the setpoint has been changed, SWI and TSK scheduling is re-enabled, and a context switch occurs only if some other thread has since been made ready to run.

### Constraints and Calling Context

- ❑ PWRM\_changeSetpoint cannot be called from an HWI.
- ❑ This API cannot be called from a program's main() function.
- ❑ PWRM\_changeSetpoint can be called from a SWI only if notifyTimeout is 0.

### Example

```
#define TIMEOUT    10 /* timeout for notifications */

PWRM_Status status;
Int i;

status = PWRM_changeSetpoint(i, TIMEOUT);
if (status == PWRM_SOK) {
    LOG_printf(TRACE, "New setpoint = %d", i);
}
else if (status == PWRM_ENOTSUPPORTED) {
    LOG_printf(TRACE, "Setpoint %d unsupported", i);
}
else {
    LOG_printf(TRACE, "Error: status = %x", status);
    return;
}
GBL_getFrequency
GBL_setFrequency
```

**PWRM\_configure***Set new configuration properties for PWRM***C Interface**

<b>Syntax</b>	<code>status = PWRM_configure(attrs);</code>
<b>Parameters</b>	<code>PWRM_Attrs  attrs;          /* configuration attributes */</code>
<b>Return Value</b>	<code>PWRM_Status status;        /* returned status */</code>

**Reentrant**                   yes

**Description**               PWRM\_configure specifies new configuration properties for the PWRM module. It overrides those specified in the static configuration.

The PWRM\_Attrs parameter you pass to PWRM\_configure has the following structure:

```
typedef struct PWRM_Attrs {
    Bool scaleVoltage;          /* scale voltage */
    Bool waitForVoltageScale;  /* wait on volt change */
    Uns  idleMask;             /* domains to idle */
} PWRM_Attrs;
```

In this structure, scaleVoltage indicates whether PWRM should scale voltages during setpoint changes. It corresponds to the "Scale voltage along with frequency" property in the V/F Scaling tab of the configuration. If scaleVoltage is TRUE, the voltage is scaled down if possible when going to a lower frequency. If scaleVoltage is FALSE, the voltage is not scaled lower. The voltage is always scaled up if the new setpoint frequency is higher than that supported at the current voltage.

The waitForVoltageScale flag indicates whether PWRM should wait for a down-voltage transition to complete before returning from PWRM\_changeSetpoint. It corresponds to the "Wait while voltage is being scaled down" property in the V/F Scaling tab of the configuration. Such transition times can be long, as they typically depend upon power supply load. Currently, it is recommended that this item always be TRUE. (The PWRM module always waits during up-voltage transitions; this is required to avoid over-clocking the DSP.)

The idleMask is a bitmask that specifies additional clock domains to be idled in the DSP/BIOS idle loop. This bitmask is ORed with the current Idle Status Register (ISTR) contents and then written to the Idle Configuration Register (ICR) before idling the processor. When the processor is awoken by an interrupt, the bits for the domains that were

idled on entry to the DSP/BIOS idle loop are written to the ICR register and the IDLE instruction is invoked again to restore the previous idle configuration.

See the Idling tab of the configuration properties for descriptions of required interactions between idled clock domains. The bitmask can be formed using the following predefined mask constants:

Name	Usage
PWRM_IDLECPU	Idle the CPU clock domain
PWRM_IDLEDMA	Idle the DMA clock domain
PWRM_IDLECACHE	Idle the CACHE clock domain
PWRM_IDLEPERIPH	Idle the PERIPH clock domain
PWRM_IDLECLKGEN	Idle the CLKGEN clock domain
PWRM_IDLEEMIF	Idle the EMIF clock domain
PWRM_IDLEIPOINT	Idle the IPOINT clock domain (OMAP 2420 only)
PWRM_IDLEHWA	Idle the HWA clock domain (OMAP 2420 only)
PWRM_IDLEMPORT	Idle the MPORT clock domain (OMAP 2420 only)
PWRM_IDLEXPOR	Idle the XPOR clock domain (OMAP 2420 only)

PWRM\_configure returns one of the following constants as a status value of type PWRM\_Status:

Name	Usage
PWRM_SOK	The operation succeeded.
PWRM_EFAIL	A general failure occurred.
PWRM_EINVALIDPOINTER	The operation failed because the attrs parameter was NULL.
PWRM_EINVALIDVALUE	The operation failed because the idleMask is invalid. For example, if the CLKGEN domain is to be idled, the CPU, DMA, and CACHE domains must also be idled.

**PWRM\_getCapabilities***Get information on PWRM capabilities on the current platform***C Interface**

**Syntax**                    status = PWRM\_getCapabilities(capsMask);

**Parameters**                Uns                    \*capsMask;    /\* pointer to location for capabilities \*/

**Return Value**              PWRM\_Status status;            /\* returned status \*/

**Reentrant**                    yes

**Description**                PWRM\_getCapabilities returns information about the PWRM module's capabilities on the current platform.

The capsMask parameter should point to the location where PWRM\_getCapabilities should write a bitmask that defines the capabilities. You can use the following constants to check for capabilities in the bitmask:

<b>Name</b>	<b>Usage</b>
PWRM_CDEEPSLEEP	PWRM_sleepDSP supports deep sleep mode.
PWRM_CRESOURCETRACKING	The PWRM module supports dynamic resource tracking.
PWRM_CSLEEPUNTILRESTART	PWRM_sleepDSP supports sleep until restart.
PWRM_CSNOOZE	PWRM_sleepDSP supports snooze mode.
PWRM_CVFSCALING	The PWRM module supports voltage and frequency scaling.

PWRM\_getCapabilities returns one of the following constants as a status value of type PWRM\_Status:

<b>Name</b>	<b>Usage</b>
PWRM_SOK	The operation succeeded.
PWRM_EFAIL	A general failure occurred.
PWRM_EINVALIDPOINTER	The operation failed because the capsMask parameter was NULL.

**Example**

```
PWRM_Status status;
Uns capsMask;

/* Query PWRM capabilities on this platform */
status = PWRM_getCapabilities(&capsMask);
LOG_printf(TRACE, "Returned mask=0x%X", capsMask);
if (status != PWRM_SOK) {          /* exit on error */
    LOG_printf(TRACE, "Status = %x", status);
    return;
}
/* exit if V/F scaling not supported */
if ((capsMask & PWRM_CVFSCALING) == 0) {
    LOG_printf(TRACE, "V/F scaling not supported");
    return;
}
```



**PWRM\_getCurrentSetpoint** *Get the current setpoint***C Interface**

**Syntax** `status = PWRM_getCurrentSetpoint(setpoint);`

**Parameters** `Uns setpoint; /* current V/F setpoint */`

**Return Value** `PWRM_Status status; /* returned status */`

**Reentrant** no

**Description** PWRM\_getCurrentSetpoint returns the V/F scaling setpoint currently in use. The setpoint parameter should point to the location where PWRM\_getCurrentSetpoint should write the current setpoint. See PWRM\_changeSetpoint for a list of valid setpoints.

PWRM\_getCurrentSetpoint returns one of the following constants as a status value of type PWRM\_Status:

Name	Usage
PWRM_SOK	The operation succeeded.
PWRM_EFAIL	A general failure occurred.
PWRM_EINVALIDPOINTER	The operation failed because the setpoint parameter was NULL.
PWRM_EINITFAILURE	A failure occurred while initializing V/F scaling support; V/F scaling is unavailable.
PWRM_ENOTIMPLEMENTED	The operation failed because V/F scaling is not supported.

**Constraints and Calling Context**

- ❑ If a call to PWRM\_getCurrentSetpoint is preempted by a thread that changes the setpoint, the value PWRM\_getCurrentSetpoint returns is the old setpoint and not the new setpoint. If this may cause a problem in your application, you can disable scheduling around the call to PWRM\_getCurrentSetpoint.

**Example**

```
PWRM_Status status;
Uns currSetpoint;

status = PWRM_getCurrentSetpoint(&currSetpoint);
LOG_printf(TRACE, "Setpoint: %d", currSetpoint);
if (status != PWRM_SOK) { /* exit on error */
    LOG_printf(TRACE, "Status = %x", status);
    return;
}
```

**PWRM\_getDependencyCount***Get count of dependencies declared on resource***C Interface**

**Syntax**                    `status = PWRM_getDependencyCount(resourceID, count);`

**Parameters**                `Uns                resourceID;            /* resource ID */`  
                               `Uns                *count;                /* pointer to where count is written */`

**Return Value**              `PWRM_Status status;            /* returned status */`

**Reentrant**                 `yes`

**Description**

PWRM\_getDependencyCount returns the number of dependencies that are currently declared on a resource. Normally this corresponds to the number of times PWRM\_setDependency has been called for the resource, minus the number of times PWRM\_releaseDependency has been called for the same resource.

Resource IDs are device-specific. They are defined in a PWRM\_Resource enumeration in a device-specific header file. For example, see pwr5509a.h for the 'C5509A.

PWRM\_getDependencyCount returns one of the following constants as a status value of type PWRM\_Status:

<b>Name</b>	<b>Usage</b>
PWRM_SOK	The operation succeeded, and the reference count was written to the location pointed to by count.
PWRM_ENOTIMPLEMENTED	The operation failed because resource tracking is not supported.

**Example**

```
/* Display some dependency counts */
LOG_printf(&trace, "Initial dependencies:");
PWRM_getDependencyCount(PWRM_5509A_CLKOUT, &count);
LOG_printf(&trace, "CLKOUT count = %d", count);
PWRM_getDependencyCount(PWRM_5509A_MCBSP0, &count);
LOG_printf(&trace, "McBSP0 count = %d", count);
PWRM_getDependencyCount(PWRM_5509A_DMA_DOMAIN, &count);
LOG_printf(&trace, "DMA domain count = %d", count);
```

**PWRM\_getNumSetpoints***Get the number of setpoints supported by platform***C Interface**

**Syntax**                    `status = PWRM_getNumSetpoints(numberSetpoints);`

**Parameters**                `Uns                    *numberSetpoints; /* number of supported setpoints */`

**Return Value**              `PWRM_Status status;                    /* returned status */`

**Reentrant**                    `yes`

**Description**                `PWRM_getNumSetpoints` returns the number of setpoints supported by the currently configured platform.

The `numberSetpoints` parameter should point to the location where `PWRM_getNumSetpoints` should write the number of setpoints. See `PWRM_changeSetpoint` for a list of valid setpoints. If V/F scaling is supported, the number of setpoints is greater than or equal to 1.

`PWRM_getNumSetpoints` returns one of the following constants as a status value of type `PWRM_Status`:

Name	Usage
<code>PWRM_SOK</code>	The operation succeeded.
<code>PWRM_EFAIL</code>	A general failure occurred.
<code>PWRM_EINVALIDPOINTER</code>	The operation failed because the <code>numberSetpoints</code> parameter was <code>NULL</code> .
<code>PWRM_EINITFAILURE</code>	A failure occurred while initializing V/F scaling support; V/F scaling is unavailable
<code>PWRM_ENOTIMPLEMENTED</code>	The operation failed because V/F scaling is not supported.

**Example**

```
PWRM_Status status;
Uns numSetpoints;

status = PWRM_getNumSetpoints(&numSetpoints);
LOG_printf(TRACE, "NumSetpoints: %d", numSetpoints);
if (status != PWRM_SOK) {                    /* exit on error */
    LOG_printf(TRACE, "Error: status = %x", status);
    return;
}
```

## **PWRM\_getSetpointInfo** *Get frequency and CPU core voltage for a setpoint*

### C Interface

**Syntax**                    status = PWRM\_getSetpointInfo(setpoint, frequency, voltage);

**Parameters**

Uns	setpoint;	/* the setpoint to query */
float	*frequency;	/* DSP core frequency */
float	*voltage;	/* DSP voltage */

**Return Value**            PWRM\_Status status;            /\* returned status \*/

**Reentrant**                yes

**Description**            PWRM\_getSetpointInfo returns the DSP CPU frequency and voltage for a given setpoint.

The setpoint parameter should specify the setpoint value for which you want to know the frequency and voltage on this platform. See PWRM\_changeSetpoint for a list of valid setpoints.

The frequency parameter should point to the location where PWRM\_getSetpointInfo should write the DSP core frequency for the specified setpoint.

The voltage parameter should point to the location where PWRM\_getSetpointInfo should write the DSP voltage for the specified setpoint.

PWRM\_getSetpointInfo returns one of the following constants as a status value of type PWRM\_Status:

<b>Name</b>	<b>Usage</b>
PWRM_SOK	The operation succeeded.
PWRM_EFAIL	A general failure occurred.
PWRM_EINVALIDVALUE	The operation failed because the setpoint parameter was invalid.
PWRM_EINVALIDPOINTER	The operation failed because the frequency or voltage parameter was NULL.
PWRM_EINITFAILURE	A failure occurred while initializing V/F scaling support; V/F scaling is unavailable
PWRM_ENOTIMPLEMENTED	The operation failed because V/F scaling is not supported.

**Example**

```
PWRM_Status status;

/* global arrays for saving setpoint info */
#define MAX_SETPOINTS      16
float freq[MAX_SETPOINTS];
float volts[MAX_SETPOINTS];

status = PWRM_getSetpointInfo(i, &freq[i], &volts[i]);
if (status != PWRM_SOK) {          /* exit on error */
    LOG_printf(TRACE, "Error: status=%x", status);
    return;
}
```



Name	Usage
PWRM_EINVALIDVALUE	The operation failed because the initialSetpoint or finalSetpoint parameter was invalid.
PWRM_EINVALIDPOINTER	The operation failed because the latency parameter was NULL.
PWRM_EINITFAILURE	A failure occurred while initializing V/F scaling support; V/F scaling is unavailable
PWRM_ENOTIMPLEMENTED	The operation failed because V/F scaling is not supported.

The time required to change a setpoint may not be deterministic (depending on the hardware characteristics, the underlying Power Scaling Library implementation, and the specific V/F swing), but it is bounded by the value returned by PWRM\_getTransitionLatency.

### Example

```
PWRM_Status status;
Uns numSetpoints = 16;
Uns frequencyLatency;
Uns voltageLatency;

status = PWRM_getTransitionLatency((numSetpoints - 1),
    0, &frequencyLatency, &voltageLatency);
LOG_printf	TRACE,
    "Frequency latency: %d, Voltage latency: %d",
    frequencyLatency, voltageLatency);
if (status != PWRM_SOK) { /* exit on error */
    LOG_printf	TRACE, "Error: status=%x", status);
    return;
}
```

## **PWRM\_idleClocks** *Immediately idle clock domains*

### **C Interface**

**Syntax**                    status = PWRM\_idleClocks(domainMask, idleStatus);

**Parameters**            Uns                    domainMask; /\* bitmask of clock domains to be idled \*/  
                              Uns                    \*idleStatus; /\* contents of ISTR after idling \*/

**Return Value**           PWRM\_Status status;            /\* returned status \*/

**Reentrant**                yes

**Description**            PWRM\_idleClocks immediately turns off the specified clock domains. This allows applications to idle non-CPU domains at any point in the application.

The domainMask is a bitmask that specifies clock domains to be idled. This value is written to the ICR register before idling the processor. See the Idling tab of the configuration properties for descriptions of required interactions between idled clock domains. The bitmask can be formed using the following predefined mask constants:

<b>Name</b>	<b>Usage</b>
PWRM_IDLEDMA	Idle the DMA clock domain
PWRM_IDLECACHE	Idle the CACHE clock domain
PWRM_IDLEPERIPH	Idle the PERIPH clock domain
PWRM_IDLEEMIF	Idle the EMIF clock domain
PWRM_IDLEIPOINT	Idle the IPOINT clock domain (OMAP 2420 only)
PWRM_IDLEHWA	Idle the HWA clock domain (OMAP 2420 only)
PWRM_IDLEMPORT	Idle the MPORT clock domain (OMAP 2420 only)
PWRM_IDLEXPOR	Idle the XPOR clock domain (OMAP 2420 only)

The idleStatus parameter should point to the location where PWRM\_idleClocks should write the contents of the Idle Status Register (ISTR) after idling clock domains. If PWRM\_idleClocks returns PWRM\_EFAIL, this parameter can be used to determine which domains were idled and which were not. For example, if a bit was set in the domainMask but is not set in idleStatus, the corresponding domain could not be idled.



PWRM\_idleClocks returns one of the following constants as a status value of type PWRM\_Status:

Name	Usage
PWRM_SOK	The operation succeeded.
PWRM_EFAIL	A general failure occurred. One of the domains specified in domainMask did not go idle.
PWRM_EINVALIDPOINTER	Operation failed because the idleStatus parameter was NULL.
PWRM_EINVALIDVALUE	Operation failed because the domainMask is invalid.

### Example

```
PWRM_Status status;
Uns idleStatus;

status = PWRM_idleClocks(PWRM_IDLEEMIF | PWRM_IDLEDMA,
                        &idleStatus);
if(idleStatus == (PWRM_IDLEEMIF | PWRM_IDLEDMA)) {
    LOG_printf(TRACE, "Idled domains successfully");
}
```



---

**Note:**

Snooze mode is currently not implemented.

---

The `eventMask` parameter is an event-specific mask. Currently `eventMask` is relevant only to setpoint changes, but it may be used in the future for other power events. For V/F setpoint registrations, this mask defines the setpoints the client supports. For example, if the client supports only one setpoint, it should set only the single corresponding bit in `eventMask`. Using the `eventMask` allows `PWRM_changeSetpoint` to immediately determine whether to begin the notification process or return `PWRM_ENOTSUPPORTED`.

The `notifyFxn` parameter specifies the function to call when the specified power event occurs. The `notifyFunction` must behave as described in the `pwrMNotifyFxn` section.

The `clientArg` parameter is an arbitrary argument to be passed to the client upon notification. This argument may allow one notify function to be used by multiple instances of a driver (that is, the `clientArg` can be used to identify the instance of the driver that is being notified).

The `notifyHandle` parameter should point to the location where `PWRM_registerNotify` should write a notification handle. If the application later needs to unregister the notification function, the application should pass this handle to `PWRM_unregisterNotify`.

The `delayedCompletionFxn` is a pointer to a function provided by the PWRM module to the client at registration time. If a client cannot act immediately upon notification, its notify function should return `PWRM_NOTIFYNOTDONE`. Later, when the action is complete, the client should call the `delayedCompletionFxn` to signal PWRM that it has finished. The `delayedCompletionFxn` is a void function, taking no arguments, and having no return value. If a client can and does act immediately on the notification, it should return `PWRM_NOTIFYDONE` in response to notification, and should not call the `delayedCompletionFxn`.

For example, if a DMA driver is to prepare for a setpoint change, it may need to wait for the current DMA transfer to complete. When the driver finishes processing the event (for example, on the next hardware interrupt), it calls the `delayedCompletionFxn` function provided when it registered for notification. This completion function tells the PWRM module that the driver is finished. Meanwhile, the PWRM module was able to continue notifying other clients, and was waiting for all clients to signal completion.

PWRM\_registerNotify returns one of the following constants as a status value of type PWRM\_Status:

Name	Usage
PWRM_SOK	The function was successfully registered.
PWRM_EFAIL	A general failure occurred.
PWRM_EINVALIDPOINTER	The operation failed because the notifyFxn, notifyHandle or delayedCompletionFxn parameter was NULL.
PWRM_EINVALIDEVENT	Operation failed because eventType is invalid.

### Constraints and Calling Context

- ❑ PWRM\_registerNotify cannot be called from a SWI or HWI. This is because PWRM\_registerNotify internally calls MEM\_alloc, which may cause a context switch.

### Example

```

/* client allows all setpoints */
#define ALLSETPOINTSALLOWED 0xFFFF
/* client doesn't allow lowest 4 setpoints */
#define SOMESETPOINTSALLOWED 0xFFFF0

PWRM_NotifyHandle notifyHandle1;
PWRM_NotifyHandle notifyHandle2;

/* pointers to returned delayed completion fxns */
Fxn delayFxn1;
Fxn delayFxn2;

/* Client 1 registers pre-setpoint notification */
PWRM_registerNotify(PWRM_PENDINGSETPOINTCHANGE,
    ALLSETPOINTSALLOWED, (Fxn)myNotifyFxn1,
    (Arg)0x1111, &notifyHandle1, (Fxn *) &delayFxn1);

/* Client 2 registers post-setpoint notification */
PWRM_registerNotify(PWRM_DONESETPOINTCHANGE,
    SOMESETPOINTSALLOWED, (Fxn)myNotifyFxn2,
    (Arg)0x2222, &notifyHandle2, &delayFxn2);

```

**pwrnNotifyFxn***Function to be called on a registered power event***C Interface**

**Syntax** `status = notifyFxn(eventType, eventArg1, eventArg2, clientArg);`

**Parameters**

PWRM_Event	eventType;	<i>/* type of power event */</i>
Arg	eventArg1;	<i>/* event-specific argument */</i>
Arg	eventArg2;	<i>/* event-specific argument */</i>
Arg	clientArg;	<i>/* arbitrary argument */</i>

**Return Value** PWRM\_NotifyResponse status; */\* returned status \*/*

**Description**

PWRM\_registerNotify registers a function to be called when a specific power event occurs. Clients, which are typically drivers, register notification functions they need to run when a particular power event occurs.

This topic describes the required prototype and behavior of such notification functions. Your application must provide and register these functions. Registered functions are called internally by the PWRM module.

The eventType parameter identifies the type of power event for which the notify function is being called. This parameter has an enumerated type of PWRM\_Event. The values for this parameter are listed in the PWRM\_registerNotify topic.

The eventArg1 and eventArg2 parameters are event-specific arguments. Currently, eventArg1 and eventArg2 are used only for V/F scaling events:

- ❑ **PWRM\_PENDINGSETPOINTCHANGE.** The eventArg1 holds the current setpoint, and eventArg2 holds the pending setpoint.
- ❑ **PWRM\_DONESETPOINTCHANGE.** The eventArg1 holds the previous setpoint, and eventArg2 holds the new setpoint.

The clientArg parameter holds the arbitrary argument passed to PWRM\_registerNotify when this function was registered. This argument may allow one notify function to be used by multiple instances of a driver (that is, the clientArg can be used to identify the instance of the driver that is being notified).

The notification function must return one of the following constants as a status value of type PWRM\_NotifyResponse:

Name	Usage
PWRM_NOTIFYDONE	The client processed the notification function successfully.
PWRM_NOTIFYNOTDONE	The client must wait for interrupt processing to occur before it can proceed. The client must later call the delayedCompletionFxn specified when this function was registered with PWRM_registerNotify.
PWRM_NOTIFYERROR	Notification cannot be processed. Either an internal client error occurred or the client was notified of an event it could not process. (For V/F setpoint changes, the client registers setpoints it can accommodate to avoid this error.) When a client returns this error, the caller of the PWRM function that triggered the notification receives a PWRM_EFAIL return status.

## Constraints and Calling Context

- ❑ The notification function should not call PWRM APIs that trigger a notification event (PWRM\_changeSetpoint and PWRM\_sleepDSP). If such an API is called, the PWRM\_EBUSY status code is returned.

## Example

```

/* notification function prototypes */
PWRM_NotifyResponse myNotifyFxn1(
    PWRM_Event eventType, Arg eventArg1, Arg eventArg2,
    Arg clientArg);
PWRM_NotifyResponse myNotifyFxn2(
    PWRM_Event eventType, Arg eventArg1, Arg eventArg2,
    Arg clientArg);

/* ===== myNotifyFxn1 ===== */
PWRM_NotifyResponse myNotifyFxn1(
    PWRM_Event eventType, Arg eventArg, Arg eventArg2,
    Arg clientArg)
{
    #if VERBOSE
        LOG_printf	TRACE, "\nclient #1 notify,
            PENDINGSETPOINTCHANGE");
        LOG_printf	TRACE, "eventArg=%p, eventArg2=%p",
            eventArg, eventArg2);
        LOG_printf	TRACE, "clientArg=%p", clientArg);
        LOG_printf	TRACE, "signal notify complete");
    #endif

    return(PWRM_NOTIFYDONE); /* notify complete */
}

```

**PWRM\_releaseDependency***Release a dependency that was previously declared***C Interface**

**Syntax**                    `status = PWRM_releaseDependency(resourceID);`

**Parameters**                `Uns                    resourceID;            /* resource ID */`

**Return Value**              `PWRM_Status status;            /* returned status */`

**Reentrant**                    `yes`

**Description**

This function is the companion to PWRM\_setDependency. It releases a resource dependency that was previously set.

Resource IDs are device-specific. They are defined in a PWRM\_Resource enumeration in a device-specific header file. For example, see pwr5509a.h for the 'C5509A.

PWRM\_ETOOMANYCALLS is returned if you call PWRM\_releaseDependency when there are no dependencies currently declared for the specified resource (either because all have been released or because none were set).

PWRM\_releaseDependency returns one of the following constants as a status value of type PWRM\_Status:

<b>Name</b>	<b>Usage</b>
PWRM_SOK	The operation succeeded, and dependency has been released.
PWRM_ETOOMANYCALLS	A dependency was not previously set and was therefore not released.
PWRM_ENOTIMPLEMENTED	The operation failed because resource tracking is not supported.

**Example**

```
/* Release default dependency on CLKOUT to save power*/
PWRM_releaseDependency(PWRM_5509A_CLKOUT);
```

**PWRM\_setDependency***Declare a dependency upon a resource***C Interface**

**Syntax**                    status = PWRM\_setDependency(resourceID);

**Parameters**                Uns                    resourceID;            /\* resource ID \*/

**Return Value**              PWRM\_Status status;            /\* returned status \*/

**Reentrant**                    yes

**Description**                This function sets a dependency on a resource. It is the companion to PWRM\_releaseDependency.

Resource IDs are device-specific. They are defined in a PWRM\_Resource enumeration in a device-specific header file. For example, see pwr5509a.h for the 'C5509A.

PWRM\_setDependency returns one of the following constants as a status value of type PWRM\_Status:

<b>Name</b>	<b>Usage</b>
PWRM_SOK	The operation succeeded, and dependency has been set.
PWRM_ENOTIMPLEMENTED	The operation failed because resource tracking is not supported.

**Example**

```
/* Declare an application dependency upon McBSP0 */
PWRM_setDependency(PWRM_5509A_MCBSP0);

/* Declare application dependency upon DMA domain */
PWRM_setDependency(PWRM_5509A_DMA_DOMAIN);
```



**PWRM\_sleepDSP***Transition the DSP to a new sleep state***C Interface**

**Syntax**                    status = PWRM\_sleepDSP(sleepCode, sleepArg, notifyTimeout);

**Parameters**            Uns                    sleepCode;    /\* new sleep state \*/  
 LgUns                    sleepArg;     /\* sleepCode-specific argument \*/  
 Uns                    notifyTimeout; /\* maximum time to wait for notification \*/

**Return Value**           PWRM\_Status status;        /\* returned status \*/

**Reentrant**                yes

**Description**

PWRM\_sleepDSP transitions the DSP to a new sleep state.

The sleepCode parameter indicates the new sleep state for the DSP. The following constants may be used:

Name	Usage
PWRM_DEEPSLEEP	Put the DSP in deep sleep until a configured interrupt occurs to wake the DSP.
PWRM_SLEEPUNTILRESTART	Idle all DSP clock domains. The only way to wake up is a DSP reset.
PWRM_SNOOZE	Sleep the DSP for the number of milliseconds specified by sleepArg.

A call to PWRM\_sleepDSP with PWRM\_DEEPSLEEP or PWRM\_SNOOZE returns when the DSP awakes from deep sleep or snoozing (respectively). The interrupts that can wake the DSP from deep sleep are specified by the following PWRM Manager Properties: Wakeup interrupt mask, IER0 and Wakeup interrupt mask, IER1.

A call to PWRM\_sleepDSP with PWRM\_SLEEPUNTILRESTART never returns. The use of PWRM\_SLEEPUNTILRESTART indicates that the only way to wake up is a DSP reset.

**Note:**

Snooze mode is currently not implemented.

The sleepArg parameter is a sleepCode-specific argument. Currently, it is used only for PWRM\_SNOOZE mode to indicate the duration (in milliseconds) for snoozing the DSP.

The notifyTimeout parameter is the maximum amount of time (in system clock ticks) to wait for registered notification functions (set by PWRM\_registerNotify) to respond to a delayed completion, before declaring failure and returning PWRM\_ETIMEOUT.

PWRM\_sleepDSP returns one of the following constants as a status value of type PWRM\_Status:

Name	Usage
PWRM_SOK	A successful sleep and wake occurred.
PWRM_EFAIL	A general failure occurred. Could not sleep the DSP.
PWRM_ENOTIMPLEMENTED	The requested sleep mode is not implemented on this platform.
PWRM_EOUTOFRANGE	The operation could not be completed because sleepArg is out of range of the capabilities of PWRM.
PWRM_ETIMEOUT	A registered notification function did not respond within the specified notifyTimeout.
PWRM_EBUSY	The requested operation cannot be performed at this time; PWRM is busy processing a previous request.

Due to the critical system nature of sleep commands, clients that register for sleep notification should make every effort to respond immediately to the sleep event.

The application should treat return values of PWRM\_ETIMEOUT or PWRM\_EFAIL as critical system failures. These values indicate the notification client is unresponsive, and the system is in an unknown state.

### Constraints and Calling Context

- ❑ PWRM\_sleepDSP cannot be called from an HWI.
- ❑ This API cannot be called from a program's main() function.
- ❑ PWRM\_sleepDSP can be called from a SWI only if notifyTimeout is 0.

### Example

```
#define TIMEOUT    10    /* timeout after 10 ticks */

LOG_printf(TRACE, "Putting DSP to deep sleep...\n");
status = PWRM_sleepDSP(PWRM_DEEPSLEEP, 0, TIMEOUT);
LOG_printf(TRACE, "DSP awake from deep sleep");
LOG_printf(TRACE, "Returned 0x%x", status);
```

**PWRM\_unregisterNotify***Unregister for an event notification from PWRM***C Interface**

**Syntax** `status = PWRM_unregisterNotify(notifyHandle);`

**Parameters** `PWRM_NotifyHandle notifyHandle; /* handle to registered function */`

**Return Value** `PWRM_Status status; /* returned status */`

**Reentrant** yes

**Description** PWRM\_unregisterNotify unregisters an event notification that was registered by PWRM\_registerNotify. For example, when an audio codec device is closed, it no longer needs to be notified, and should unregister for event notification.

The notifyHandle parameter is the parameter that was provided by PWRM\_registerNotify when the function was registered.

PWRM\_unregisterNotify returns one of the following constants as a status value of type PWRM\_Status:

Name	Usage
PWRM_SOK	The function was successfully unregistered.
PWRM_EFAIL	A general failure occurred.
PWRM_EINVALIDHANDLE	Operation failed because notifyHandle is invalid.

**Constraints and Calling Context**

- ❑ This API cannot be called from a program's main() function.

**Example**

```
PWRM_NotifyHandle notifyHandle1;

PWRM_registerNotify(PWRM_PENDINGSETPOINTCHANGE,
    ALLSETPOINTSALLOWED, (Fxn)myNotifyFxn1,
    (Arg)0x1111, &notifyHandle1, (Fxn *) &delayFxn1);

PWRM_unregisterNotify(notifyHandle1);
```

## 2.21 QUE Module

The QUE module is the atomic queue manager.

### Functions

- ❑ `QUE_create`. Create an empty queue.
- ❑ `QUE_delete`. Delete an empty queue.
- ❑ `QUE_dequeue`. Remove from front of queue (non-atomically).
- ❑ `QUE_empty`. Test for an empty queue.
- ❑ `QUE_enqueue`. Insert at end of queue (non-atomically).
- ❑ `QUE_get`. Remove element from front of queue (atomically)
- ❑ `QUE_head`. Return element at front of queue.
- ❑ `QUE_insert`. Insert in middle of queue (non-atomically).
- ❑ `QUE_new`. Set a queue to be empty.
- ❑ `QUE_next`. Return next element in queue (non-atomically).
- ❑ `QUE_prev`. Return previous element in queue (non-atomically).
- ❑ `QUE_put`. Put element at end of queue (atomically).
- ❑ `QUE_remove`. Remove from middle of queue (non-atomically).

### Constants, Types, and Structures

```
typedef struct QUE_Obj *QUE_Handle; /* queue obj handle */
struct QUE_Attrs{ /* queue attributes */
    Int dummy; /* DUMMY */
};

QUE_Attrs QUE_ATTRS = { /* default attribute values */
    0,
};

typedef QUE_Elem; /* queue element */
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the QUE Manager Properties and QUE Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

## Instance Configuration Parameters

Name	Type	Default
comment	String	"<add comments here>"

### Description

The QUE module makes available a set of functions that manipulate queue objects accessed through handles of type QUE\_Handle. Each queue contains an ordered sequence of zero or more elements referenced through variables of type QUE\_Elem, which are generally embedded as the first field within a structure. The QUE\_Elem item is used as an internal pointer.

For example, the DEV\_Frame structure, which is used by the SIO Module and DEV Module to enqueue and dequeue I/O buffers, contains a field of type QUE\_Elem:

```

struct DEV_Frame { /* frame object */
    QUE_Elem link; /* must be first field! */
    Ptr addr; /* buffer address */
    size_t size; /* buffer size */
    Arg misc; /* reserved for driver */
    Arg arg; /* user argument */
    Uns cmd; /* mini-driver command */
    Int status; /* status of command */
} DEV_Frame;

```

Many QUE module functions either are passed or return a pointer to an element having the structure defined for QUE elements.

The functions QUE\_put and QUE\_get are atomic in that they manipulate the queue with interrupts disabled. These functions can therefore be used to safely share queues between tasks, or between tasks and SWIs or HWIs. All other QUE functions should only be called by tasks, or by tasks and SWIs or HWIs when they are used in conjunction with some mutual exclusion mechanism (for example, SEM\_pend / SEM\_post, TSK\_disable / TSK\_enable).

Once a queue has been created, use MEM\_alloc to allocate elements for the queue.

### QUE Manager Properties

The following global property can be set for the QUE module in the QUE Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- Object Memory.** The memory segment that contains the QUE objects.

Tconf Name: OBJMEMSEG Type: Reference

Example: `bios.QUE.OBJMEMSEG = prog.get("myMEM");`

## QUE Object Properties

To create a QUE object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var myQue = bios.QUE.create("myQue");
```

The following property can be set for a QUE object in the PRD Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **comment.** Type a comment to identify this QUE object.

Tconf Name: comment

Type: String

Example: `myQue.comment = "my QUE";`

**QUE\_create***Create an empty queue***C Interface**

**Syntax**                    `queue = QUE_create(attrs);`

**Parameters**                `QUE_Attrs *attrs;    /* pointer to queue attributes */`

**Return Value**              `QUE_Handle queue;    /* handle for new queue object */`

**Description**

QUE\_create creates a new queue which is initially empty. If successful, QUE\_create returns the handle of the new queue. If unsuccessful, QUE\_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS\_error, and SYS\_error is configured to abort).

If attrs is NULL, the new queue is assigned a default set of attributes. Otherwise, the queue's attributes are specified through a structure of type QUE\_Attrs.

**Note:**

At present, no attributes are supported for queue objects, and the type QUE\_Attrs is defined as a dummy structure.

All default attribute values are contained in the constant QUE\_ATTRS, which can be assigned to a variable of type QUE\_Attrs prior to calling QUE\_create.

You can also create a queue by declaring a variable of type QUE\_Obj and initializing the queue with QUE\_new.

QUE\_create calls MEM\_alloc to dynamically create the object's data structure. MEM\_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2-205.

**Constraints and Calling Context**

- QUE\_create cannot be called from a SWI or HWI.
- You can reduce the size of your application program by creating objects with the Tconf rather than using the XXX\_create functions.

**See Also**

MEM\_alloc  
 QUE\_empty  
 QUE\_delete  
 SYS\_error

**QUE\_delete***Delete an empty queue***C Interface****Syntax**                   QUE\_delete(queue);**Parameters**               QUE\_Handle queue;   /\* queue handle \*/**Return Value**            Void**Description**            QUE\_delete uses MEM\_free to free the queue object referenced by queue.

QUE\_delete calls MEM\_free to delete the QUE object. MEM\_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- ❑ queue must be empty.
- ❑ QUE\_delete cannot be called from a SWI or HWI.
- ❑ No check is performed to prevent QUE\_delete from being used on a statically-created object. If a program attempts to delete a queue object that was created using Tconf, SYS\_error is called.

**See Also**QUE\_create  
QUE\_empty



**QUE\_dequeue***Remove from front of queue (non-atomically)***C Interface**

**Syntax** `elem = QUE_dequeue(queue);`

**Parameters** `QUE_Handle queue;` /\* queue object handle \*/

**Return Value** `Ptr elem;` /\* pointer to former first element \*/

**Description**

QUE\_dequeue removes the element from the front of queue and returns elem.

The return value, elem, is a pointer to the element at the front of the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

Calling QUE\_dequeue with an empty queue returns the queue itself. However, QUE\_dequeue is non-atomic. Therefore, the method described for QUE\_get of checking to see if a queue is empty and returning the first element otherwise is non-atomic.

---

**Note:**

You should use QUE\_get instead of QUE\_dequeue if multiple threads share a queue. QUE\_get runs atomically and is never interrupted; QUE\_dequeue performs the same action but runs non-atomically. You can use QUE\_dequeue if you disable interrupts or use a synchronization mechanism such as LCK or SEM to protect the queue. An HWI or task that preempts QUE\_dequeue and operates on the same queue can corrupt the data structure.

QUE\_dequeue is somewhat faster than QUE\_get, but you should not use it unless you know your QUE operation cannot be preempted by another thread that operates on the same queue.

---

**See Also**

QUE\_get

**QUE\_empty***Test for an empty queue***C Interface****Syntax** `empty = QUE_empty(queue);`**Parameters** `QUE_Handle queue;` /\* queue object handle \*/**Return Value** `Bool empty;` /\* TRUE if queue is empty \*/**Description** QUE\_empty returns TRUE if there are no elements in queue, and FALSE otherwise.**See Also** QUE\_get

**QUE\_enqueue***Insert at end of queue (non-atomically)***C Interface****Syntax**

QUE\_enqueue(queue, elem);

**Parameters**QUE\_Handle queue; /\* queue object handle \*/  
Ptr elem; /\* pointer to queue element \*/**Return Value**

Void

**Description**

QUE\_enqueue inserts elem at the end of queue.

The elem parameter must be a pointer to an element to be placed in the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

---

**Note:**

Use QUE\_put instead of QUE\_enqueue if multiple threads share a queue. QUE\_put is never interrupted; QUE\_enqueue performs the same action but runs non-atomically. You can use QUE\_enqueue if you disable interrupts or use a synchronization mechanism such as LCK or SEM to protect the queue.

QUE\_enqueue is somewhat faster than QUE\_put, but you should not use it unless you know your QUE operation cannot be preempted by another thread that operates on the same queue.

---

**See Also**

QUE\_put

**QUE\_get***Get element from front of queue (atomically)***C Interface**

**Syntax** `elem = QUE_get(queue);`

**Parameters** `QUE_Handle queue; /* queue object handle */`

**Return Value** `Void *elem; /* pointer to former first element */`

**Description**

QUE\_get removes the element from the front of queue and returns elem.

The return value, elem, is a pointer to the element at the front of the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

Since QUE\_get manipulates the queue with interrupts disabled, the queue can be shared by multiple tasks, or by tasks and SWIs or HWIs.

Calling QUE\_get with an empty queue returns the queue itself. This provides a means for using a single atomic action to check if a queue is empty, and to remove and return the first element if it is not empty:

```
if ((QUE_Handle) (elem = QUE_get(q)) != q)
    ` process elem `
```

---

**Note:**

Use QUE\_get instead of QUE\_dequeue if multiple threads share a queue. QUE\_get is never interrupted; QUE\_dequeue performs the same action but runs non-atomically. You can use QUE\_dequeue if you disable interrupts or use a synchronization mechanism such as LCK or SEM to protect the queue.

QUE\_dequeue is somewhat faster than QUE\_get, but you should not use it unless you know your QUE operation cannot be preempted by another thread that operates on the same queue.

---

**See Also**

QUE\_create  
QUE\_empty  
QUE\_put

**QUE\_head***Return element at front of queue***C Interface**

**Syntax** `elem = QUE_head(queue);`

**Parameters** `QUE_Handle queue; /* queue object handle */`

**Return Value** `QUE_Elem *elem; /* pointer to first element */`

**Description**

QUE\_head returns a pointer to the element at the front of queue. The element is not removed from the queue.

The return value, elem, is a pointer to the element at the front of the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

Calling QUE\_head with an empty queue returns the queue itself.

**See Also**

QUE\_create  
QUE\_empty  
QUE\_put

**QUE\_insert***Insert in middle of queue (non-atomically)***C Interface****Syntax**

QUE\_insert(qelem, elem);

**Parameters**

Ptr            qelem;    /\* element already in queue \*/  
Ptr            elem;     /\* element to be inserted in queue \*/

**Return Value**

Void

**Description**

QUE\_insert inserts elem in the queue in front of qelem.

The qelem parameter is a pointer to an existing element of the QUE. The elem parameter is a pointer to an element to be placed in the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

---

**Note:**

If the queue is shared by multiple tasks, or tasks and SWIs or HWIs, QUE\_insert should be used in conjunction with some mutual exclusion mechanism (for example, SEM\_pend/SEM\_post, TSK\_disable/TSK\_enable).

---

**See Also**

QUE\_head  
QUE\_next  
QUE\_prev  
QUE\_remove

**QUE\_new***Set a queue to be empty***C Interface**

<b>Syntax</b>	QUE_new(queue);
<b>Parameters</b>	QUE_Handle queue; /* pointer to queue object */
<b>Return Value</b>	Void

**Description**

QUE\_new adjusts a queue object to make the queue empty. This operation is not atomic. A typical use of QUE\_new is to initialize a queue object that has been statically declared instead of being created with QUE\_create. Note that if the queue is not empty, the element(s) in the queue are not freed or otherwise handled, but are simply abandoned.

If you created a queue by declaring a variable of type QUE\_Obj, you can initialize the queue with QUE\_new.

**See Also**

QUE\_create  
QUE\_delete  
QUE\_empty

**QUE\_next***Return next element in queue (non-atomically)***C Interface**

**Syntax**                    elem = QUE\_next(qelem);

**Parameters**                Ptr            qelem;    /\* element in queue \*/

**Return Value**            Ptr            elem;    /\* next element in queue \*/

**Description**              QUE\_next returns elem which points to the element in the queue after qelem.

The qelem parameter is a pointer to an existing element of the QUE. The return value, elem, is a pointer to the next element in the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

Since QUE queues are implemented as doubly linked lists with a dummy node at the head, it is possible for QUE\_next to return a pointer to the queue itself. Be careful not to call QUE\_remove(elem) in this case.

---

**Note:**

If the queue is shared by multiple tasks, or tasks and SWIs or HWIs, QUE\_next should be used in conjunction with some mutual exclusion mechanism (for example, SEM\_pend/SEM\_post, TSK\_disable/TSK\_enable).

---

**See Also**

QUE\_get  
QUE\_insert  
QUE\_prev  
QUE\_remove



**QUE\_prev***Return previous element in queue (non-atomically)***C Interface****Syntax**                    elem = QUE\_prev(qelem);**Parameters**                Ptr            qelem;    /\* element in queue \*/**Return Value**              Ptr            elem;     /\* previous element in queue \*/**Description**

QUE\_prev returns elem which points to the element in the queue before qelem.

The qelem parameter is a pointer to an existing element of the QUE. The return value, elem, is a pointer to the previous element in the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

Since QUE queues are implemented as doubly linked lists with a dummy node at the head, it is possible for QUE\_prev to return a pointer to the queue itself. Be careful not to call QUE\_remove(elem) in this case.

**Note:**

If the queue is shared by multiple tasks, or tasks and SWIs or HWIs, QUE\_prev should be used in conjunction with some mutual exclusion mechanism (for example, SEM\_pend/SEM\_post, TSK\_disable/TSK\_enable).

**See Also**

QUE\_head  
 QUE\_insert  
 QUE\_next  
 QUE\_remove

**QUE\_put***Put element at end of queue (atomically)***C Interface**

**Syntax**                    QUE\_put(queue, elem);

**Parameters**                QUE\_Handle queue;    /\* queue object handle \*/  
Void                        \*elem;    /\* pointer to new queue element \*/

**Return Value**            Void

**Description**             QUE\_put puts elem at the end of queue.

The elem parameter is a pointer to an element to be placed at the end of the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

Since QUE\_put manipulates queues with interrupts disabled, queues can be shared by multiple tasks, or by tasks and SWIs or HWIs.

---

**Note:**

Use QUE\_put instead of QUE\_enqueue if multiple threads share a queue. QUE\_put is never interrupted; QUE\_enqueue performs the same action but runs non-atomically. You can use QUE\_enqueue if you disable interrupts or use a synchronization mechanism such as LCK or SEM to protect the queue.

QUE\_enqueue is somewhat faster than QUE\_put, but you should not use it unless you know your QUE operation cannot be preempted by another thread that operates on the same queue.

---

**See Also**                    QUE\_get  
                              QUE\_head

**QUE\_remove***Remove from middle of queue (non-atomically)***C Interface**

<b>Syntax</b>	QUE_remove(qelem);
<b>Parameters</b>	Ptr            qelem;    /* element in queue */
<b>Return Value</b>	Void

**Description**

QUE\_remove removes qelem from the queue.

The qelem parameter is a pointer to an existing element to be removed from the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE\_Elem and is used as an internal pointer.

Since QUE queues are implemented as doubly linked lists with a dummy node at the head, be careful not to remove the header node. This can happen when qelem is the return value of QUE\_next or QUE\_prev. The following code sample shows how qelem should be verified before calling QUE\_remove.

```

QUE_Elem *qelem;

/* get pointer to first element in the queue */
qelem = QUE_head(queue);

/* scan entire queue for desired element */
while (qelem != queue) {
    if(' qelem is the elem we're looking for ') {
        break;
    }
    qelem = QUE_next(qelem);
}
/* make sure qelem is not the queue itself */
if (qelem != queue) {
    QUE_remove(qelem);
}

```

**Note:**

If the queue is shared by multiple tasks, or tasks and SWIs or HWIs, QUE\_remove should be used in conjunction with some mutual exclusion mechanism (for example, SEM\_pend/SEM\_post, TSK\_disable/ TSK\_enable).

**Constraints and  
Calling Context**

QUE\_remove should not be called when qelem is equal to the queue itself.

**See Also**

QUE\_head  
QUE\_insert  
QUE\_next  
QUE\_prev

## 2.22 RTDX Module

The RTDX modules manage the real-time data exchange settings.

### RTDX Data Declaration Macros

- RTDX\_CreateInputChannel
- RTDX\_CreateOutputChannel

### Function Macros

- RTDX\_disableInput
- RTDX\_disableOutput
- RTDX\_enableInput
- RTDX\_enableOutput
- RTDX\_read
- RTDX\_readNB
- RTDX\_sizeofInput
- RTDX\_write

### Channel Test Macros

- RTDX\_channelBusy
- RTDX\_isInputEnabled
- RTDX\_isOutputEnabled

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the RTDX Manager Properties and RTDX Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default (Enum Options)
ENABLERTDX	Bool	true
MODE	EnumString	"JTAG" ("Simulator")
RTDXDATASEG	Reference	prog.get("DARAM")
BUFSIZE	Int16	258
INTERRUPTMASK	Int16	0x00000000

#### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
channelMode	EnumString	"output" ("input")

### Description

The RTDX module provides the data types and functions for:

- Sending data from the target to the host.
- Sending data from the host to the target.



You should allow all interrupts to be disabled inside critical RTDX sections if your application makes any RTDX calls from SWI or TSK threads. If your application does not make RTDX calls from SWI or TSK threads, you may modify bits in this mask to enable specific high-priority interrupts. See the RTDX documentation for details.

Tconf Name: INTERRUPTMASK Type: Int16

Example: `bios.RTDX.INTERRUPTMASK = 0x00000000;`

## RTDX Object Properties

To create an RTDX object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var myRtdx = bios.RTDX.create("myRtdx");
```

The following properties can be set for an RTDX object in the RTDX Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- comment.** Type a comment to identify this RTDX object.

Tconf Name: comment Type: String

Example: `myRtdx.comment = "my RTDX";`
- Channel Mode.** Select output if the RTDX channel handles output from the DSP to the host. Select input if the RTDX channel handles input to the DSP from the host.

Tconf Name: channelMode Type: EnumString

Options: "input", "output"

Example: `myRtdx.channelMode = "output";`

## Examples

The `rtdx.xls` example is in the `TI_DIR\examples\hostapps\rtdx` folder. The examples are described below.

- Ta\_write.asm.** Target to Host transmission example. This example sends 100 consecutive integers starting from 0. In the `rtdx.xls` file, use the `h_read` VB macro to view data on the host.
- Ta\_read.asm.** Host to target transmission example. This example reads 100 integers. Use the `h_write` VB macro of the `rtdx.xls` file to send data to the target.
- Ta\_readNB.asm.** Host to target transmission example. This example reads 100 integers. Use the `h_write` VB macro of the `rtdx.xls` file to send data to the target. This example demonstrates how to use the non-blocking read, `RTDX_readNB`, function.

---

**Note:** Programs must be linked with C run-time libraries and contain the symbol `_main`.

---

**RTDX\_channelBusy***Return status indicating whether data channel is busy***C Interface**

**Syntax** `int RTDX_channelBusy( RTDX_inputChannel *pichan );`

**Parameters** `pichan` */\* Identifier for the input data channel \*/*

**Return Value** `int` */\* Status: 0 = Channel is not busy. \*/*  
*/\* non-zero = Channel is busy. \*/*

**Reentrant** `yes`

**Description** RTDX\_channelBusy is designed to be used in conjunction with RTDX\_readNB. The return value indicates whether the specified data channel is currently in use or not. If a channel is busy reading, the test/control flag (TC) bit of status register 0 (STO) is set to 1. Otherwise, the TC bit is set to 0.

**Constraints and Calling Context**  RTDX\_channelBusy cannot be called by an HWI function.

**See Also** RTDX\_readNB



## **RTDX\_CreateInputChannel** *Declare input channel structure*

### **C Interface**

**Syntax**                    RTDX\_CreateInputChannel( ichan );

**Parameters**                ichan                            /\* Label for the input channel \*/

**Return Value**                none

**Reentrant**                    no

**Description**                This macro declares and initializes to 0, the RTDX data channel for input.

Data channels must be declared as global objects. A data channel can be used either for input or output, but not both. The contents of an input or output data channel are unknown to the user.

A channel can be in one of two states: enabled or disabled. Channels are initialized as disabled.

Channels can be enabled or disabled via a User Interface function. They can also be enabled or disabled remotely from Code Composer or its COM interface.

### **Constraints and Calling Context**

❑ RTDX\_CreateInputChannel cannot be called by an HWI function.

**See Also**                      RTDX\_CreateOutputChannel

**RTDX\_CreateOutputChannel** *Declare output channel structure***C Interface**

**Syntax** RTDX\_CreateOutputChannel( ochan );

**Parameters** ochan /\* Label for the output channel \*/

**Return Value** none

**Reentrant** no

**Description** This macro declares and initializes the RTDX data channels for output.

Data channels must be declared as global objects. A data channel can be used either for input or output, but not both. The contents of an input or output data channel are unknown to the user.

A channel can be in one of two states: enabled or disabled. Channels are initialized as disabled.

Channels can be enabled or disabled via a User Interface function. They can also be enabled or disabled remotely from Code Composer Studio or its OLE interface.

**Constraints and Calling Context**

❑ RTDX\_CreateOutputChannel cannot be called by an HWI function.

**See Also** RTDX\_CreateInputChannel

**RTDX\_disableInput***Disable an input data channel***C Interface****Syntax**                   void RTDX\_disableInput( RTDX\_inputChannel \*ichan );**Parameters**               ichan                       /\* Identifier for the input data channel \*/**Return Value**             void**Reentrant**                 yes**Description**             A call to a disable function causes the specified input channel to be disabled.**Constraints and Calling Context**     ❑ RTDX\_disableInput cannot be called by an HWI function.**See Also**                   RTDX\_disableOutput  
RTDX\_enableInput  
RTDX\_read

**RTDX\_disableOutput** *Disable an output data channel***C Interface**

**Syntax** void RTDX\_disableOutput( RTDX\_outputChannel \*ochan );

**Parameters** ochan /\* Identifier for an output data channel \*/

**Return Value** void

**Reentrant** yes

**Description** A call to a disable function causes the specified data channel to be disabled.

**Constraints and Calling Context**  RTDX\_disableOutput cannot be called by an HWI function.

**See Also** RTDX\_disableInput  
RTDX\_enableOutput  
RTDX\_read

**RTDX\_enableInput** *Enable an input data channel***C Interface**

**Syntax** void RTDX\_enableInput( RTDX\_inputChannel \*ichan );

**Parameters** ochan /\* Identifier for an output data channel \*/  
ichan /\* Identifier for the input data channel \*/

**Return Value** void

**Reentrant** yes

**Description** A call to an enable function causes the specified data channel to be enabled.

**Constraints and Calling Context**  RTDX\_enableInput cannot be called by an HWI function.

**See Also** RTDX\_disableInput  
RTDX\_enableOutput  
RTDX\_read

**RTDX\_enableOutput** *Enable an output data channel***C Interface**

**Syntax** void RTDX\_enableOutput( RTDX\_outputChannel \*ochan );

**Parameters** ochan /\* Identifier for an output data channel \*/

**Return Value** void

**Reentrant** yes

**Description** A call to an enable function causes the specified data channel to be enabled.

**Constraints and Calling Context**  RTDX\_enableOutput cannot be called by an HWI function.

**See Also** RTDX\_disableOutput  
RTDX\_enableInput  
RTDX\_write

**RTDX\_isInputEnabled***Return status of the input data channel***C Interface**

**Syntax** RTDX\_isInputEnabled( ichan );

**Parameter** ichan /\* Identifier for an input channel. \*/

**Return Value** 0 /\* Not enabled. \*/  
non-zero /\* Enabled. \*/

**Reentrant** yes

**Description** The RTDX\_isInputEnabled macro tests to see if an input channel is enabled and sets the test/control flag (TC bit) of status register 0 to 1 if the input channel is enabled. Otherwise, it sets the TC bit to 0.

**Constraints and Calling Context**  RTDX\_isInputEnabled cannot be called by an HWI function.

**See Also** RTDX\_isOutputEnabled

**RTDX\_isOutputEnabled** *Return status of the output data channel***C Interface**

**Syntax** RTDX\_isOutputEnabled(ohan );

**Parameter** ochan /\* Identifier for an output channel. \*/

**Return Value** 0 /\* Not enabled. \*/  
non-zero /\* Enabled. \*/

**Reentrant** yes

**Description** The RTDX\_isOutputEnabled macro tests to see if an output channel is enabled and sets the test/control flag (TC bit) of status register 0 to 1 if the output channel is enabled. Otherwise, it sets the TC bit to 0.

**Constraints and Calling Context**  RTDX\_isOutputEnabled cannot be called by an HWI function.

**See Also** RTDX\_isInputEnabled





**RTDX\_readNB***Read from input channel without blocking***C Interface**

**Syntax**                    int RTDX\_readNB( RTDX\_inputChannel \*ichan, void \*buffer, int bsize );

**Parameters**

ichan	/* Identifier for the input data channel */
buffer	/* A pointer to the buffer that receives the data */
bsize	/* The size of the buffer in address units */

**Return Value**

RTDX_OK	/* Success.*/
0 (zero)	/* Failure. The target buffer is full. */
RTDX_READ_ERROR	/*Channel is currently busy reading. */

**Reentrant**                    yes

**Description**                    RTDX\_readNB is a nonblocking form of the function RTDX\_read. RTDX\_readNB issues a read request to be posted to the specified input data channel and immediately returns. If the channel is not enabled or the channel is currently busy reading, the function returns RTDX\_READ\_ERROR. The function returns 0 if it cannot post the read request due to lack of space in the RTDX target buffer.

When the function RTDX\_readNB is used, the target application notifies the RTDX Host Library that it is ready to receive data but the target application does not wait. Execution of the target application continues immediately. Use the RTDX\_channelBusy and RTDX\_sizeofInput functions to determine when the RTDX Host Library has written data into the target buffer.

When RTDX\_read is used, the target application notifies the RTDX Host Library that it is ready to receive data and then waits for the RTDX Host Library to write data into the target buffer. When the data is received, the target application continues execution.

**Constraints and Calling Context**

❑ RTDX\_readNB cannot be called by an HWI function.

**See Also**

RTDX\_channelBusy  
RTDX\_read  
RTDX\_sizeofInput

---

**RTDX\_sizeofInput** *Return the number of MADUs read from a data channel***C Interface**

**Syntax** `int RTDX_sizeofInput( RTDX_inputChannel *pichan );`

**Parameters** `pichan` */\* Identifier for the input data channel \*/*

**Return Value** `int` */\* Number of sizeof units of data actually \*/*  
*/\* supplied in buffer \*/*

**Reentrant** `yes`

**Description** RTDX\_sizeofInput is designed to be used in conjunction with RTDX\_readNB after a read operation has completed. The function returns the number of sizeof units actually read from the specified data channel into the accumulator (register A).

**Constraints and Calling Context**  RTDX\_sizeofInput cannot be called by an HWI function.

**See Also** RTDX\_readNB

**RTDX\_write***Write to an output channel***C Interface**

**Syntax** `int RTDX_write( RTDX_outputChannel *ochan, void *buffer, int bsize );`

**Parameters**

<code>ochan</code>	<code>/* Identifier for the output data channel */</code>
<code>buffer</code>	<code>/* A pointer to the buffer containing the data */</code>
<code>bsize</code>	<code>/* The size of the buffer in address units */</code>

**Return Value** `int` `/* Status: non-zero = Success. 0 = Failure. */`

**Reentrant** `yes`

**Description** RTDX\_write causes the specified data to be written to the specified output data channel, provided that channel is enabled. On return from the function, the data has been copied out of the specified user buffer and into the RTDX target buffer. If the channel is not enabled, the write operation is suppressed. If the RTDX target buffer is full, Failure is returned.

**Constraints and Calling Context**

- ❑ RTDX\_write cannot be called by an HWI function.

**See Also** RTDX\_read

## 2.23 SEM Module

The SEM module is the semaphore manager.

### Functions

- ❑ SEM\_count. Get current semaphore count
- ❑ SEM\_create. Create a semaphore
- ❑ SEM\_delete. Delete a semaphore
- ❑ SEM\_new. Initialize a semaphore
- ❑ SEM\_pend. Wait for a counting semaphore
- ❑ SEM\_pendBinary. Wait for a binary semaphore
- ❑ SEM\_post. Signal a counting semaphore
- ❑ SEM\_postBinary. Signal a binary semaphore
- ❑ SEM\_reset. Reset semaphore

### Constants, Types, and Structures

```
typedef struct SEM_Obj  *SEM_Handle;
                        /* handle for semaphore object */

struct SEM_Attrs { /* semaphore attributes */
    String name; /* printable name */
};

SEM_Attrs SEM_ATTRS = { /* default attribute values */
    "", /* name */
};
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the SEM Manager Properties and SEM Object Properties topics. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

#### Instance Configuration Parameters

Name	Type	Default
comment	String	"<add comments here>"
count	Int16	0

**Description**

The SEM module makes available a set of functions that manipulate semaphore objects accessed through handles of type SEM\_Handle. Semaphores can be used for task synchronization and mutual exclusion.

Semaphores can be counting semaphores or binary semaphores. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.

- ❑ **Counting semaphores** keep track of the number of times the semaphore has been posted with SEM\_post. This is useful, for example, if you have a group of resources that are shared between tasks. Such tasks might call SEM\_pend to see if a resource is available before using one. SEM\_pend and SEM\_post are for use with counting semaphores.
- ❑ **Binary semaphores** can have only two states: available and unavailable. They can be used to share a single resource between tasks. They can also be used for a basic signaling mechanism, where the semaphore can be posted multiple times and a subsequent call to SEM\_pendBinary clears the count and returns. Binary semaphores do not keep track of the count; they simply track whether the semaphore has been posted or not. SEM\_pendBinary and SEM\_postBinary are for use with binary semaphores.

The MBX module uses a counting semaphore internally to manage the count of free (or full) mailbox elements. Another example of a counting semaphore is an ISR that might fill multiple buffers of data for consumption by a task. After filling each buffer, the ISR puts the buffer on a queue and calls SEM\_post. The task waiting for the data calls SEM\_pend, which simply decrements the semaphore count and returns or blocks if the count is 0. The semaphore count thus tracks the number of full buffers available for the task. The GIO and SIO modules follow this model and use counting semaphores.

The internal data structures used for binary and counting semaphores are the same; the only change is whether semaphore values are incremented and decremented or simply set to zero and non-zero.

SEM\_pend and SEM\_pendBinary are used to wait for a semaphore. The timeout parameter allows the task to wait until a timeout, wait indefinitely, or not wait at all. The return value is used to indicate if the semaphore was signaled successfully.

SEM\_post and SEM\_postBinary are used to signal a semaphore. If a task is waiting for the semaphore, SEM\_post/SEM\_postBinary removes the task from the semaphore queue and puts it on the ready queue. If no



## **SEM\_count**

*Get current semaphore count*

### **C Interface**

**Syntax**

```
count = SEM_count(sem);
```

**Parameters**

```
SEM_Handle sem;    /* semaphore handle */
```

**Return Value**

```
Int          count; /* current semaphore count */
```

**Description**

SEM\_count returns the current value of the semaphore specified by sem.



**SEM\_create***Create a semaphore***C Interface**

**Syntax**                    `sem = SEM_create(count, attrs);`

**Parameters**                `Int            count;        /* initial semaphore count */`  
                               `SEM_Attrs    *attrs;       /* pointer to semaphore attributes */`

**Return Value**              `SEM_Handle sem;       /* handle for new semaphore object */`

**Description**

SEM\_create creates a new semaphore object which is initialized to count. If successful, SEM\_create returns the handle of the new semaphore. If unsuccessful, SEM\_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS\_error, and SYS\_error is configured to abort).

If attrs is NULL, the new semaphore is assigned a default set of attributes. Otherwise, the semaphore's attributes are specified through a structure of type SEM\_Attrs.

```
struct SEM_Attrs { /* semaphore attributes */
    String name; /* printable name */
};
```

Default attribute values are contained in the constant SEM\_ATTRS, which can be assigned to a variable of type SEM\_Attrs before calling SEM\_create.

```
SEM_Attrs SEM_ATTRS = { /* default attribute values */
    "", /* name */
};
```

SEM\_create calls MEM\_alloc to dynamically create the object's data structure. MEM\_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module.

**Constraints and Calling Context**

- ❑ count must be greater than or equal to 0.
- ❑ SEM\_create cannot be called from a SWI or HWI.
- ❑ You can reduce the size of your application by creating objects with Tconf rather than XXX\_create functions.

**See Also**

MEM\_alloc  
SEM\_delete

**SEM\_delete***Delete a semaphore***C Interface**

<b>Syntax</b>	SEM_delete(sem);
<b>Parameters</b>	SEM_Handle sem;     /* semaphore object handle */
<b>Return Value</b>	Void

**Description** SEM\_delete uses MEM\_free to free the semaphore object referenced by sem.

SEM\_delete calls MEM\_free to delete the SEM object. MEM\_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- ❑ No tasks should be pending on sem when SEM\_delete is called.
- ❑ SEM\_delete cannot be called from a SWI or HWI.
- ❑ No check is performed to prevent SEM\_delete from being used on a statically-created object. If a program attempts to delete a semaphore object that was created using Tconf, SYS\_error is called.

**See Also** SEM\_create

**SEM\_new***Initialize semaphore object***C Interface****Syntax**

Void SEM\_new(sem, count);

**Parameters**SEM\_Handle sem; /\* pointer to semaphore object \*/  
Int count; /\* initial semaphore count \*/**Return Value**

Void

**Description**

SEM\_new initializes the semaphore object pointed to by sem with count. The function should be used on a statically created semaphore for initialization purposes only. No task switch occurs when calling SEM\_new.

**Constraints and Calling Context**

- count must be greater than or equal to 0
- no tasks should be pending on the semaphore when SEM\_new is called

**See Also**

QUE\_new



**SEM\_pendBinary***Wait for a binary semaphore***C Interface**

<b>Syntax</b>	<code>status = SEM_pendBinary(sem, timeout);</code>
<b>Parameters</b>	<code>SEM_Handle sem;</code> /* semaphore object handle */ <code>Uns timeout;</code> /* return after this many system clock ticks */
<b>Return Value</b>	<code>Bool status;</code> /* TRUE if successful, FALSE if timeout */

**Description**

`SEM_pendBinary` and `SEM_postBinary` are for use with binary semaphores. These are semaphores that can have only two states: available and unavailable. They can be used to share a single resource between tasks. They can also be used for a basic signaling mechanism, where the semaphore can be posted multiple times and a subsequent call to `SEM_pendBinary` clears the count and returns. Binary semaphores do not keep track of the count; they simply track whether the semaphore has been posted or not.

In contrast, `SEM_pend` and `SEM_post` are for use with counting semaphores, which keep track of the number of times the semaphore has been posted. This is useful, for example, if you have a group of resources that are shared between tasks. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.

If the semaphore count is non-zero (available), `SEM_pendBinary` sets the count to zero (unavailable) and returns TRUE.

If the semaphore count is zero (unavailable), `SEM_pendBinary` suspends execution of this task until `SEM_post` is called or the timeout expires.

If timeout is `SYS_FOREVER`, a task remains suspended until `SEM_postBinary` is called on this semaphore. If timeout is 0, `SEM_pendBinary` returns immediately.

If timeout expires (or timeout is 0) before the semaphore is available, `SEM_pendBinary` returns FALSE. Otherwise `SEM_pendBinary` returns TRUE.

If timeout is not equal to `SYS_FOREVER` or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

A task switch occurs when calling `SEM_pendBinary` if the semaphore count is 0 and timeout is not zero.

**Constraints and Calling Context**

- ❑ This API can be called from a TSK with any timeout value, but if called from an HWI or SWI the timeout must be 0.

- ❑ This API cannot be called from the program's main() function.
- ❑ If you need to call this API within a TSK\_disable/TSK\_enable block, you must use a timeout of 0.
- ❑ This API should not be called from within an IDL function. Doing so prevents analysis tools from gathering run-time information.

**See Also**

SEM\_pend  
SEM\_postBinary

**SEM\_post***Signal a semaphore***C Interface**

<b>Syntax</b>	SEM_post(sem);
<b>Parameters</b>	SEM_Handle sem;     /* semaphore object handle */
<b>Return Value</b>	Void

**Description**

SEM\_pend and SEM\_post are for use with counting semaphores, which keep track of the number of times the semaphore has been posted. This is useful, for example, if you have a group of resources that are shared between tasks.

In contrast, SEM\_pendBinary and SEM\_postBinary are for use with binary semaphores, which can have only an available or unavailable state. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.

SEM\_post readies the first task waiting for the semaphore. If no task is waiting, SEM\_post simply increments the semaphore count and returns.

A task switch occurs when calling SEM\_post if a higher priority task is made ready to run.

**Constraints and Calling Context**

- ❑ When called within an HWI, the code sequence calling SEM\_post must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.
- ❑ If SEM\_post is called from within a TSK\_disable/TSK\_enable block, the semaphore operation is not processed until TSK\_enable is called.

**See Also**

SEM\_pend  
SEM\_postBinary

**SEM\_postBinary***Signal a binary semaphore***C Interface**

<b>Syntax</b>	SEM_postBinary(sem);
<b>Parameters</b>	SEM_Handle sem;     /* semaphore object handle */
<b>Return Value</b>	Void

**Description**

SEM\_pendBinary and SEM\_postBinary are for use with binary semaphores. These are semaphores that can have only two states: available and unavailable. They can be used to share a single resource between tasks. They can also be used for a basic signaling mechanism, where the semaphore can be posted multiple times and a subsequent call to SEM\_pendBinary clears the count and returns. Binary semaphores do not keep track of the count; they simply track whether the semaphore has been posted or not.

In contrast, SEM\_pend and SEM\_post are for use with counting semaphores, which keep track of the number of times the semaphore has been posted. This is useful, for example, if you have a group of resources that are shared between tasks. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.

SEM\_postBinary readies the first task in the list if one or more tasks are waiting. SEM\_postBinary sets the semaphore count to non-zero (available) if no tasks are waiting.

A task switch occurs when calling SEM\_postBinary if a higher priority task is made ready to run.

**Constraints and Calling Context**

- ❑ When called within an HWI, the code sequence calling this API must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.
- ❑ If this API is called from within a TSK\_disable/TSK\_enable block, the semaphore operation is not processed until TSK\_enable is called.

**See Also**

SEM\_post  
SEM\_pendBinary



**SEM\_reset***Reset semaphore count***C Interface****Syntax**

SEM\_reset(sem, count);

**Parameters**SEM\_Handle sem; /\* semaphore object handle \*/  
Int count; /\* semaphore count \*/**Return Value**

Void

**Description**

SEM\_reset resets the semaphore count to count.

No task switch occurs when calling SEM\_reset.

**Constraints and  
Calling Context**

- count must be greater than or equal to 0.
- No tasks should be waiting on the semaphore when SEM\_reset is called.
- SEM\_reset cannot be called by an HWI or a SWI.

**See Also**

SEM\_create

## 2.24 SIO Module

The SIO module is the stream input and output manager.

### Functions

- ❑ SIO\_bufsize. Size of the buffers used by a stream
- ❑ SIO\_create. Create stream
- ❑ SIO\_ctrl. Perform a device-dependent control operation
- ❑ SIO\_delete. Delete stream
- ❑ SIO\_flush. Idle a stream by flushing buffers
- ❑ SIO\_get. Get buffer from stream
- ❑ SIO\_idle. Idle a stream
- ❑ SIO\_issue. Send a buffer to a stream
- ❑ SIO\_put. Put buffer to a stream
- ❑ SIO\_ready. Determine if device is ready
- ❑ SIO\_reclaim. Request a buffer back from a stream
- ❑ SIO\_reclaimx. Request a buffer and frame status back from a stream
- ❑ SIO\_segid. Memory segment used by a stream
- ❑ SIO\_select. Select a ready device
- ❑ SIO\_staticbuf. Acquire static buffer from stream

### Constants, Types, and Structures

```
#define SIO_STANDARD      0 /* open stream for */
                          /* standard streaming model */
#define SIO_ISSUERECLAIM 1 /* open stream for */
                          /* issue/reclaim streaming model */

#define SIO_INPUT        0 /* open for input */
#define SIO_OUTPUT       1 /* open for output */

typedef SIO_Handle;      /* stream object handle */

typedef DEV_Callback SIO_Callback;

struct SIO_Attrs { /* stream attributes */
    Int    nbufs;      /* number of buffers */
    Int    segid;      /* buffer segment ID */
    size_t align;      /* buffer alignment */
    Bool   flush;     /* TRUE->don't block in DEV_idle*/
    Uns    model;     /* SIO_STANDARD, SIO_ISSUERECLAIM*/
    Uns    timeout;    /* passed to DEV_reclaim */
    SIO_Callback *callback;
                          /* initializes callback in DEV_Obj */
} SIO_Attrs;
```

```

SIO_Attrs SIO_ATTRS = {
    2,          /* nbufs */
    0,          /* segid */
    0,          /* align */
    FALSE,     /* flush */
    SIO_STANDARD, /* model */
    SYS_FOREVER /* timeout */
    NULL      /* callback */
};

```

## Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the SIO Manager Properties and SIO Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")
USEISSUERECLAIM	Bool	false

### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
deviceName	Reference	prog.get("dev-name")
controlParameter	String	""
mode	EnumString	"input" ("output")
bufSize	Int16	0x80
numBufs	Int16	2
bufSegId	Reference	prog.get("SIO.OBJMEMSEG")
bufAlign	EnumInt	1 (2, 4, 8, 16, 32, 64, ..., 32768)
flush	Bool	false
modelName	EnumString	"Standard" ("Issue/Reclaim")
allocStaticBuf	Bool	false
timeout	Int16	-1
useCallBackFxn	Bool	false
callBackFxn	Extern	prog.extern("FXN_F_nop")
arg0	Arg	0
arg1	Arg	0

**Description**

The stream manager provides efficient real-time device-independent I/O through a set of functions that manipulate stream objects accessed through handles of type SIO\_Handle. The device independence is afforded by having a common high-level abstraction appropriate for real-time applications, continuous streams of data, that can be associated with a variety of devices. All I/O programming is done in a high-level manner using these stream handles to the devices and the stream manager takes care of dispatching into the underlying device drivers.

For efficiency, streams are treated as sequences of fixed-size buffers of data rather than just sequences of MADUs.

Streams can be opened and closed during program execution using the functions SIO\_create and SIO\_delete, respectively.

The SIO\_issue and SIO\_reclaim function calls are enhancements to the basic DSP/BIOS device model. These functions provide a second usage model for streaming, referred to as the issue/reclaim model. It is a more flexible streaming model that allows clients to supply their own buffers to a stream, and to get them back in the order that they were submitted. The SIO\_issue and SIO\_reclaim functions also provide a user argument that can be used for passing information between the stream client and the stream devices.

Both SWI and TSK threads can be used with the SIO module. However, SWI threads can be used only with the issue/reclaim model, and only then if the timeout parameter is 0. TSK threads can be used with either model.

**SIO Manager Properties**

The following global properties can be set for the SIO module in the SIO Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- Object Memory.** The memory segment that contains the SIO objects created with Tconf.

Tconf Name: OBJMEMSEG Type: Reference

Example: `bios.SIO.OBJMEMSEG = prog.get("myMEM");`

- Use Only Issue/Reclaim Model.** Enable this option if you want the SIO module to use only the issue/reclaim model. If this option is false (the default) you can also use the standard model.

Tconf Name: USEISSUERECLAIM Type: Bool

Example: `bios.SIO.USEISSUERECLAIM = false;`

**SIO Object Properties**

To create an SIO object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var mySio = bios.SIO.create("mySio");
```

The following properties can be set for an SIO object in the SIO Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- comment.** Type a comment to identify this SIO object.

Tconf Name: comment Type: String

Example: `mySio.comment = "my SIO";`
- Device.** Select the device to which you want to bind this SIO object. User-defined devices are listed along with DGN and DPI devices.

Tconf Name: deviceName Type: Reference

Example: `mySio.deviceName = prog.get("UDEVE0");`
- Device Control String.** Type the device suffix to be passed to any devices stacked below the device connected to this stream.

Tconf Name: controlParameter Type: String

Example: `mySio.controlParameter =  
"/split4/codec";`
- Mode.** Select input if this stream is to be used for input to the application program and output if this stream is to be used for output.

Tconf Name: mode Type: EnumString

Options: "input", "output"

Example: `mySio.mode = "input";`
- Buffer size.** If this stream uses the Standard model, this property controls the size of buffers (in MADUs) allocated for use by the stream. If this stream uses the Issue/Reclaim model, the stream can handle buffers of any size.

Tconf Name: bufSize Type: Int16

Example: `mySio.bufSize = 0x80;`
- Number of buffers.** If this stream uses the Standard model, this property controls the number of buffers allocated for use by the stream. If this stream uses the Issue/Reclaim model, the stream can handle up to the specified Number of buffers.

Tconf Name: numBufs Type: Int16

Example: `mySio.numBufs = 2;`
- Place buffers in memory segment.** Select the memory segment to contain the stream buffers if Model is Standard.

Tconf Name: bufSegId Type: Reference

Example: `mySio.bufSegId = prog.get("myMEM");`

- Buffer alignment.** Specify the memory alignment to use for stream buffers if Model is Standard. For example, if you select 16, the buffer must begin at an address that is a multiple of 16. The default is 1, which means the buffer can begin at any address.

Tconf Name: bufAlign Type: EnumInt

Options: 1, 2, 4, 8, 16, 32, 64, ..., 32768

Example: `mySio.bufAlign = 1;`

- Flush.** Check this box if you want the stream to discard all pending data and return without blocking if this object is idled at run-time with SIO\_idle.

Tconf Name: flush Type: Bool

Example: `mySio.flush = false;`

- Model.** Select Standard if you want all buffers to be allocated when the stream is created. Select Issue/Reclaim if your program is to allocate the buffers and supply them using SIO\_issue. Both SWI and TSK threads can be used with the SIO module. However, SWI threads can be used only with the issue/reclaim model, and only then if the timeout parameter is 0. TSK threads can be used with either model.

Tconf Name: modelName Type: EnumString

Options: "Standard", "Issue/Reclaim"

Example: `mySio.modelName = "Standard";`

- Allocate Static Buffer(s).** If this property is set to true, the configuration allocates stream buffers for the user. The SIO\_staticbuf function is used to acquire these buffers from the stream. When the Standard model is used, checking this box causes one buffer more than the Number of buffers property to be allocated. When the Issue/Reclaim model is used, buffers are not normally allocated. Checking this box causes the number of buffers specified by the Number of buffers property to be allocated.

Tconf Name: allocStaticBuf Type: Bool

Example: `mySio.allocStaticBuf = false;`

- Timeout for I/O operation.** This parameter specifies the length of time the I/O operations SIO\_get, SIO\_put, and SIO\_reclaim wait for I/O. The device driver's Dxx\_reclaim function typically uses this timeout while waiting for I/O. If the timeout expires before a buffer is available, the I/O operation returns (-1 \* SYS\_ETIMEOUT) and no buffer is returned.

Tconf Name: timeout Type: Int16

Example: `mySio.timeout = -1;`

- ❑ **use callback function.** Check this box if you want to use this SIO object with a callback function. In most cases, the callback function is SWI\_andnHook or a similar function that posts a SWI. Checking this box allows the SIO object to be used with SWI threads.

Tconf Name: useCallBackFxn Type: Bool

Example: `mySio.useCallBackFxn = false;`

- ❑ **callback function.** A function for the SIO object to call. In most cases, the callback function is SWI\_andnHook or a similar function that posts a SWI. This function gets called by the class driver (see the DIO Adapter) in the class driver's callback function. This callback function in the class driver usually gets called in the mini-driver code as a result of the HWI.

Tconf Name: callBackFxn Type: Extern

Example: `mySio.callBackFxn =  
          prog.extern("SWI_andnHook");`

- ❑ **argument 0.** The first argument to pass to the callback function. If the callback function is SWI\_andnHook, this argument should be a SWI object handle.

Tconf Name: arg0 Type: Arg

Example: `mySio.arg0 = prog.get("mySwi");`

- ❑ **argument 1.** The second argument to pass to the callback function. If the callback function is SWI\_andnHook, this argument should be a value mask.

Tconf Name: arg1 Type: Arg

Example: `mySio.arg1 = 2;`

## **SIO\_bufsize**

*Return the size of the buffers used by a stream*

### **C Interface**

**Syntax**                    `size = SIO_bufsize(stream);`

**Parameters**                `SIO_Handle stream;`

**Return Value**              `size_t        size;`

**Description**                `SIO_bufsize` returns the size of the buffers used by stream.

This API can be used only if the model is SIO\_STANDARD.

**See Also**                    `SIO_segid`



**SIO\_create***Open a stream***C Interface**

**Syntax** `stream = SIO_create(name, mode, bufsize, attrs);`

**Parameters**

String	name;	/* name of device */
Int	mode;	/* SIO_INPUT or SIO_OUTPUT */
size_t	bufsize;	/* stream buffer size */
SIO_Attrs	*attrs;	/* pointer to stream attributes */

**Return Value** `SIO_Handle stream;` /\* stream object handle \*/

**Description**

SIO\_create creates a new stream object and opens the device specified by name. If successful, SIO\_create returns the handle of the new stream object. If unsuccessful, SIO\_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS\_error, and SYS\_error is configured to abort).

Internally, SIO\_create calls Dxx\_open to open a device.

The mode parameter specifies whether the stream is to be used for input (SIO\_INPUT) or output (SIO\_OUTPUT).

If the stream is being opened in SIO\_STANDARD mode, SIO\_create allocates buffers of size bufsize for use by the stream. Initially these buffers are placed on the device todevice queue for input streams, and the device fromdevice queue for output streams.

If the stream is being opened in SIO\_ISSUERECLAIM mode, SIO\_create does not allocate any buffers for the stream. In SIO\_ISSUERECLAIM mode all buffers must be supplied by the client via the SIO\_issue call. It does, however, prepare the stream for a maximum number of buffers of the specified size.

If the attrs parameter is NULL, the new stream is assigned the default set of attributes specified by SIO\_ATTRS. The following stream attributes are currently supported:

```

struct SIO_Attrs { /* stream attributes */
    Int    nbufs;      /* number of buffers */
    Int    segid;     /* buffer segment ID */
    size_t align;     /* buffer alignment */
    Bool   flush;    /* TRUE->don't block in DEV_idle */
    Uns    model;    /* SIO_STANDARD, SIO_ISSUERECLAIM */
    Uns    timeout;  /* passed to DEV_reclaim */
    SIO_Callback *callback;
                    /* initialize callback in DEV_Obj */
} SIO_Attrs;

```

- ❑ **nbufs.** Specifies the number of buffers allocated by the stream in the SIO\_STANDARD usage model, or the number of buffers to prepare for in the SIO\_ISSUERECLAIM usage model. The default value of nbufs is 2. In the SIO\_ISSUERECLAIM usage model, nbufs is the maximum number of buffers that can be outstanding (that is, issued but not reclaimed) at any point in time.
- ❑ **segid.** Specifies the memory segment for stream buffers. Use the memory segment names defined in the configuration. The default value is 0, meaning that buffers are to be allocated from the "Segment for DSP/BIOS objects" property in the MEM Manager Properties.
- ❑ **align.** Specifies the memory alignment for stream buffers. The default value is 0, meaning that no alignment is needed.
- ❑ **flush.** Indicates the desired behavior for an output stream when it is deleted. If flush is TRUE, a call to SIO\_delete causes the stream to discard all pending data and return without blocking. If flush is FALSE, a call to SIO\_delete causes the stream to block until all pending data has been processed. The default value is FALSE.
- ❑ **model.** Indicates the usage model that is to be used with this stream. The two usage models are SIO\_ISSUERECLAIM and SIO\_STANDARD. The default usage model is SIO\_STANDARD.
- ❑ **timeout.** Specifies the length of time the device driver waits for I/O completion before returning an error (for example, SYS\_ETIMEOUT). timeout is usually passed as a parameter to SEM\_pend by the device driver. The default is SYS\_FOREVER which indicates that the driver waits forever. If timeout is SYS\_FOREVER, the task remains suspended until a buffer is available to be returned by the stream. The timeout attribute applies to the I/O operations SIO\_get, SIO\_put, and SIO\_reclaim. If timeout is 0, the I/O operation returns immediately. If the timeout expires before a buffer is available to be returned, the I/O operation returns the value of (-1 \* SYS\_ETIMEOUT). Otherwise the I/O operation returns the number of valid MADUs in the buffer, or -1 multiplied by an error code.

- ❑ **callback.** Specifies a pointer to channel-specific callback information. The SIO\_Callback structure is defined by the SIO module to match the DEV\_Callback structure. This structure contains the callback function and two function arguments. The callback function is typically SWI\_andnHook or a similar function that posts a SWI. Callbacks can only be used with the SIO\_ISSUERECLAIM model.

Existing DEV drivers do not use this callback function. While DEV drivers can be modified to use this callback, it is not recommended. Instead, the IOM device driver model is recommended for drivers that need the SIO callback feature. IOM drivers use the DIO module to interface with the SIO functions.

SIO\_create calls MEM\_alloc to dynamically create the object's data structure. MEM\_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is set by the "Segment for DSP/BIOS objects" property in the MEM Manager Properties.

### Constraints and Calling Context

- ❑ A stream can only be used by one task simultaneously. Catastrophic failure can result if more than one task calls SIO\_get (or SIO\_issue/SIO\_reclaim) on the same input stream, or more than one task calls SIO\_put (or SIO\_issue / SIO\_reclaim) on the same output stream.
- ❑ SIO\_create creates a stream dynamically. Do not call SIO\_create on a stream that was created with Tconf.
- ❑ You can reduce the size of your application program by creating objects with Tconf rather than using the XXX\_create functions. However, streams that are to be used with stacking drivers must be created dynamically with SIO\_create.
- ❑ SIO\_create cannot be called from a SWI or HWI.

### See Also

Dxx\_open  
MEM\_alloc  
SEM\_pend  
SIO\_delete  
SIO\_issue  
SIO\_reclaim  
SYS\_error



**SIO\_delete***Close a stream and free its buffers***C Interface**

**Syntax**                    `status = SIO_delete(stream);`

**Parameters**                `SIO_Handle stream; /* stream object */`

**Return Value**               `Int                status; /* result of operation */`

**Description**

SIO\_delete idles the device before freeing the stream object and buffers.

If the stream being deleted was opened for input, then any pending input data is discarded. If the stream being deleted was opened for output, the method for handling data is determined by the value of the flush field in the SIO\_Attrs structure (passed in with SIO\_create). If flush is TRUE, SIO\_delete discards all pending data and returns without blocking. If flush is FALSE, SIO\_delete blocks until all pending data has been processed by the stream.

SIO\_delete returns SYS\_OK if and only if the operation is successful.

SIO\_delete calls MEM\_free to delete a stream. MEM\_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

Internally, SIO\_delete first calls Dxx\_idle to idle the device. Then it calls Dxx\_close.

**Constraints and Calling Context**

- ❑ SIO\_delete cannot be called from a SWI or HWI.
- ❑ No check is performed to prevent SIO\_delete from being used on a statically-created object. If a program attempts to delete a stream object that was created using Tconf, SYS\_error is called.
- ❑ In SIO\_ISSUERECLAIM mode, all buffers issued to a stream must be reclaimed before SIO\_delete is called. Failing to reclaim such buffers causes a memory leak.

**See Also**

SIO\_create  
SIO\_flush  
SIO\_idle  
Dxx\_idle  
Dxx\_close

**SIO\_flush***Flush a stream***C Interface**

**Syntax**                    status = SIO\_flush(stream);

**Parameters**                SIO\_Handle stream; /\* stream handle \*/

**Return Value**              Int                status; /\* result of operation \*/

**Description**

SIO\_flush causes all pending data to be discarded regardless of the mode of the stream. SIO\_flush differs from SIO\_idle in that SIO\_flush never suspends program execution to complete processing of data, even for a stream created in output mode.

The underlying device connected to stream is idled as a result of calling SIO\_flush. In general, the interrupt is disabled for the device.

One of the purposes of this function is to provide synchronization with the external environment.

SIO\_flush returns SYS\_OK if and only if the stream is successfully idled.

Internally, SIO\_flush calls Dxx\_idle and flushes all pending data.

If a callback was specified in the SIO\_Attrs structure used with SIO\_create, then SIO\_flush performs no processing and returns SYS\_OK.

**Constraints and Calling Context**

- ❑ SIO\_flush cannot be called from an HWI.
- ❑ If SIO\_flush is called from a SWI, no action is performed.

**See Also**

Dxx\_idle  
SIO\_create  
SIO\_idle

**SIO\_get***Get a buffer from stream***C Interface**

<b>Syntax</b>	<code>nmadus = SIO_get(stream, bufp);</code>						
<b>Parameters</b>	<table> <tr> <td><code>SIO_Handle</code></td> <td><code>stream</code></td> <td><code>/* stream handle */</code></td> </tr> <tr> <td><code>Ptr</code></td> <td><code>*bufp;</code></td> <td><code>/* pointer to a buffer */</code></td> </tr> </table>	<code>SIO_Handle</code>	<code>stream</code>	<code>/* stream handle */</code>	<code>Ptr</code>	<code>*bufp;</code>	<code>/* pointer to a buffer */</code>
<code>SIO_Handle</code>	<code>stream</code>	<code>/* stream handle */</code>					
<code>Ptr</code>	<code>*bufp;</code>	<code>/* pointer to a buffer */</code>					
<b>Return Value</b>	<code>Int</code> <code>nmadus;</code> <code>/* number of MADUs read or error if negative */</code>						

**Description**

SIO\_get exchanges an empty buffer with a non-empty buffer from stream. The bufp is an input/output parameter which points to an empty buffer when SIO\_get is called. When SIO\_get returns, bufp points to a new (different) buffer, and nmadus indicates success or failure of the call.

SIO\_get blocks until a buffer can be returned to the caller, or until the stream's timeout attribute expires (see SIO\_create). If a timeout occurs, the value (-1 \* SYS\_ETIMEOUT) is returned. If timeout is not equal to SYS\_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

To indicate success, SIO\_get returns a positive value for nmadus. As a success indicator, nmadus is the number of MADUs received from the stream. To indicate failure, SIO\_get returns a negative value for nmadus. As a failure indicator, nmadus is the actual error code multiplied by -1.

An inconsistency exists between the sizes of buffers in a stream and the return types corresponding to these sizes. While all buffer sizes in a stream are of type size\_t, APIs that return a buffer size return a type of Int. The inconsistency is due to a change in stream buffer sizes and the need to retain the return type for backward compatibility. Because of this inconsistency, it is not possible to return the correct buffer size when the actual buffer size exceeds the size of an Int type. This issue has the following implications:

- ❑ **If the actual buffer size is less than/equal to the maximum positive Int value (15 bits).** Check the return value for negative values, which should be treated as errors. Positive values reflect the correct size.
- ❑ **If the actual buffer size is greater than the maximum positive Int value.** Ignore the return value. There is little room for this situation on 'C55x large model since size\_t is the same as unsigned int. Since the sign in Int takes up one bit, the size\_t type contains just one more bit than an Int. If you are using the 'C55x huge model, size\_t is 32 bits and Int allows positive integers only up to 15 bits.

For other architectures, size\_t is:

- ❑ 'C28x - unsigned long
- ❑ 'C54x/'C55x/'C6x - unsigned int

Since this operation is generally accomplished by redirection rather than by copying data, references to the contents of the buffer pointed to by bufp must be recomputed after the call to SIO\_get.

A task switch occurs when calling SIO\_get if there are no non-empty data buffers in stream.

Internally, SIO\_get calls Dxx\_issue and Dxx\_reclaim for the device.

### Constraints and Calling Context

- ❑ The stream must not be created with attrs.model set to SIO\_ISSUERECLAIM. The results of calling SIO\_get on a stream created for the issue/reclaim streaming model are undefined.
- ❑ SIO\_get cannot be called from a SWI or HWI.
- ❑ This API is callable from the program's main() function only if the stream's configured timeout attribute is 0, or if it is certain that there is a buffer available to be returned.

### See Also

Dxx\_issue  
Dxx\_reclaim  
SIO\_put



**SIO\_idle***Idle a stream***C Interface**

**Syntax**                    `status = SIO_idle(stream);`

**Parameters**                `SIO_Handle stream; /* stream handle */`

**Return Value**              `Int                status; /* result of operation */`

**Description**

If stream is being used for output, SIO\_idle causes any currently buffered data to be transferred to the output device associated with stream. SIO\_idle suspends program execution for as long as is required for the data to be consumed by the underlying device.

If stream is being used for input, SIO\_idle causes any currently buffered data to be discarded. The underlying device connected to stream is idled as a result of calling SIO\_idle. In general, the interrupt is disabled for this device.

If discarding of unrendered output is desired, use SIO\_flush instead.

One of the purposes of this function is to provide synchronization with the external environment.

SIO\_idle returns SYS\_OK if and only if the stream is successfully idled.

Internally, SIO\_idle calls Dxx\_idle to idle the device.

If a callback was specified in the SIO\_Attrs structure used with SIO\_create, then SIO\_idle performs no processing and returns SYS\_OK.

**Constraints and Calling Context**

- SIO\_idle cannot be called from an HWI.
- If SIO\_idle is called from a SWI, no action is performed.

**See Also**

Dxx\_idle  
SIO\_create  
SIO\_flush



the data that it was issued with. `arg` provides a user argument as a method for a client to associate additional information with a particular buffer of data.

`SIO_issue` is used in conjunction with `SIO_reclaim` to operate a stream opened in `SIO_ISSUERECLAIM` mode. The `SIO_issue` call sends a buffer to a stream, and `SIO_reclaim` retrieves a buffer from a stream. In normal operation each `SIO_issue` call is followed by an `SIO_reclaim` call. Short bursts of multiple `SIO_issue` calls can be made without an intervening `SIO_reclaim` call, but over the life of the stream `SIO_issue` and `SIO_reclaim` must be called the same number of times.

At any given point in the life of a stream, the number of `SIO_issue` calls can exceed the number of `SIO_reclaim` calls by a maximum of `nbufs`. The value of `nbufs` is determined by the `SIO_create` call or by setting the Number of buffers property for the object in the configuration.

---

**Note:**

An `SIO_reclaim` call should not be made without at least one outstanding `SIO_issue` call. Calling `SIO_reclaim` with no outstanding `SIO_issue` calls has undefined results.

---

**Constraints and Calling Context**

- ❑ The stream must be created with `attrs.model` set to `SIO_ISSUERECLAIM`.
- ❑ `SIO_issue` cannot be called from an HWI.

**See Also**

`Dxx_issue`  
`SIO_create`  
`SIO_reclaim`

**SIO\_put***Put a buffer to a stream***C Interface**

**Syntax** `nmadus = SIO_put(stream, bufp, nmadus);`

**Parameters**

<code>SIO_Handle</code>	<code>stream;</code>	<i>/* stream handle */</i>
<code>Ptr</code>	<code>*bufp;</code>	<i>/* pointer to a buffer */</i>
<code>size_t</code>	<code>nmadus;</code>	<i>/* number of MADUs in the buffer */</i>

**Return Value** `Int` `nmadus;` */\* number of MADUs, negative if error \*/*

**Description**

SIO\_put exchanges a non-empty buffer with an empty buffer. The bufp parameter is an input/output parameter that points to a non-empty buffer when SIO\_put is called. When SIO\_put returns, bufp points to a new (different) buffer, and nmadus indicates success or failure of the call.

SIO\_put blocks until a buffer can be returned to the caller, or until the stream's timeout attribute expires (see SIO\_create). If a timeout occurs, the value (-1 \* SYS\_ETIMEOUT) is returned. If timeout is not equal to SYS\_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

To indicate success, SIO\_put returns a positive value for nmadus. As a success indicator, nmadus is the number of valid MADUs in the buffer returned by the stream (usually zero). To indicate failure, SIO\_put returns a negative value (the actual error code multiplied by -1).

An inconsistency exists between the sizes of buffers in a stream and the return types corresponding to these sizes. While all buffer sizes in a stream are of type size\_t, APIs that return a buffer size return a type of Int. The inconsistency is due to a change in stream buffer sizes and the need to retain the return type for backward compatibility. Because of this inconsistency, it is not possible to return the correct buffer size when the actual buffer size exceeds the size of an Int type. This issue has the following implications:

- ❑ **If the actual buffer size is less than/equal to the maximum positive Int value (15 bits).** Check the return value for negative values, which should be treated as errors. Positive values reflect the correct size.
- ❑ **If the actual buffer size is greater than the maximum positive Int value.** Ignore the return value. There is little room for this situation on 'C55x large model since size\_t is the same as unsigned int. Since the sign in Int takes up one bit, the size\_t type contains just one more bit than an Int. If you are using the 'C55x huge model, size\_t is 32 bits and Int allows positive integers only up to 15 bits.

Since this operation is generally accomplished by redirection rather than by copying data, references to the contents of the buffer pointed to by `bufp` must be recomputed after the call to `SIO_put`.

A task switch occurs when calling `SIO_put` if there are no empty data buffers in the stream.

Internally, `SIO_put` calls `Dxx_issue` and `Dxx_reclaim` for the device.

### Constraints and Calling Context

- ❑ The stream must not be created with `attrs.model` set to `SIO_ISSUERECLAIM`. The results of calling `SIO_put` on a stream created for the issue/reclaim model are undefined.
- ❑ `SIO_put` cannot be called from a SWI or HWI.
- ❑ This API is callable from the program's `main()` function only if the stream's configured timeout attribute is 0, or if it is certain that there is a buffer available to be returned.

### See Also

`Dxx_issue`  
`Dxx_reclaim`  
`SIO_get`

**SIO\_ready***Determine if device for stream is ready***C Interface**

**Syntax**                    `status = SIO_ready(stream);`

**Parameters**                `SIO_Handle stream;`

**Return Value**             `Int            status;    /* result of operation */`

**Description**

SIO\_ready returns TRUE if a stream is ready for input or output.

If you are using SIO objects with SWI threads, you may want to use SIO\_ready to avoid calling SIO\_reclaim when it may fail because no buffers are available.

SIO\_ready is similar to SIO\_select, except that it does not block. You can prevent SIO\_select from blocking by setting the timeout to zero, however, SIO\_ready is more efficient because SIO\_select performs SEM\_pend with a timeout of zero. SIO\_ready simply polls the stream to see if the device is ready.

**See Also**

SIO\_select

**SIO\_reclaim***Request a buffer back from a stream***C Interface**

**Syntax** `nmadus = SIO_reclaim(stream, pbufp, parg);`

**Parameters**

<code>SIO_Handle</code>	<code>stream;</code>	<code>/* stream handle */</code>
<code>Ptr</code>	<code>*pbufp;</code>	<code>/* pointer to the buffer */</code>
<code>Arg</code>	<code>*parg;</code>	<code>/* pointer to a user argument */</code>

**Return Value** `Int` `nmadus;` `/* number of MADUs or error if negative */`

**Description**

SIO\_reclaim is used to request a buffer back from a stream. It returns a pointer to the buffer, the number of valid MADUs in the buffer, and a user argument (parg). After the SIO\_reclaim call parg points to the same value that was passed in with this buffer using the SIO\_issue call.

If you want to return a frame-specific status along with the buffer, use SIO\_reclaimx instead of SIO\_reclaim.

Internally, SIO\_reclaim calls Dxx\_reclaim, then it gets the frame from the driver's device->fromdevice queue.

If a stream was created in SIO\_OUTPUT mode, then SIO\_reclaim returns an empty buffer, and nmadus is zero, since the buffer is empty. If a stream was opened in SIO\_INPUT mode, SIO\_reclaim returns a non-empty buffer, and nmadus is the number of valid MADUs of data in the buffer.

If SIO\_reclaim is called from a TSK thread, it blocks (in either mode) until a buffer can be returned to the caller, or until the stream's timeout attribute expires (see SIO\_create), and it returns a positive number or zero (indicating success), or a negative number (indicating an error condition). If timeout is not equal to SYS\_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

If SIO\_reclaim is called from a SWI thread, it returns an error if it is called when no buffer is available. SIO\_reclaim never blocks when called from a SWI.

To indicate success, SIO\_reclaim returns a positive value for nmadus. As a success indicator, nmadus is the number of valid MADUs in the buffer. To indicate failure, SIO\_reclaim returns a negative value for nmadus. As a failure indicator, nmadus is the actual error code multiplied by -1.

Failure of SIO\_reclaim indicates that no buffer was returned to the client. Therefore, if SIO\_reclaim fails, the client should not attempt to de-reference pbufp, since it is not guaranteed to contain a valid buffer pointer.

An inconsistency exists between the sizes of buffers in a stream and the return types corresponding to these sizes. While all buffer sizes in a stream are of type size\_t, APIs that return a buffer size return a type of Int. The inconsistency is due to a change in stream buffer sizes and the need to retain the return type for backward compatibility. Because of this inconsistency, it is not possible to return the correct buffer size when the actual buffer size exceeds the size of an Int type. This issue has the following implications:

- ❑ **If the actual buffer size is less than/equal to the maximum positive Int value (15 bits).** Check the return value for negative values, which should be treated as errors. Positive values reflect the correct size.
- ❑ **If the actual buffer size is greater than the maximum positive Int value.** Ignore the return value. There is little room for this situation on 'C55x large model since size\_t is the same as unsigned int. Since the sign in Int takes up one bit, the size\_t type contains just one more bit than an Int. If you are using the 'C55x huge model, size\_t is 32 bits and Int allows positive integers only up to 15 bits.

SIO\_reclaim is used in conjunction with SIO\_issue to operate a stream opened in SIO\_ISSUERECLAIM mode. The SIO\_issue call sends a buffer to a stream, and SIO\_reclaim retrieves a buffer from a stream. In normal operation each SIO\_issue call is followed by an SIO\_reclaim call. Short bursts of multiple SIO\_issue calls can be made without an intervening SIO\_reclaim call, but over the life of the stream SIO\_issue and SIO\_reclaim must be called the same number of times. The number of SIO\_issue calls can exceed the number of SIO\_reclaim calls by a maximum of nbufs at any given time. The value of nbufs is determined by the SIO\_create call or by setting the Number of buffers property for the object in the configuration.

---

**Note:**

An SIO\_reclaim call should not be made without at least one outstanding SIO\_issue call. Calling SIO\_reclaim with no outstanding SIO\_issue calls has undefined results.

---

SIO\_reclaim only returns buffers that were passed in using SIO\_issue. It also returns the buffers in the same order that they were issued.



---

A task switch occurs when calling SIO\_reclaim if timeout is not set to 0, and there are no data buffers available to be returned.

**Constraints and  
Calling Context**

- ❑ The stream must be created with `attrs.model` set to `SIO_ISSUERECLAIM`.
- ❑ There must be at least one outstanding SIO\_issue when an SIO\_reclaim call is made.
- ❑ SIO\_reclaim returns an error if it is called from a SWI when no buffer is available. SIO\_reclaim does not block if called from a SWI.
- ❑ All frames issued to a stream must be reclaimed before closing the stream.
- ❑ SIO\_reclaim cannot be called from a HWI.
- ❑ This API is callable from the program's `main()` function only if the stream's configured timeout attribute is 0, or if it is certain that there is a buffer available to be returned.

**See Also**

Dxx\_reclaim  
SIO\_issue  
SIO\_create  
SIO\_reclaimx

**SIO\_reclaimx***Request a buffer back from a stream, including frame status***C Interface**

**Syntax** `nmadus = SIO_reclaimx(stream, *pbufp, *parg, *pfstatus);`

**Parameters**

`SIO_Handle stream;` /\* stream handle \*/  
`Ptr *pbufp;` /\* pointer to the buffer \*/  
`Arg *parg;` /\* pointer to a user argument \*/  
`Int *pfstatus;` /\* pointer to frame status \*/

**Return Value** `Int nmadus;` /\* number of MADUs or error if negative \*/

**Description**

SIO\_reclaimx is identical to SIO\_reclaim, except that it also returns a frame-specific status in the `Int` pointed to by the `pfstatus` parameter.

The device driver can use the frame-specific status to pass frame-specific status information to the application. This allows the device driver to fill in the status for each frame, and gives the application access to that status.

The returned frame status is valid only if SIO\_reclaimx() returns successfully. If the `nmadus` value returned is negative, the frame status should not be considered accurate.

**Constraints and Calling Context**

- ❑ The stream must be created with `attrs.model` set to `SIO_ISSUERECLAIM`.
- ❑ There must be at least one outstanding SIO\_issue when an SIO\_reclaimx call is made.
- ❑ SIO\_reclaimx returns an error if it is called from a SWI when no buffer is available. SIO\_reclaimx does not block if called from a SWI.
- ❑ All frames issued to a stream must be reclaimed before closing the stream.
- ❑ SIO\_reclaimx cannot be called from a HWI.
- ❑ This API is callable from the program's `main()` function only if the stream's configured timeout attribute is 0, or if it is certain that there is a buffer available to be returned.

**See Also**

SIO\_reclaim

**SIO\_segid***Return the memory segment used by the stream***C Interface****Syntax**                    `segid = SIO_segid(stream);`**Parameters**                `SIO_Handle stream;`**Return Value**             `Int            segid;     /* memory segment ID */`**Description**              `SIO_segid` returns the identifier of the memory segment that stream uses for buffers.**See Also**                    `SIO_bufsize`

**SIO\_select***Select a ready device***C Interface**

**Syntax**                    mask = SIO\_select(streamtab, nstreams, timeout);

**Parameters**            SIO\_Handle streamtab; /\* stream table \*/  
                           Int            nstreams; /\* number of streams \*/  
                           Uns            timeout; /\* return after this many system clock ticks \*/

**Return Value**            Uns            mask; /\* stream ready mask \*/

**Description**

SIO\_select waits until one or more of the streams in the streamtab[] array is ready for I/O (that is, it does not block when an I/O operation is attempted).

streamtab[] is an array of streams where nstreams < 16. The timeout parameter indicates the number of system clock ticks to wait before a stream becomes ready. If timeout is 0, SIO\_select returns immediately. If timeout is SYS\_FOREVER, SIO\_select waits until one of the streams is ready. Otherwise, SIO\_select waits for up to 1 system clock tick less than timeout due to granularity in system timekeeping.

The return value is a mask indicating which streams are ready for I/O. A 1 in bit position j indicates the stream streamtab[j] is ready.

SIO\_select results in a context switch if no streams are ready for I/O.

Internally, SIO\_select calls Dxx\_ready to determine if the device is ready for an I/O operation.

SIO\_ready is similar to SIO\_select, except that it does not block. You can prevent SIO\_select from blocking by setting the timeout to zero, however, SIO\_ready is more efficient in this situation because SIO\_select performs SEM\_pend with a timeout of zero. SIO\_ready simply polls the stream to see if the device is ready.

For the SIO\_STANDARD model in SIO\_INPUT mode only, if stream I/O has not been started (that is, if SIO\_get has not been called), SIO\_select calls Dxx\_issue for all empty frames to start the device.

**Constraints and  
Calling Context**

- ❑ streamtab must contain handles of type SIO\_Handle returned from prior calls to SIO\_create.
- ❑ streamtab[] is an array of streams; streamtab[i] corresponds to bit position i in mask.
- ❑ SIO\_select cannot be called from an HWI.
- ❑ SIO\_select can only be called from a SWI if the timeout value is zero.

**See Also**

Dxx\_ready  
SIO\_get  
SIO\_put  
SIO\_ready  
SIO\_reclaim

**SIO\_staticbuf***Acquire static buffer from stream***C Interface**

**Syntax** `nmadus = SIO_staticbuf(stream, bufp);`

**Parameters** `SIO_Handle stream; /* stream handle */`  
`Ptr *bufp; /* pointer to a buffer */`

**Return Value** `Int nmadus; /* number of MADUs in buffer */`

**Description**

SIO\_staticbuf returns buffers for static streams that were configured statically. Buffers are allocated for static streams by checking the Allocate Static Buffer(s) check box for the related SIO object.

SIO\_staticbuf returns the size of the buffer or 0 if no more buffers are available from the stream.

An inconsistency exists between the sizes of buffers in a stream and the return types corresponding to these sizes. While all buffer sizes in a stream are of type size\_t, APIs that return a buffer size return a type of Int. This due to a change in stream buffer sizes and the need to retain the return type for backward compatibility. Because of this inconsistency, it is not possible to return the correct buffer size when the actual buffer size exceeds the size of an Int type. This issue has the following implications:

- ❑ **If the actual buffer size is less than/equal to the maximum positive Int value (15 bits).** Check the return value for negative values, which indicate errors. Positive values reflect the correct size.
- ❑ **If the actual buffer size is greater than the maximum positive Int value.** Ignore the return value. There is little room for this situation on 'C55x large model since size\_t is the same as unsigned int. Since the sign in Int takes up one bit, the size\_t type contains just one more bit than an Int. If you are using the 'C55x huge model, size\_t is 32 bits and Int allows positive integers only up to 15 bits.

SIO\_staticbuf can be called multiple times for SIO\_ISSUERECLAIM model streams.

SIO\_staticbuf must be called to acquire all static buffers before calling SIO\_get, SIO\_put, SIO\_issue or SIO\_reclaim.

**Constraints and Calling Context**

- ❑ SIO\_staticbuf should only be called for streams that are defined statically using Tconf.
- ❑ SIO\_staticbuf should only be called for static streams whose "Allocate Static Buffer(s)" property has been set to true.
- ❑ SIO\_staticbuf cannot be called after SIO\_get, SIO\_put, SIO\_issue or SIO\_reclaim have been called for the given stream.
- ❑ SIO\_staticbuf cannot be called from an HWI.

**See Also**

SIO\_get

## 2.25 STS Module

The STS module is the statistics objects manager.

### Functions

- ❑ STS\_add. Update statistics using provided value
- ❑ STS\_delta. Update statistics using difference between provided value and setpoint
- ❑ STS\_reset. Reset values stored in STS object
- ❑ STS\_set. Save a setpoint value

### Constants, Types, and Structures

```
struct STS_Obj {
    LgInt    num;        /* count */
    LgInt    acc;        /* total value */
    LgInt    max;        /* maximum value */
}
```

---

#### Note:

STS objects should not be shared across threads. Therefore, STS\_add, STS\_delta, STS\_reset, and STS\_set are not reentrant.

---

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the STS Manager Properties and STS Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

#### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

#### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
previousVal	Int32	0
unitType	EnumString	"Not time based" ("High resolution time based", "Low resolution time based")
operation	EnumString	"Nothing" ("A * x", "A * x + B", "(A * x + B) / C")
numA	Int32	1



Name	Type	Default (Enum Options)
numB	Int32	0
numC	Int32	1

## Description

The STS module manages objects called statistics accumulators. Each STS object accumulates the following statistical information about an arbitrary 32-bit wide data series:

- Count.** The number of values in an application-supplied data series
- Total.** The sum of the individual data values in this series
- Maximum.** The largest value already encountered in this series

Using the count and total, the Statistics View analysis tool calculates the average on the host.

Statistics are accumulated in 32-bit variables on the target and in 64-bit variables on the host. When the host polls the target for real-time statistics, it resets the variables on the target. This minimizes space requirements on the target while allowing you to keep statistics for long test runs.

## Default STS Tracing

In the RTA Control Panel, you can enable statistics tracing for the following modules by marking the appropriate checkbox. You can also set the HWI Object Properties to perform various STS operations on registers, addresses, or pointers.

Except for tracing TSK execution, your program does not need to include any calls to STS functions in order to gather these statistics. The default units for the statistics values are shown in Table 2-6.

Table 2-6. *Statistics Units for HWI, PIP, PRD, and SWI Modules*

Module	Units
HWI	Gather statistics on monitored values within HWIs
PIP	Number of frames read from or written to data pipe (count only)
PRD	Number of ticks elapsed from time that the PRD object is ready to run to end of execution
SWI	Instruction cycles elapsed from time posted to completion
TSK	Instruction cycles elapsed from time TSK is made ready to run until the application calls TSK_deltatime.

## Custom STS Objects

You can create custom STS objects using Tconf. The STS\_add operation updates the count, total, and maximum using the value you provide. The STS\_set operation sets a previous value. The STS\_delta

operation accumulates the difference between the value you pass and the previous value and updates the previous value to the value you pass.

By using custom STS objects and the STS operations, you can do the following:

- ❑ **Count the number of occurrences of an event.** You can pass a value of 0 to STS\_add. The count statistic tracks how many times your program calls STS\_add for this STS object.
- ❑ **Track the maximum and average values for a variable in your program.** For example, suppose you pass amplitude values to STS\_add. The count tracks how many times your program calls STS\_add for this STS object. The total is the sum of all the amplitudes. The maximum is the largest value. The Statistics View calculates the average amplitude.
- ❑ **Track the minimum value for a variable in your program.** Negate the values you are monitoring and pass them to STS\_add. The maximum is the negative of the minimum value.
- ❑ **Time events or monitor incremental differences in a value.** For example, suppose you want to measure the time between hardware interrupts. You would call STS\_set when the program begins running and STS\_delta each time the interrupt routine runs, passing the result of CLK\_gettime each time. STS\_delta subtracts the previous value from the current value. The count tracks how many times the interrupt routine was performed. The maximum is the largest number of clock counts between interrupt routines. The Statistics View also calculates the average number of clock counts.
- ❑ **Monitor differences between actual values and desired values.** For example, suppose you want to make sure a value stays within a certain range. Subtract the midpoint of the range from the value and pass the absolute value of the result to STS\_add. The count tracks how many times your program calls STS\_add for this STS object. The total is the sum of all deviations from the middle of the range. The maximum is the largest deviation. The Statistics View calculates the average deviation.

You can further customize the statistics data by setting the STS Object Properties to apply a printf format to the Total, Max, and Average fields in the Statistics View window and choosing a formula to apply to the data values on the host.

## **Statistics Data Gathering by the Statistics View Analysis Tool**

The statistics manager allows the creation of any number of statistics objects, which in turn can be used by the application to accumulate simple statistics about a time series. This information includes the 32-bit



- ❑ **prev.** The initial 32-bit history value to use in this object.

Tconf Name: `previousVal` Type: `Int32`

Example: `mySts.previousVal = 0;`
- ❑ **unit type.** The unit type property enables you to choose the type of time base units.

  - Not time based. If you select this unit type, the values are displayed in the Statistics View without applying any conversion.
  - High-resolution time based. If you select this type, the Statistics View, by default, presents results in units of instruction cycles.
  - Low-resolution time based. If you select this unit type, the default Statistics View presents results in timer interrupt units.

Tconf Name: `unitType` Type: `EnumString`

Options: `"Not time based", "High resolution time based", "Low resolution time based"`

Example: `mySts.unitType = "Not time based";`
- ❑ **host operation.** The expression evaluated (by the host) on the data for this object before it is displayed by the Statistics View real-time analysis tool. The operation can be:

  - $A \times X$
  - $A \times X + B$
  - $(A \times X + B) / C$

Tconf Name: `operation` Type: `EnumString`

Options: `"Nothing", "A * x", "A * x + B", "(A * x + B) / C"`

Example: `mySts.operation = "Nothing";`
- ❑ **A, B, C.** The integer parameters used by the expression specified by the Host Operation property above.

Tconf Name: `numA` Type: `Int32`

Tconf Name: `numB` Type: `Int32`

Tconf Name: `numC` Type: `Int32`

Example: `mySts.numA = 1;`  
`mySts.numB = 0;`  
`mySts.numC = 1;`

**STS\_add***Update statistics using the provided value***C Interface**

**Syntax** STS\_add(sts, value);

**Parameters** STS\_Handle sts; /\* statistics object handle \*/  
LgInt value; /\* new value to update statistics object \*/

**Return Value** Void

**Reentrant** no

**Description** STS\_add updates a custom STS object's Total, Count, and Max fields using the data value you provide.

For example, suppose your program passes 32-bit amplitude values to STS\_add. The Count field tracks how many times your program calls STS\_add for this STS object. The Total field tracks the total of all the amplitudes. The Max field holds the largest value passed to this point. The Statistics View analysis tool calculates the average amplitude.

You can count the occurrences of an event by passing a dummy value (such as 0) to STS\_add and watching the Count field.

You can view the statistics values with the Statistics View analysis tool by enabling statistics in the DSP/BIOS→RTA Control Panel window and choosing your custom STS object in the DSP/BIOS→Statistics View window.

**See Also** STS\_delta  
STS\_reset  
STS\_set  
TRC\_disable  
TRC\_enable

**STS\_delta***Update statistics using difference between provided value & setpoint***C Interface****Syntax** STS\_delta(sts,value);**Parameters** STS\_Handle sts; /\* statistics object handle \*/  
LgInt value; /\* new value to update statistics object \*/**Return Value** Void**Reentrant** no**Description** Each STS object contains a previous value that can be initialized with Tconf or with a call to STS\_set. A call to STS\_delta subtracts the previous value from the value it is passed and then invokes STS\_add with the result to update the statistics. STS\_delta also updates the previous value with the value it is passed.

STS\_delta can be used in conjunction with STS\_set to monitor the difference between a variable and a desired value or to benchmark program performance. You can benchmark code by using paired calls to STS\_set and STS\_delta that pass the value provided by CLK\_gettime.

```
STS_set(&sts, CLK_gettime());
    "processing to be benchmarked"
STS_delta(&sts, CLK_gettime());
```

**Constraints and Calling Context**

- ❑ Before the first call to STS\_delta is made, the previous value of the STS object should be initialized either with a call to STS\_set or by setting the prev property of the STS object using Tconf.

**Example**

```
STS_set(&sts, targetValue);
    "processing"
STS_delta(&sts, currentValue);
    "processing"
STS_delta(&sts, currentValue);
```

**See Also**

STS\_add  
STS\_reset  
STS\_set  
CLK\_gettime  
CLK\_gettime  
PRD\_getticks  
TRC\_disable  
TRC\_enable

**STS\_reset***Reset the values stored in an STS object***C Interface**

<b>Syntax</b>	STS_reset(sts);
<b>Parameters</b>	STS_Handle sts;      /* statistics object handle */
<b>Return Value</b>	Void

**Reentrant**            no

**Description**            STS\_reset resets the values stored in an STS object. The Count and Total fields are set to 0 and the Max field is set to the largest negative number. STS\_reset does not modify the value set by STS\_set.

After the Statistics View analysis tool polls statistics data on the target, it performs STS\_reset internally. This keeps the 32-bit total and count values from wrapping back to 0 on the target. The host accumulates these values as 64-bit numbers to allow a much larger range than can be stored on the target.

**Example**                    STS\_reset(&sts);  
                              STS\_set(&sts, value);

**See Also**                    STS\_add  
                              STS\_delta  
                              STS\_set  
                              TRC\_disable  
                              TRC\_enable

**STS\_set***Save a value for STS\_delta***C Interface****Syntax** STS\_set(sts, value);**Parameters** STS\_Handle sts; /\* statistics object handle \*/  
LgInt value; /\* new value to update statistics object \*/**Return Value** Void**Reentrant** no**Description** STS\_set can be used in conjunction with STS\_delta to monitor the difference between a variable and a desired value or to benchmark program performance. STS\_set saves a value as the previous value in an STS object. STS\_delta subtracts this saved value from the value it is passed and invokes STS\_add with the result.

STS\_delta also updates the previous value with the value it was passed. Depending on what you are measuring, you can need to use STS\_set to reset the previous value before the next call to STS\_delta.

You can also set a previous value for an STS object in the configuration. STS\_set changes this value.

See STS\_delta for details on how to use the value you set with STS\_set.

**Example** This example gathers performance information for the processing between STS\_set and STS\_delta.

```
STS_set(&sts, CLK_gettime());  
    "processing to be benchmarked"  
STS_delta(&sts, CLK_gettime());
```

This example gathers information about a value's deviation from the desired value.

```
STS_set(&sts, targetValue);  
    "processing"  
STS_delta(&sts, currentValue);  
    "processing"  
STS_delta(&sts, currentValue);  
    "processing"  
STS_delta(&sts, currentValue);
```

This example gathers information about a value's difference from a base value.



```
STS_set(&sts, baseValue);  
    "processing"  
STS_delta(&sts, currentValue);  
STS_set(&sts, baseValue);  
    "processing"  
STS_delta(&sts, currentValue);  
STS_set(&sts, baseValue);
```

**See Also**

STS\_add  
STS\_delta  
STS\_reset  
TRC\_disable  
TRC\_enable

## 2.26 SWI Module

The SWI module is the software interrupt manager.

### Functions

- ❑ SWI\_andn. Clear bits from SWI's mailbox; post if becomes 0.
- ❑ SWI\_andnHook. Specialized version of SWI\_andn for use as hook function for configured DSP/BIOS objects. Both its arguments are of type (Arg).
- ❑ SWI\_create. Create a software interrupt.
- ❑ SWI\_dec. Decrement SWI's mailbox value; post if becomes 0.
- ❑ SWI\_delete. Delete a software interrupt.
- ❑ SWI\_disable. Disable software interrupts.
- ❑ SWI\_enable. Enable software interrupts.
- ❑ SWI\_getattrs. Get attributes of a software interrupt.
- ❑ SWI\_getmbox. Return the mailbox value of the SWI when it started running.
- ❑ SWI\_getpri. Return a SWI's priority mask.
- ❑ SWI\_inc. Increment SWI's mailbox value and post the SWI.
- ❑ SWI\_isSWI. Check current thread calling context.
- ❑ SWI\_or. Or mask with value contained in SWI's mailbox and post the SWI.
- ❑ SWI\_orHook. Specialized version of SWI\_or for use as hook function for configured DSP/BIOS objects. Both its arguments are of type (Arg).
- ❑ SWI\_post. Post a software interrupt.
- ❑ SWI\_raisepri. Raise a SWI's priority.
- ❑ SWI\_restorepri. Restore a SWI's priority.
- ❑ SWI\_self. Return address of currently executing SWI object.
- ❑ SWI\_setattrs. Set attributes of a software interrupt.

### Constants, Types, and Structures

```
typedef struct SWI_Obj SWI_Handle;

SWI_MINPRI = 1; /* Minimum execution priority */
SWI_MAXPRI = 14 /* Maximum execution priority */
```

```

struct SWI_Attrs {      /* SWI attributes */
    SWI_Fxn  fxn;      /* address of SWI function */
    Arg      arg0;     /* first arg to function */
    Arg      arg1;     /* second arg to function */
    Int      priority; /* Priority of SWI object */
    Uns      mailbox;  /* check for SWI posting */
};

SWI_Attrs SWI_ATTRS = { /* Default attribute values */
    (SWI_Fxn)FXN_F_nop, /* SWI function */
    0,                  /* arg0 */
    0,                  /* arg1 */
    1,                  /* priority */
    0                   /* mailbox */
};

```

## Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the SWI Manager Properties and SWI Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

### Module Configuration Parameters

Name	Type	Default
OBJMEMSEG	Reference	prog.get("DARAM")

### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
fxn	Extern	prog.extern("FXN_F_nop")
priority	EnumInt	1 (0 to 14)
mailbox	Int16	0
arg0	Arg	0
arg1	Arg	0

## Description

The SWI module manages software interrupt service routines, which are patterned after HWI hardware interrupt service routines.

DSP/BIOS manages four distinct levels of execution threads: hardware interrupt service routines, software interrupt routines, tasks, and background idle functions. A software interrupt is an object that encapsulates a function to be executed and a priority. Software interrupts are prioritized, preempt tasks, and are preempted by hardware interrupt service routines.

**Note:**

SWI functions are called after the processor register state has been saved. SWI functions can be written in C or assembly and must follow the C calling conventions described in the compiler manual.

---

**Note: RTS Functions Callable from TSK Threads Only**

Many runtime support (RTS) functions use lock and unlock functions to prevent reentrancy. However, DSP/BIOS SWI and HWI threads cannot call LCK\_pend and LCK\_post. As a result, RTS functions that call LCK\_pend or LCK\_post *must not be called in the context of a SWI or HWI thread*. For a list of RTS functions that should not be called from a SWI or an HWI function, see “LCK\_pend” on page 2-180.

---

The C++ new operator calls malloc, which in turn calls LCK\_pend. As a result, the new operator cannot be used in the context of a SWI or HWI thread.

---

Each software interrupt has a priority level. A software interrupt preempts any lower-priority software interrupt currently executing.

A target program uses an API call to post a SWI object. This causes the SWI module to schedule execution of the software interrupt's function. When a SWI is posted by an API call, the SWI object's function is not executed immediately. Instead, the function is scheduled for execution. DSP/BIOS uses the SWI's priority to determine whether to preempt the thread currently running. Note that if a SWI is posted several times before it begins running, (because HWIs and higher priority interrupts are running,) when the SWI does eventually run, it will run only one time.

Software interrupts can be posted for execution with a call to SWI\_post or a number of other SWI functions. Each SWI object has a 16-bit mailbox which is used either to determine whether to post the SWI or as a value that can be evaluated within the SWI's function. SWI\_andn and SWI\_dec post the SWI if the mailbox value transitions to 0. SWI\_or and SWI\_inc also modify the mailbox value. (SWI\_or sets bits, and SWI\_andn clears bits.)

	Treat mailbox as bitmask	Treat mailbox as counter	Does not modify mailbox
Always post	SWI_or	SWI_inc	SWI_post
Post if becomes 0	SWI_andn	SWI_dec	

The SWI\_disable and SWI\_enable operations allow you to post several SWIs and enable them all for execution at the same time. The SWI priorities then determine which SWI runs first.

All SWIs run to completion; you cannot suspend a SWI while it waits for something (for example, a device) to be ready. So, you can use the mailbox to tell the SWI when all the devices and other conditions it relies on are ready. Within a SWI processing function, a call to SWI\_getmbox returns the value of the mailbox when the SWI started running. Note that the mailbox is automatically reset to its original value when a SWI runs; however, SWI\_getmbox will return the saved mailbox value from when the SWI started execution.

Software interrupts can have up to 15 priority levels. The highest level is SWI\_MAXPRI (14). The lowest is SWI\_MINPRI (0). The priority level of 0 is reserved for the KNL\_swi object, which runs the task (TSK) scheduler.

A SWI preempts any currently running SWI with a lower priority. If two SWIs with the same priority level have been posted, the SWI that was posted first runs first. HWIs in turn preempt any currently running SWI, allowing the target to respond quickly to hardware peripherals.

Interrupt threads (including HWIs and SWIs) are all executed using the same stack. A context switch is performed when a new thread is added to the top of the stack. The SWI module automatically saves the processor's registers before running a higher-priority SWI that preempts a lower-priority SWI. After the higher-priority SWI finishes running, the registers are restored and the lower-priority SWI can run if no other higher-priority SWI has been posted. (A separate task stack is used by each task thread.)

See the *Code Composer Studio* online tutorial for more information on how to post SWIs and scheduling issues for the Software Interrupt manager.

## SWI Manager Properties

The following global property can be set for the SWI module in the SWI Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **Object Memory.** The memory segment that contains the SWI objects.

Tconf Name: OBJMEMSEG Type: Reference

Example: `bios.SWI.OBJMEMSEG = prog.get("myMEM");`

## SWI Object Properties

To create a SWI object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var mySwi = bios.SWI.create("mySwi");
```

If you cannot create a new SWI object (an error occurs or the Insert SWI item is inactive in the DSP/BIOS Configuration Tool), try increasing the Stack Size property in the MEM Manager Properties before adding a SWI object or a SWI priority level.

The following properties can be set for a SWI object in the SWI Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **comment.** Type a comment to identify this SWI object.

Tconf Name: comment Type: String

Example: `mySwi.comment = "my SWI";`

- ❑ **function.** The function to execute. If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. (The DSP/BIOS Configuration Tool generates assembly code, which must use leading underscores when referencing C functions or labels.) If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.

Tconf Name: fxn Type: Extern

Example: `mySwi.fxn = prog.extern("swiFxn");`

- ❑ **priority.** This property shows the numeric priority level for this SWI object. SWIs can have up to 15 priority levels. The highest level is SWI\_MAXPRI (14). The lowest is SWI\_MINPRI (0). The priority level of 0 is reserved for the KNL\_swi object, which runs the task scheduler. Instead of typing a number in the DSP/BIOS Configuration Tool, you change the relative priority levels of SWI objects by dragging the objects in the ordered collection view.

Tconf Name: priority Type: EnumInt

Options: 0 to 14

Example: `mySwi.priority = 1;`

- ❑ **mailbox.** The initial value of the 16-bit word used to determine if this SWI should be posted.  
Tconf Name: mailbox Type: Int16  
Example: `mySwi.mailbox = 7;`
- ❑ **arg0, arg1.** Two arbitrary pointer type (Arg) arguments to the above configured user function.  
Tconf Name: arg0 Type: Arg  
Tconf Name: arg1 Type: Arg  
Example: `mySwi.arg0 = 0;`

**SWI\_andn***Clear bits from SWI's mailbox and post if mailbox becomes 0***C Interface**

**Syntax** SWI\_andn(swi, mask);

**Parameters** SWI\_Handle swi; /\* SWI object handle\*/  
Uns mask /\* inverse value to be ANDed \*/

**Return Value** Void

**Reentrant** yes

**Description** SWI\_andn is used to conditionally post a software interrupt. SWI\_andn clears the bits specified by a mask from SWI's internal mailbox. If SWI's mailbox becomes 0, SWI\_andn posts the SWI. The bitwise logical operation performed is:

```
mailbox = mailbox AND (NOT MASK)
```

For example, if multiple conditions that all be met before a SWI can run, you should use a different bit in the mailbox for each condition. When a condition is met, clear the bit for that condition.

SWI\_andn results in a context switch if the SWI's mailbox becomes zero and the SWI has higher priority than the currently executing thread.

You specify a SWI's initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes.

---

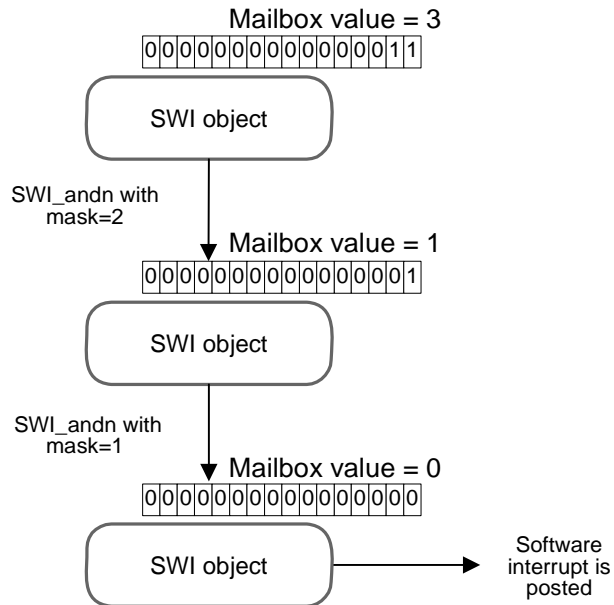
**Note:**

Use the specialized version, SWI\_andnHook, when SWI\_andn functionality is required for a DSP/BIOS object hook function.

---



The following figure shows an example of how a mailbox with an initial value of 3 can be cleared by two calls to SWI\_andn with values of 2 and 1. The entire mailbox could also be cleared with a single call to SWI\_andn with a value of 3.



### Constraints and Calling Context

- ❑ If this function is invoked outside the context of an HWI, interrupts must be enabled.
- ❑ When called within an HWI, the code sequence calling SWI\_andn must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

### Example

```
/* ===== ioReady ===== */
void ioReady(unsigned int mask)
{
    /* clear bits of "ready mask" */
    SWI_andn(&copySWI, mask);
}
```

### See Also

SWI\_andnHook  
 SWI\_dec  
 SWI\_getmbox  
 SWI\_inc  
 SWI\_or  
 SWI\_orHook  
 SWI\_post  
 SWI\_self

**SWI\_andnHook***Clear bits from SWI's mailbox and post if mailbox becomes 0***C Interface****Syntax** SWI\_andnHook(swi, mask);**Parameters**  
Arg swi; /\* SWI object handle\*/  
Arg mask /\* value to be ANDed \*/**Return Value** Void**Reentrant** yes**Description** SWI\_andnHook is a specialized version of SWI\_andn for use as hook function for configured DSP/BIOS objects. SWI\_andnHook clears the bits specified by a mask from SWI's internal mailbox and also moves the arguments to the correct registers for proper interface with low level DSP/BIOS assembly code. If SWI's mailbox becomes 0, SWI\_andnHook posts the SWI. The bitwise logical operation performed is:

```
mailbox = mailbox AND (NOT MASK)
```

For example, if there are multiple conditions that must all be met before a SWI can run, you should use a different bit in the mailbox for each condition. When a condition is met, clear the bit for that condition.

SWI\_andnHook results in a context switch if the SWI's mailbox becomes zero and the SWI has higher priority than the currently executing thread.

You specify a SWI's initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes.

**Constraints and Calling Context**

- ❑ If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- ❑ When called within an HWI, the code sequence calling SWI\_andnHook must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

**Example**

```
/* ===== ioReady ===== */

Void ioReady(unsigned int mask)
{
    /* clear bits of "ready mask" */
    SWI_andnHook(&copySWI, mask);
}
```

**See Also**SWI\_andn  
SWI\_orHook

**SWI\_create***Create a software interrupt***C Interface**

<b>Syntax</b>	<code>swi = SWI_create(attrs);</code>
<b>Parameters</b>	<code>SWI_Attrs *attrs; /* pointer to swi attributes */</code>
<b>Return Value</b>	<code>SWI_Handle swi; /* handle for new swi object */</code>

**Description**

SWI\_create creates a new SWI object. If successful, SWI\_create returns the handle of the new SWI object. If unsuccessful, SWI\_create returns NULL unless it aborts. For example, SWI\_create can abort if it directly or indirectly calls SYS\_error, and SYS\_error is configured to abort.

The attrs parameter, which can be either NULL or a pointer to a structure that contains attributes for the object to be created, facilitates setting the SWI object's attributes. The SWI object's attributes are specified through a structure of type SWI\_attrs defined as follows:

```
struct SWI_Attrs {
    SWI_Fxn  fxn;
    Arg      arg0;
    Arg      arg1;
    Int      priority;
    Uns      mailbox;
};
```

If attrs is NULL, the new SWI object is assigned the following default attributes.

```
SWI_Attrs SWI_ATTRS = { /* Default attribute values */
    (SWI_Fxn)FXN_F_nop, /* SWI function */
    0, /* arg0 */
    0, /* arg1 */
    1, /* priority */
    0 /* mailbox */
};
```

The fxn attribute, which is the address of the SWI function, serves as the entry point of the software interrupt service routine.

The arg0 and arg1 attributes specify the arguments passed to the SWI function, fxn.

The priority attribute specifies the SWI object's execution priority and must range from 0 to 14. The highest level is SWI\_MAXPRI (14). The lowest is SWI\_MINPRI (0). The priority level of 0 is reserved for the KNL\_swi object, which runs the task scheduler.

The mailbox attribute is used either to determine whether to post the SWI or as a value that can be evaluated within the SWI function.

All default attribute values are contained in the constant SWI\_ATTRS, which can be assigned to a variable of type SWI\_Attrs prior to calling SWI\_create.

SWI\_create calls MEM\_alloc to dynamically create the object's data structure. MEM\_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2–205.

### **Constraints and Calling Context**

- ❑ SWI\_create cannot be called from a SWI or HWI.
- ❑ The fxn attribute cannot be NULL.
- ❑ The priority attribute must be less than or equal to 14 and greater than or equal to 1.

### **See Also**

SWI\_delete  
SWI\_getattrs  
SWI\_setattrs  
SYS\_error

**SWI\_dec***Decrement SWI's mailbox value and post if mailbox becomes 0***C Interface**

<b>Syntax</b>	SWI_dec(swi);
<b>Parameters</b>	SWI_Handle swi;      /* SWI object handle*/
<b>Return Value</b>	Void

**Reentrant**                    yes

**Description**                SWI\_dec is used to conditionally post a software interrupt. SWI\_dec decrements the value in SWI's mailbox by 1. If SWI's mailbox value becomes 0, SWI\_dec posts the SWI. You can increment a mailbox value by using SWI\_inc, which always posts the SWI.

For example, you would use SWI\_dec if you wanted to post a SWI after a number of occurrences of an event.

You specify a SWI's initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes.

SWI\_dec results in a context switch if the SWI's mailbox becomes zero and the SWI has higher priority than the currently executing thread.

**Constraints and Calling Context**

- ❑ If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- ❑ When called within an HWI, the code sequence calling SWI\_dec must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

**Example**

```
/* ===== strikeOrBall ===== */

Void strikeOrBall(unsigned int call)
{
    if (call == 1) {
        /* initial mailbox value is 3 */
        SWI_dec(&strikeoutSwi);
    }
    if (call == 2) {
        /* initial mailbox value is 4 */
        SWI_dec(&walkSwi);
    }
}
```

**See Also**                    SWI\_inc

**SWI\_delete***Delete a software interrupt***C Interface**

<b>Syntax</b>	SWI_delete(swi);
<b>Parameters</b>	SWI_Handle swi;      /* SWI object handle */
<b>Return Value</b>	Void

**Description**

SWI\_delete uses MEM\_free to free the SWI object referenced by swi.

SWI\_delete calls MEM\_free to delete the SWI object. MEM\_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- ❑ swi cannot be the currently executing SWI object (SWI\_self)
- ❑ SWI\_delete cannot be called from a SWI or HWI.
- ❑ SWI\_delete must not be used to delete a statically-created SWI object. No check is performed to prevent SWI\_delete from being used on a statically-created object. If a program attempts to delete a SWI object that was created using Tconf, SYS\_error is called.

**See Also**

SWI\_create  
SWI\_getattrs  
SWI\_setattrs  
SYS\_error

**SWI\_disable***Disable software interrupts***C Interface****Syntax** SWI\_disable();**Parameters** Void**Return Value** Void**Reentrant** yes

**Description** SWI\_disable and SWI\_enable control software interrupt processing. SWI\_disable disables all other SWI functions from running until SWI\_enable is called. Hardware interrupts can still run.

SWI\_disable and SWI\_enable let you ensure that statements that must be performed together during critical processing are not interrupted. In the following example, the critical section is not preempted by any SWIs.

```
SWI_disable();
    ^critical section^
SWI_enable();
```

You can also use SWI\_disable and SWI\_enable to post several SWIs and have them performed in priority order. See the following example.

SWI\_disable calls can be nested. The number of nesting levels is stored internally. SWI handling is not reenabled until SWI\_enable has been called as many times as SWI\_disable.

**Constraints and Calling Context**

- ❑ The calls to HWI\_enter and HWI\_exit required in any HWIs that schedule SWIs automatically disable and reenables SWI handling. You should not call SWI\_disable or SWI\_enable within a HWI.
- ❑ SWI\_disable cannot be called from the program's main() function.
- ❑ Do not call SWI\_enable when SWIs are already enabled. If you do, a subsequent call to SWI\_disable does not disable SWI processing.

**Example**

```
/* ===== postEm ===== */
Void postEm
{
    SWI_disable();
    SWI_post(&encoderSwi);
    SWI_andn(&copySwi, mask);
    SWI_dec(&strikeoutSwi);
    SWI_enable();
}
```

**See Also**

HWI\_disable  
SWI\_enable

**SWI\_enable***Enable software interrupts***C Interface****Syntax** SWI\_enable();**Parameters** Void**Return Value** Void**Reentrant** yes**Description**

SWI\_disable and SWI\_enable control software interrupt processing. SWI\_disable disables all other SWI functions from running until SWI\_enable is called. Hardware interrupts can still run. See the SWI\_disable section for details.

SWI\_disable calls can be nested. The number of nesting levels is stored internally. SWI handling is not be reenabled until SWI\_enable has been called as many times as SWI\_disable.

SWI\_enable results in a context switch if a higher-priority SWI is ready to run.

**Constraints and Calling Context**

- ❑ The calls to HWI\_enter and HWI\_exit are required in any HWI that schedules SWIs. They automatically disable and reenable SWI handling. You should not call SWI\_disable or SWI\_enable within a HWI.
- ❑ SWI\_enable cannot be called from the program's main() function.
- ❑ Do not call SWI\_enable when SWIs are already enabled. If you do so, the subsequent call to SWI\_disable will not disable SWI processing.

**See Also**

HWI\_disable  
HWI\_enable  
SWI\_disable



**SWI\_getattrs***Get attributes of a software interrupt***C Interface**

**Syntax**                    SWI\_getattrs(swi, attrs);

**Parameters**                SWI\_Handle swi;        /\* handle of the swi \*/  
                               SWI\_Attrs \*attrs;     /\* pointer to swi attributes \*/

**Return Value**              Void

**Description**

SWI\_getattrs retrieves attributes of an existing SWI object.

The swi parameter specifies the address of the SWI object whose attributes are to be retrieved. The attrs parameter, which is the pointer to a structure that contains the retrieved attributes for the SWI object, facilitates retrieval of the attributes of the SWI object.

The SWI object's attributes are specified through a structure of type SWI\_attrs defined as follows:

```
struct SWI_Attrs {
    SWI_Fxn  fxn;
    Arg      arg0;
    Arg      arg1;
    Int      priority;
    Uns      mailbox;
};
```

The fxn attribute, which is the address of the SWI function, serves as the entry point of the software interrupt service routine.

The arg0 and arg1 attributes specify the arguments passed to the SWI function, fxn.

The priority attribute specifies the SWI object's execution priority and ranges from 0 to 14. The highest level is SWI\_MAXPRI (14). The lowest is SWI\_MINPRI (0). The priority level of 0 is reserved for the KNL\_swi object, which runs the task scheduler.

The mailbox attribute is used either to determine whether to post the SWI or as a value that can be evaluated within the SWI function.

The following example uses SWI\_getattrs:

```
extern SWI_Handle swi;
SWI_Attrs attrs;

SWI_getattrs(swi, &attrs);
attrs.priority = 5;
SWI_setattrs(swi, &attrs);
```

**Constraints and  
Calling Context**

- ❑ SWI\_getattrs cannot be called from a SWI or HWI.
- ❑ The attrs parameter cannot be NULL.

**See Also**

SWI\_create  
SWI\_delete  
SWI\_setattrs

**SWI\_getmbox***Return a SWI's mailbox value***C Interface**

**Syntax**                    num = Uns SWI\_getmbox();

**Parameters**                Void

**Return Value**              Uns            num        /\* mailbox value \*/

**Reentrant**                    yes

**Description**

SWI\_getmbox returns the value that SWI's mailbox had when the SWI started running. DSP/BIOS saves the mailbox value internally so that SWI\_getmbox can access it at any point within a SWI object's function. DSP/BIOS then automatically resets the mailbox to its initial value (defined with Tconf) so that other threads can continue to use the SWI's mailbox.

SWI\_getmbox should only be called within a function run by a SWI object.

When called from with the context of a SWI, the value returned by SWI\_getmbox is zero if the SWI was posted by a call to SWI\_andn, SWI\_andnHook, or SWI\_dec. Therefore, SWI\_getmbox provides relevant information only if the SWI was posted by a call to SWI\_inc, SWI\_or, SWI\_orHook, or SWI\_post.

**Constraints and Calling Context**

- ❑ SWI\_getmbox cannot be called from the context of an HWI or TSK.
- ❑ SWI\_getmbox cannot be called from a program's main() function.

**Example**

This call could be used within a SWI object's function to use the mailbox value within the function. For example, if you use SWI\_or or SWI\_inc to post a SWI, different mailbox values can require different processing.

```
swicount = SWI_getmbox();
```

**See Also**

SWI\_andn  
 SWI\_andnHook  
 SWI\_dec  
 SWI\_inc  
 SWI\_or  
 SWI\_orHook  
 SWI\_post  
 SWI\_self

**SWI\_getpri***Return a SWI's priority mask***C Interface**

**Syntax**                    `key = SWI_getpri(swi);`

**Parameters**                `SWI_Handle swi;        /* SWI object handle*/`

**Return Value**              `Uns            key        /* Priority mask of swi */`

**Reentrant**                    `yes`

**Description**                `SWI_getpri` returns the priority mask of the SWI passed in as the argument.

**Example**                      `/* Get the priority key of swi1 */`  
`key = SWI_getpri(&swi1);`

`/* Get the priorities of swi1 and swi3 */`  
`key = SWI_getpri(&swi1) | SWI_getpri(&swi3);`

**See Also**                    `SWI_raisepri`  
`SWI_restorepri`

**SWI\_inc***Increment SWI's mailbox value and post the SWI***C Interface**

<b>Syntax</b>	SWI_inc(swi);
<b>Parameters</b>	SWI_Handle swi;      /* SWI object handle*/
<b>Return Value</b>	Void

**Reentrant**                      no

**Description**                      SWI\_inc increments the value in SWI's mailbox by 1 and posts the SWI regardless of the resulting mailbox value. You can decrement a mailbox value using SWI\_dec, which only posts the SWI if the mailbox value is 0.

If a SWI is posted several times before it has a chance to begin executing, because HWIs and higher priority SWIs are running, the SWI only runs one time. If this situation occurs, you can use SWI\_inc to post the SWI. Within the SWI's function, you could then use SWI\_getmbox to find out how many times this SWI has been posted since the last time it was executed.

You specify a SWI's initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes. To get the mailbox value, use SWI\_getmbox.

SWI\_inc results in a context switch if the SWI is higher priority than the currently executing thread.

**Constraints and Calling Context**

- ❑ If this macro (API) is invoked outside the context of an Hwi, interrupts must be enabled.
- ❑ When called within an Hwi, the code sequence calling SWI\_inc must be either wrapped within an Hwi\_enter/Hwi\_exit pair or invoked by the Hwi dispatcher.

**Example**

```
extern SWI_ObjMySwi;
/* ===== AddAndProcess ===== */
Void AddAndProcess(int count)

    int i;
    for (i = 1; I <= count; ++i)
        SWI_inc(&MySwi);
}
```

**See Also**

SWI\_dec  
SWI\_getmbox

**SWI\_isSWI***Check to see if called in the context of a SWI***C Interface****Syntax**                    result = SWI\_isSWI(Void);**Parameters**                Void**Return Value**            Bool            result;     /\* TRUE if in SWI context, FALSE otherwise \*/**Reentrant**                 yes**Description**             This macro returns TRUE when it is called within the context of a SWI or PRD function. This applies no matter whether the SWI was posted by an HWI, TSK, or IDL thread. This macro returns FALSE in all other contexts.

In previous versions of DSP/BIOS, calling SWI\_isSWI() from a task switch hook resulted in TRUE. This is no longer the case; task switch hooks are identified as part of the TSK context.

**See Also**                    HWI\_isHWI  
                                  TSK\_isTSK

**SWI\_or**

*OR mask with the value contained in SWI's mailbox field*

**C Interface**

**Syntax** SWI\_or(swi, mask);

**Parameters** SWI\_Handle swi; /\* SWI object handle\*/  
Uns mask; /\* value to be ORed \*/

**Return Value** Void

**Reentrant** no

**Description** SWI\_or is used to post a software interrupt. SWI\_or sets the bits specified by a mask in SWI's mailbox. SWI\_or posts the SWI regardless of the resulting mailbox value. The bitwise logical operation performed on the mailbox value is:

```
mailbox = mailbox OR mask
```

You specify a SWI's initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes. To get the mailbox value, use SWI\_getmbox.

For example, you might use SWI\_or to post a SWI if any of three events should cause a SWI to be executed, but you want the SWI's function to be able to tell which event occurred. Each event would correspond to a different bit in the mailbox.

SWI\_or results in a context switch if the SWI is higher priority than the currently executing thread.

**Note:**

Use the specialized version, SWI\_orHook, when SWI\_or functionality is required for a DSP/BIOS object hook function.

**Constraints and Calling Context**

- If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- When called within an HWI, the code sequence calling SWI\_or must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

**See Also**

SWI\_andn  
SWI\_orHook

**SWI\_orHook***OR mask with the value contained in SWI's mailbox field***C Interface**

**Syntax** SWI\_orHook(swi, mask);

**Parameters** Arg swi; /\* SWI object handle\*/  
Arg mask; /\* value to be ORed \*/

**Return Value** Void

**Reentrant** no

**Description** SWI\_orHook is used to post a software interrupt, and should be used when hook functionality is required for DSP/BIOS hook objects. SWI\_orHook sets the bits specified by a mask in SWI's mailbox and also moves the arguments to the correct registers for interfacing with low level DSP/BIOS assembly code. SWI\_orHook posts the SWI regardless of the resulting mailbox value. The bitwise logical operation performed on the mailbox value is:

```
mailbox = mailbox OR mask
```

You specify a SWI's initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes. To get the mailbox value, use SWI\_getmbox.

For example, you might use SWI\_orHook to post a SWI if any of three events should cause a SWI to be executed, but you want the SWI's function to be able to tell which event occurred. Each event would correspond to a different bit in the mailbox.

SWI\_orHook results in a context switch if the SWI is higher priority than the currently executing thread.

**Note:**

Use the specialized version, SWI\_orHook, when SWI\_or functionality is required for a DSP/BIOS object hook function.

**Constraints and Calling Context**

- If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- When called within an HWI, the code sequence calling SWI\_orHook must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

**See Also** SWI\_andnHook  
SWI\_or



**SWI\_post***Post a software interrupt***C Interface**

<b>Syntax</b>	SWI_post(swi);
<b>Parameters</b>	SWI_Handle swi;      /* SWI object handle*/
<b>Return Value</b>	Void

**Reentrant**                      yes

**Description**                      SWI\_post is used to post a software interrupt regardless of the mailbox value. No change is made to the SWI object's mailbox value.

To have a PRD object post a SWI object's function, you can set `_SWI_post` as the function property of a PRD object and the name of the SWI object you want to post its function as the `arg0` property.

SWI\_post results in a context switch if the SWI is higher priority than the currently executing thread.

**Constraints and Calling Context**

- ❑ If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- ❑ When called within an HWI, the code sequence calling SWI\_post must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

**See Also**

SWI\_andn  
 SWI\_dec  
 SWI\_getmbox  
 SWI\_inc  
 SWI\_or  
 SWI\_self

**SWI\_raisepri***Raise a SWI's priority***C Interface**

**Syntax**                   key = SWI\_raisepri(mask);

**Parameters**            Uns            mask;     /\* mask of desired priority level \*/

**Return Value**         Uns            key;     /\* key for use with SWI\_restorepri \*/

**Reentrant**                yes

**Description**            SWI\_raisepri is used to raise the priority of the currently running SWI to the priority mask passed in as the argument. SWI\_raisepri can be used in conjunction with SWI\_restorepri to provide a mutual exclusion mechanism without disabling SWIs.

SWI\_raisepri should be called before a shared resource is accessed, and SWI\_restorepri should be called after the access to the shared resource.

A call to SWI\_raisepri not followed by a SWI\_restorepri keeps the SWI's priority for the rest of the processing at the raised level. A SWI\_post of the SWI posts the SWI at its original priority level.

A SWI object's execution priority must range from 0 to 14. The highest level is SWI\_MAXPRI (14). The lowest is SWI\_MINPRI (0). Priority zero (0) is reserved for the KNL\_swi object, which runs the task scheduler.

SWI\_raisepri never lowers the current SWI priority.

**Constraints and Calling Context**

❑ SWI\_raisepri cannot be called from an HWI or TSK level.

**Example**

```
/* raise priority to the priority of swi_1 */
key = SWI_raisepri(SWI_getpri(&swi_1));
--- access shared resource ---
SWI_restore(key);
```

**See Also**

SWI\_getpri  
SWI\_restorepri

**SWI\_restorepri***Restore a SWI's priority***C Interface**

**Syntax** SWI\_restorepri(key);

**Parameters** Uns key; /\* key to restore original priority level \*/

**Return Value** Void

**Reentrant** yes

**Description** SWI\_restorepri restores the priority to the SWI's priority prior to the SWI\_raisepri call returning the key. SWI\_restorepri can be used in conjunction with SWI\_raisepri to provide a mutual exclusion mechanism without disabling all SWIs.

SWI\_raisepri should be called right before the shared resource is referenced, and SWI\_restorepri should be called after the reference to the shared resource.

**Constraints and Calling Context**

- ❑ SWI\_restorepri cannot be called from an HWI or TSK level.
- ❑ SWI\_restorepri cannot be called from the program's main() function.

**Example**

```
/* raise priority to the priority of swi_1 */
key = SWI_raisepri(SWI_getpri(&swi_1));
--- access shared resource ---
SWI_restore(key);
```

**See Also**

SWI\_getpri  
SWI\_raisepri

**SWI\_self***Return address of currently executing SWI object***C Interface****Syntax** `curswi = SWI_self();`**Parameters** Void**Return Value** SWI\_Handle swi; /\* handle for current swi object \*/**Reentrant** yes**Description** SWI\_self returns the address of the currently executing SWI.**Constraints and Calling Context**

- ❑ SWI\_self cannot be called from an HWI or TSK level.
- ❑ SWI\_self cannot be called from the program's main() function.

**Example** You can use SWI\_self if you want a SWI to repost itself:

```
SWI_post(SWI_self());
```

**See Also**

- SWI\_andn
- SWI\_getmbox
- SWI\_post

**SWI\_setattrs***Set attributes of a software interrupt***C Interface**

<b>Syntax</b>	SWI_setattrs(swi, attrs);
<b>Parameters</b>	SWI_Handle swi;     /* handle of the swi */ SWI_Attrs *attrs;   /* pointer to swi attributes */
<b>Return Value</b>	Void

**Description**

SWI\_setattrs sets attributes of an existing SWI object.

The swi parameter specifies the address of the SWI object whose attributes are to be set.

The attrs parameter, which can be either NULL or a pointer to a structure that contains attributes for the SWI object, facilitates setting the attributes of the SWI object. If attrs is NULL, the new SWI object is assigned a default set of attributes. Otherwise, the SWI object's attributes are specified through a structure of type SWI\_attrs defined as follows:

```
struct SWI_Attrs {
    SWI_Fxn  fxn;
    Arg      arg0;
    Arg      arg1;
    Int      priority;
    Uns      mailbox;
};
```

The fxn attribute, which is the address of the swi function, serves as the entry point of the software interrupt service routine.

The arg0 and arg1 attributes specify the arguments passed to the swi function, fxn.

The priority attribute specifies the SWI object's execution priority and must range from 1 to 14. Priority 14 is the highest priority. You cannot use a priority of 0; that priority is reserved for the system SWI that runs the TSK scheduler.

The mailbox attribute is used either to determine whether to post the SWI or as a value that can be evaluated within the SWI function.

All default attribute values are contained in the constant SWI\_ATTRS, which can be assigned to a variable of type SWI\_Attrs prior to calling SWI\_setattrs.

The following example uses SWI\_setattrs:

```
extern SWI_Handle swi;  
SWI_Attrs attrs;  
  
SWI_getattrs(swi, &attrs);  
attrs.priority = 5;  
SWI_setattrs(swi, &attrs);
```

**Constraints and  
Calling Context**

- ❑ SWI\_setattrs must not be used to set the attributes of a SWI that is preempted or is ready to run.
- ❑ The fxn attribute cannot be NULL.
- ❑ The priority attribute must be less than or equal to 14 and greater than or equal to 1.

**See Also**

SWI\_create  
SWI\_delete  
SWI\_getattrs

## 2.27 SYS Module

The SYS modules manages system settings.

### Functions

- ❑ SYS\_abort. Abort program execution
- ❑ SYS\_atexit. Stack an exit handler
- ❑ SYS\_error. Flag error condition
- ❑ SYS\_exit. Terminate program execution
- ❑ SYS\_printf. Formatted output
- ❑ SYS\_putchar. Output a single character
- ❑ SYS\_sprintf. Formatted output to string buffer
- ❑ SYS\_vprintf. Formatted output, variable argument list
- ❑ SYS\_vsprintf. Output formatted data

### Constants, Types, and Structures

```
#define SYS_FOREVER    (Uns)-1 /* wait forever */
#define SYS_POLL      (Uns)0  /* don't wait */

#define SYS_OK        0 /* no error */
#define SYS_EALLOC    1 /* memory alloc error */
#define SYS_EFREE     2 /* memory free error */
#define SYS_ENODEV    3 /* dev driver not found */
#define SYS_EBUSY     4 /* device driver busy */
#define SYS_EINVAL    5 /* invalid parameter */
#define SYS_EBADIO    6 /* I/O failure */
#define SYS_EMODE     7 /* bad mode for driver */
#define SYS_EDOMAIN   8 /* domain error */
#define SYS_ETIMEOUT  9 /* call timed out */
#define SYS_EEOF      10 /* end-of-file */
#define SYS_EDEAD     11 /* deleted obj */
#define SYS_EBADOBJ   12 /* invalid object */
#define SYS_ENOTIMPL  13 /* action not implemented */
#define SYS_ENOTFOUND 14 /* resource not found */

#define SYS_EUSER    256 /* user errors start here */

#define SYS_NUMHANDLERS 8 /* # of atexit handlers */

extern String SYS_errors[]; /* error string array */
```

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the SYS Manager Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

## Module Configuration Parameters

Name	Type	Default
TRACESIZE	Numeric	512
TRACESEG	Reference	prog.get("DARAM")
ABORTFXN	Extern	prog.extern("UTL_doAbort")
ERRORFXN	Extern	prog.extern("UTL_doError")
EXITFXN	Extern	prog.extern("UTL_halt")
PUTCFXN	Extern	prog.extern("UTL_doPutc")

### Description

The SYS module makes available a set of general-purpose functions that provide basic system services, such as halting program execution and printing formatted text. In general, each SYS function is patterned after a similar function normally found in the standard C library.

SYS does not directly use the services of any other DSP/BIOS module and therefore resides at the bottom of the system. Other DSP/BIOS modules use the services provided by SYS in lieu of similar C library functions. The SYS module provides hooks for binding system-specific code. This allows programs to gain control wherever other DSP/BIOS modules call one of the SYS functions.

### SYS Manager Properties

The following global properties can be set for the SYS module in the SYS Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script.

- ❑ **Trace Buffer Size.** The size of the buffer that contains system trace information. This system trace buffer can be viewed only by looking for the SYS\_PUTCBEG symbol in the Code Composer Studio memory view. For example, by default the Putc function writes to the trace buffer.

Tconf Name: TRACESIZE Type: Numeric

Example: `bios.SYS.TRACESIZE = 512;`

- ❑ **Trace Buffer Memory.** The memory segment that contains system trace information.

Tconf Name: TRACESEG Type: Reference

Example: `bios.SYS.TRACESEG = prog.get("myMEM");`



- ❑ **Abort Function.** The function to run if the application aborts by calling `SYS_abort`. The default function is `_UTL_doAbort`, which logs an error message and calls `_halt`. If you are using `Tconf`, do not add an underscore before the function name; `Tconf` adds the underscore needed to call a C function from assembly internally. The prototype for this function should be:

```
Void myAbort(String fmt, va_list ap);
```

Tconf Name: ABORTFXN Type: Extern

```
Example:  bios.SYS.ABORTFXN =
           prog.extern("myAbort");
```

- ❑ **Error Function.** The function to run if an error flagged by `SYS_error` occurs. The default function is `_UTL_doError`, which logs an error message and returns. The prototype for this function should be:

```
Void myError(String s, Int errno, va_list ap);
```

Tconf Name: ERRORFXN Type: Extern

```
Example:  bios.SYS.ERRORFXN =
           prog.extern("myError");
```

- ❑ **Exit Function.** The function to run when the application exits by calling `SYS_exit`. The default function is `UTL_halt`, which loops forever with interrupts disabled and prevents other processing. The prototype for this function should be:

```
Void myExit(Int status);
```

Tconf Name: EXITFXN Type: Extern

```
Example:  bios.SYS.EXITFXN =
           prog.extern("myExit");
```

- ❑ **Putc Function.** The function to run if the application calls `SYS_putchar`, `SYS_printf`, or `SYS_vprintf`. The default function is `_UTL_doPutc`, which writes a character to the system trace buffer. This system trace buffer can be viewed only by looking for the `SYS_PUTCBEG` symbol in the Code Composer Studio memory view. The prototype for this function should be:

```
Void myPutc(Char c);
```

Tconf Name: PUTCFXN Type: Extern

```
Example:  bios.SYS.PUTCFXN =
           prog.extern("myPutc");
```

## SYS Object Properties

The SYS module does not support the creation of individual SYS objects.

**SYS\_abort***Abort program execution***C Interface**

**Syntax**                   SYS\_abort(format, [arg,] ...);

**Parameters**             String           format;   /\* format specification string \*/  
                          Arg                arg;       /\* optional argument \*/

**Return Value**           Void

**Description**

SYS\_abort aborts program execution by calling the function bound to the configuration parameter Abort function, where vargs is of type va\_list (a void pointer which can be interpreted as an argument list) and represents the sequence of arg parameters originally passed to SYS\_abort.

```
(* (Abort_function)) (format, vargs)
```

The function bound to Abort function can elect to pass the format and vargs parameters directly to SYS\_vprintf or SYS\_vsprintf prior to terminating program execution.

The default Abort function for the SYS manager is \_UTL\_doAbort, which logs an error message and calls UTL\_halt, which is defined in the boot.c file. The UTL\_halt function performs an infinite loop with all processor interrupts disabled.

**Constraints and Calling Context**

- ❑ If the function bound to Abort function is not reentrant, SYS\_abort must be called atomically.

**See Also**

SYS\_exit  
SYS\_printf

**SYS\_atexit***Stack an exit handler***C Interface**

<b>Syntax</b>	success = SYS_atexit(handler);
<b>Parameters</b>	Fxn            handler    /* exit handler function */
<b>Return Value</b>	Bool            success   /* handler successfully stacked */

**Description**

SYS\_atexit pushes handler onto an internal stack of functions to be executed when SYS\_exit is called. Up to SYS\_NUMHANDLERS(8) functions can be specified in this manner. SYS\_exit pops the internal stack until empty and calls each function as follows, where status is the parameter passed to SYS\_exit:

```
(*handler) (status)
```

SYS\_atexit returns TRUE if handler has been successfully stacked; FALSE if the internal stack is full.

The handlers on the stack are called only if either of the following happens:

- ❑ SYS\_exit is called.
- ❑ All tasks for which the Don't shut down system while this task is still running property is TRUE have exited. (By default, this includes the TSK\_idle task, which manages communication between the target and analysis tools.)
- ❑ handler cannot be NULL.

**Constraints and Calling Context**

**SYS\_error***Flag error condition***C Interface**

<b>Syntax</b>	SYS_error(s, errno, [arg], ...);		
<b>Parameters</b>	String	s;	/* error string */
	Int	errno;	/* error code */
	Arg	arg;	/* optional argument */
<b>Return Value</b>	Void		

**Description**

SYS\_error is used to flag DSP/BIOS error conditions. Application programs should call SYS\_error to handle program errors. Internal functions also call SYS\_error.

SYS\_error calls a function to handle errors. The default error function for the SYS manager is \_UTL\_doError, which logs an error message and returns. The default function can be replaced with your own error function by setting the SYS.ERRORFXN configuration property.

The default error function or an alternate configured error function is called as follows, where vargs is of type va\_list (a void pointer which can be interpreted as an argument list) and represents the sequence of arg parameters originally passed to SYS\_error.

```
(*Error_function)(s, errno, vargs)
```

**Constraints and Calling Context**

- ❑ The only valid error numbers are the error constants defined in sys.h (SYS\_E\*) or numbers greater than or equal to SYS\_EUSER. Passing any other error values to SYS\_error can cause DSP/BIOS to crash.

**SYS\_exit***Terminate program execution***C Interface**

**Syntax**                   SYS\_exit(status);

**Parameters**             Int             status;    /\* termination status code \*/

**Return Value**           Void

**Description**

SYS\_exit first pops a stack of handlers registered through the function SYS\_atexit, and then terminates program execution by calling the function bound to the configuration parameter Exit function, passing on its original status parameter.

```
(*handlerN) (status)
...
(*handler2) (status)
(*handler1) (status)

(*(Exit_function)) (status)
```

The default Exit function for the SYS manager is UTL\_halt, which performs an infinite loop with all processor interrupts disabled.

**Constraints and Calling Context**

- ❑ If the function bound to Exit function or any of the handler functions is not reentrant, SYS\_exit must be called atomically.

**See Also**

SYS\_abort  
SYS\_atexit

**SYS\_printf***Output formatted data***C Interface**

<b>Syntax</b>	SYS_printf(format, [arg,] ...);		
<b>Parameters</b>	String	format;	/* format specification string */
	Arg	arg;	/* optional argument */
<b>Return Value</b>	Void		

**Description** SYS\_printf provides a subset of the capabilities found in the standard C library function printf.

**Note:**

SYS\_printf and the related functions are code-intensive. If possible, applications should use the LOG Module functions to reduce code size and execution time.

Conversion specifications begin with a % and end with a conversion character. The conversion characters recognized by SYS\_printf are limited to the characters shown in Table 2-7.

*Table 2-7. Conversion Characters Recognized by SYS\_printf*

<b>Character</b>	<b>Corresponding Output Format</b>
d	signed decimal integer
u	unsigned decimal integer
o	octal integer
x	hexadecimal integer
c	single character
s	NULL-terminated string
p	data pointer

Between the % and the conversion character, the following symbols or specifiers contained in square brackets can appear, in the order shown.

% [-] [0] [width] type

A dash (-) symbol causes the converted argument to be left-justified within a field of width characters with blanks following. A 0 (zero) causes the converted argument to be right-justified within a field of size width with

leading 0s. If neither a dash nor 0 are given, the converted argument is right-justified in a field of size width, with leading blanks. The width is a decimal integer. The converted argument is not modified if it has more than width characters, or if width is not given.

The length modifier l can precede %d, %u, %o, and %x if the corresponding argument is a long integer.

SYS\_vprintf is equivalent to SYS\_printf, except that the optional set of arguments is replaced by a va\_list on which the standard C macro va\_start has already been applied. SYS\_sprintf and SYS\_vsprintf are counterparts of SYS\_printf and SYS\_vprintf, respectively, in which output is placed in a specified buffer.

Both SYS\_printf and SYS\_vprintf internally call the function SYS\_putchar to output individual characters via the Putc function configured in the SYS Manager Properties. The default Putc function is \_UTL\_doPutc, which writes a character to the system trace buffer. The size and memory segment for the system trace buffer can also be set in the SYS Manager Properties. This system trace buffer can be viewed only by looking for the SYS\_PUTCBEG symbol in the Code Composer Studio memory view.

### Constraints and Calling Context

- ❑ The function bound to Exit function or any of the handler functions are not reentrant; SYS\_exit must be called atomically.

### See Also

SYS\_sprintf  
SYS\_vprintf  
SYS\_vsprintf

**SYS\_sprintf***Output formatted data***C Interface****Syntax** SYS\_sprintf (buffer, format, [arg,] ...);**Parameters**  
String buffer; /\* output buffer \*/  
String format; /\* format specification string \*/  
Arg arg; /\* optional argument \*/**Return Value** Void**Description** SYS\_sprintf provides a subset of the capabilities found in the standard C library function printf.**Note:**

SYS\_sprintf and the related functions are code-intensive. If possible, applications should use LOG Module module functions to reduce code size and execution time.

Conversion specifications begin with a % and end with a conversion character. The conversion characters recognized by SYS\_sprintf are limited to the characters in Table 2-8.

*Table 2-8. Conversion Characters Recognized by SYS\_sprintf*

Character	Corresponding Output Format
d	signed decimal integer
u	unsigned decimal integer
o	octal integer
x	hexadecimal integer
c	single character
s	NULL-terminated string
p	data pointer

Between the % and the conversion character, the following symbols or specifiers contained within square brackets can appear, in the order shown.



`%[-][0][width]type`

A dash (-) symbol causes the converted argument to be left-justified within a field of width characters with blanks following. A 0 (zero) causes the converted argument to be right-justified within a field of size width with leading 0s. If neither a dash nor 0 are given, the converted argument is right-justified in a field of size width, with leading blanks. The width is a decimal integer. The converted argument is not modified if it has more than width characters, or if width is not given.

The length modifier `l` can precede `%d`, `%u`, `%o`, and `%x` if the corresponding argument is a long integer.

`SYS_vprintf` is equivalent to `SYS_printf`, except that the optional set of arguments is replaced by a `va_list` on which the standard C macro `va_start` has already been applied. `SYS_sprintf` and `SYS_vsprintf` are counterparts of `SYS_printf` and `SYS_vprintf`, respectively, in which output is placed in a specified buffer.

Both `SYS_printf` and `SYS_vprintf` internally call the function `SYS_putchar` to output individual characters in a system-dependent fashion via the configuration parameter `Putc` function. This parameter is bound to a function that displays output on a debugger if one is running, or places output in an output buffer between `PUTCEND` and `PUTCBEG`.

- ❑ The function bound to `Exit` function or any of the handler functions are not reentrant; `SYS_exit` must be called atomically.

## Constraints and Calling Context

### See Also

`SYS_printf`  
`SYS_vprintf`  
`SYS_vsprintf`

**SYS\_vprintf***Output formatted data***C Interface**

<b>Syntax</b>	SYS_vprintf(format, vargs);
<b>Parameters</b>	String        format;    /* format specification string */ va_list        vargs;     /* variable argument list reference */
<b>Return Value</b>	Void

**Description**        SYS\_vprintf provides a subset of the capabilities found in the standard C library function printf.

**Note:**

SYS\_vprintf and the related functions are code-intensive. If possible, applications should use LOG Module functions to reduce code size and execution time.

Conversion specifications begin with a % and end with a conversion character. The conversion characters recognized by SYS\_vprintf are limited to the characters in Table 2-9.

*Table 2-9. Conversion Characters Recognized by SYS\_vprintf*

<b>Character</b>	<b>Corresponding Output Format</b>
d	signed decimal integer
u	unsigned decimal integer
o	octal integer
x	hexadecimal integer
c	single character
s	NULL-terminated string
p	data pointer

Between the % and the conversion character, the following symbols or specifiers contained within square brackets can appear, in the order shown.

`%[-][0][width]type`

A dash (-) symbol causes the converted argument to be left-justified within a field of width characters with blanks following. A 0 (zero) causes the converted argument to be right-justified within a field of size width with leading 0s. If neither a dash nor 0 are given, the converted argument is right-justified in a field of size width, with leading blanks. The width is a decimal integer. The converted argument is not modified if it has more than width characters, or if width is not given.

The length modifier `l` can precede `%d`, `%u`, `%o`, and `%x` if the corresponding argument is a long integer.

`SYS_vprintf` is equivalent to `SYS_printf`, except that the optional set of arguments is replaced by a `va_list` on which the standard C macro `va_start` has already been applied. `SYS_sprintf` and `SYS_vsprintf` are counterparts of `SYS_printf` and `SYS_vprintf`, respectively, in which output is placed in a specified buffer.

Both `SYS_printf` and `SYS_vprintf` internally call the function `SYS_putchar` to output individual characters via the `Putc` function configured in the SYS Manager Properties. The default `Putc` function is `_UTL_doPutc`, which writes a character to the system trace buffer. The size and memory segment for the system trace buffer can also be set in the SYS Manager Properties. This system trace buffer can be viewed only by looking for the `SYS_PUTCBEG` symbol in the Code Composer Studio memory view.

- ❑ The function bound to `Exit` function or any of the handler functions are not reentrant; `SYS_exit` must be called atomically.

## Constraints and Calling Context

### See Also

`SYS_printf`  
`SYS_sprintf`  
`SYS_vsprintf`

**SYS\_vsprintf***Output formatted data***C Interface****Syntax**

SYS\_vsprintf(buffer, format, vargs);

**Parameters**

String        buffer;     /\* output buffer \*/  
String        format;    /\* format specification string \*/  
va\_list       vargs;     /\* variable argument list reference \*/

**Return Value**

Void

**Description**

SYS\_vsprintf provides a subset of the capabilities found in the standard C library function printf.

**Note:**

SYS\_vsprintf and the related functions are code-intensive. If possible, applications should use LOG Module functions to reduce code size and execution time.

Conversion specifications begin with a % and end with a conversion character. The conversion characters recognized by SYS\_vsprintf are limited to the characters in Table 2-10.

*Table 2-10. Conversion Characters Recognized by SYS\_vsprintf*

<b>Character</b>	<b>Corresponding Output Format</b>
d	signed decimal integer
u	unsigned decimal integer
o	octal integer
x	hexadecimal integer
c	single character
s	NULL-terminated string
p	data pointer

Between the % and the conversion character, the following symbols or specifiers contained within square brackets can appear, in the order shown.

%[-][0][width]type

A dash (-) symbol causes the converted argument to be left-justified within a field of width characters with blanks following. A 0 (zero) causes the converted argument to be right-justified within a field of size width with leading 0s. If neither a dash nor 0 are given, the converted argument is right-justified in a field of size width, with leading blanks. The width is a decimal integer. The converted argument is not modified if it has more than width characters, or if width is not given.

The length modifier l can precede %d, %u, %o, and %x if the corresponding argument is a long integer.

SYS\_vsprintf is equivalent to SYS\_printf, except that the optional set of arguments is replaced by a va\_list on which the standard C macro va\_start has already been applied. SYS\_sprintf and SYS\_vsprintf are counterparts of SYS\_printf and SYS\_vprintf, respectively, in which output is placed in a specified buffer.

Both SYS\_printf and SYS\_vprintf internally call the function SYS\_putchar to output individual characters in a system-dependent fashion via the configuration parameter Putc function. This parameter is bound to a function that displays output on a debugger if one is running, or places output in an output buffer between PUTCEND and PUTCBEG.

### Constraints and Calling Context

- ❑ The function bound to Exit function or any of the handler functions are not reentrant; SYS\_exit must be called atomically.

### See Also

SYS\_printf  
SYS\_sprintf  
SYS\_vprintf

**SYS\_putchar***Output a single character***C Interface**

<b>Syntax</b>	SYS_putchar(c);
<b>Parameters</b>	Char           c;           /* next output character */
<b>Return Value</b>	Void

**Description**           SYS\_putchar outputs the character c by calling the system-dependent function bound to the configuration parameter Putc function.

```
((Putc function))(c)
```

For systems with limited I/O capabilities, the function bound to Putc function might simply place c into a global buffer that can be examined after program termination.

The default Putc function for the SYS manager is \_UTL\_doPutc, which writes a character to the system trace buffer. The size and memory segment for the system trace buffer can be set in the SYS Manager Properties. This system trace buffer can be viewed only by looking for the SYS\_PUTCBEG symbol in the Code Composer Studio memory view.

SYS\_putchar is also used internally by SYS\_printf and SYS\_vprintf when generating their output.

**Constraints and Calling Context**

- ❑ If the function bound to Putc function is not reentrant, SYS\_putchar must be called atomically.

**See Also**

SYS\_printf

## 2.28 TRC Module

The TRC module is the trace manager.

### Functions

- TRC\_disable. Disable trace class(es)
- TRC\_enable. Enable trace type(s)
- TRC\_query. Query trace class(es)

### Description

The TRC module manages a set of trace control bits which control the real-time capture of program information through event logs and statistics accumulators. For greater efficiency, the target does not store log or statistics information unless tracing is enabled.

Table 2-11 lists events and statistics that can be traced. The constants defined in `trc.hand` `trc.h55` are shown in the left column.

*Table 2-11. Events and Statistics Traced by TRC*

Constant	Tracing Enabled/Disabled	Default
TRC_LOGCLK	Log timer interrupts	off
TRC_LOGPRD	Log periodic ticks and start of periodic functions	off
TRC_LOGSWI	Log events when a SWI is posted and completes	off
TRC_LOGTSK	Log events when a task is made ready, starts, becomes blocked, resumes	off
TRC_STSHWI	Gather statistics on monitored values within HWIs	off
TRC_STSPIP	Count number of frames read from or written to data pipe	off
TRC_STSPRD	Gather statistics on number of ticks elapsed during execution	off
TRC_STSSWI	Gather statistics on length of SWI execution	off
TRC_STSTSK	Gather statistics on length of TSK execution. Statistics are gathered from the time TSK is made ready to run until the application calls <code>TSK_deltatime</code> .	off
TRC_USER0 and TRC_USER1	Your program can use these bits to enable or disable sets of explicit instrumentation actions. You can use <code>TRC_query</code> to check the settings of these bits and either perform or omit instrumentation calls based on the result.	off
TRC_GBLHOST	This bit must be set in order for any implicit instrumentation to be performed. Simultaneously starts or stops gathering of all enabled types of tracing. This can be important if you are trying to correlate events of different types. This	off
TRC_GBLTARG	This bit must also be set for any implicit instrumentation to be performed. This bit can only be set by the target program and is enabled by default.	on
TRC_STSSWI	Gather statistics on length of SWI execution	off

All trace constants except TRC\_GBLTARG are switched off initially. To enable tracing you can use calls to TRC\_enable or the DSP/BIOS→RTA Control Panel, which uses the TRC module internally. You do not need to enable tracing for messages written with LOG\_printf or LOG\_event and statistics added with STS\_add or STS\_delta.

Your program can call the TRC\_enable and TRC\_disable operations to explicitly start and stop event logging or statistics accumulation in response to conditions encountered during real-time execution. This enables you to preserve the specific log or statistics information you need to see.



**TRC\_disable***Disable trace class(es)***C Interface**

**Syntax** TRC\_disable(mask);

**Parameters** Uns mask; /\* trace type constant mask \*/

**Return Value** Void

**Reentrant** no

**Description** TRC\_disable disables tracing of one or more trace types. Trace types are specified with a 32-bit mask. (See the TRC Module topic for a list of constants to use in the mask.)

The following C code would disable tracing of statistics for software interrupts and periodic functions:

```
TRC_disable(TRC_LOGSWI | TRC_LOGPRD);
```

Internally, DSP/BIOS uses a bitwise AND NOT operation to disable multiple trace types.

For example, you might want to use TRC\_disable with a circular log and disable tracing when an unwanted condition occurs. This allows test equipment to retrieve the log events that happened just before this condition started.

**See Also**

TRC\_enable  
 TRC\_query  
 LOG\_printf  
 LOG\_event  
 STS\_add  
 STS\_delta

**TRC\_enable***Enable trace type(s)***C Interface**

**Syntax** TRC\_enable(mask);

**Parameters** Uns mask; /\* trace type constant \*/

**Return Value** Void

**Reentrant** no

**Description** TRC\_enable enables tracing of one or more trace types. Trace types are specified with a 32-bit mask. (See the TRC Module topic for a list of constants to use in the mask.)

The following C code would enable tracing of statistics for software interrupts and periodic functions:

```
TRC_enable(TRC_STSSWI | TRC_STSPRD);
```

Internally, DSP/BIOS uses a bitwise OR operation to enable multiple trace types.

For example, you might want to use TRC\_enable with a fixed log to enable tracing when a specific condition occurs. This allows test equipment to retrieve the log events that happened just after this condition occurred.

**See Also**

TRC\_disable  
TRC\_query  
LOG\_printf  
LOG\_event  
STS\_add  
STS\_delta

**TRC\_query***Query trace class(es)***C Interface**

<b>Syntax</b>	<code>result = TRC_query(mask);</code>
<b>Parameters</b>	Uns          mask; <i>/* trace type constant mask */</i>
<b>Return Value</b>	Int          result <i>/* indicates whether all trace types enabled */</i>
<b>Reentrant</b>	yes

**Description**

TRC\_query determines whether particular trace types are enabled. TRC\_query returns 0 if all trace types in the mask are enabled. If any trace types in the mask are disabled, TRC\_query returns a value with a bit set for each trace type in the mask that is disabled. (See the TRC Module topic for a list of constants to use in the mask.)

Trace types are specified with a 16-bit mask. The full list of constants you can use is included in the description of the TRC module.

For example, the following C code returns 0 if statistics tracing for the PRD class is enabled:

```
result = TRC_query(TRC_STSPRD);
```

The following C code returns 0 if both logging and statistics tracing for the SWI class are enabled:

```
result = TRC_query(TRC_LOGSWI | TRC_STSSWI);
```

Note that TRC\_query does not return 0 unless the bits you are querying and the TRC\_GBLHOST and TRC\_GBLTARG bits are set. TRC\_query returns non-zero if either TRC\_GBLHOST or TRC\_GBLTARG are disabled. This is because no tracing is done unless these bits are set.

For example, if the TRC\_GBLHOST, TRC\_GBLTARG, and TRC\_LOGSWI bits are set, this C code returns the results shown:

```
result = TRC_query(TRC_LOGSWI); /* returns 0 */
result = TRC_query(TRC_LOGPRD); /* returns non-zero */
```

However, if only the TRC\_GBLHOST and TRC\_LOGSWI bits are set, the same C code returns the results shown:

```
result = TRC_query(TRC_LOGSWI); /* returns non-zero */
result = TRC_query(TRC_LOGPRD); /* returns non-zero */
```

**See Also**

TRC\_enable  
TRC\_disable

## 2.29 TSK Module

The TSK module is the task manager.

### Functions

- ❑ TSK\_checkstacks. Check for stack overflow
- ❑ TSK\_create. Create a task ready for execution
- ❑ TSK\_delete. Delete a task
- ❑ TSK\_deltatime. Update task STS with time difference
- ❑ TSK\_disable. Disable DSP/BIOS task scheduler
- ❑ TSK\_enable. Enable DSP/BIOS task scheduler
- ❑ TSK\_exit. Terminate execution of the current task
- ❑ TSK\_getenv. Get task environment
- ❑ TSK\_geterr. Get task error number
- ❑ TSK\_getname. Get task name
- ❑ TSK\_getpri. Get task priority
- ❑ TSK\_getsts. Get task STS object
- ❑ TSK\_isTSK. Check current thread calling context
- ❑ TSK\_itick. Advance system alarm clock (interrupt only)
- ❑ TSK\_self. Get handle of currently executing task
- ❑ TSK\_setenv. Set task environment
- ❑ TSK\_seterr. Set task error number
- ❑ TSK\_setpri. Set a task's execution priority
- ❑ TSK\_settime. Set task STS previous time
- ❑ TSK\_sleep. Delay execution of the current task
- ❑ TSK\_stat. Retrieve the status of a task
- ❑ TSK\_tick. Advance system alarm clock
- ❑ TSK\_time. Return current value of system clock
- ❑ TSK\_yield. Yield processor to equal priority task

### Task Hook Functions

```
Void TSK_createFxn(TSK_Handle task);
Void TSK_deleteFxn(TSK_Handle task);
Void TSK_exitFxn(Void);
Void TSK_readyFxn(TSK_Handle newtask);
Void TSK_switchFxn(TSK_Handle oldtask,
                  TSK_Handle newtask);
```

## Constants, Types, and Structures

```

typedef struct TSK_OBJ *TSK_Handle; /* task object handle*/

struct TSK_Attrs { /* task attributes */
    Int    priority; /* execution priority */
    Ptr    stack; /* pre-allocated stack */
    size_t stacksize; /* stack size in MADUs */
#ifdef _55_
    size_t sysstacksize; /*C55x system stack in MADUs */
#endif
    Int    stackseg; /* mem seg for stack allocation */
    Ptr    environ; /* global environment data struct */
    String name; /* printable name */
    Bool   exitflag; /* program termination requires */
                /* this task to terminate */
    Bool   initstackflag; /* initialize task stack? */
};

Int TSK_pid; /* MP processor ID */

Int TSK_MAXARGS = 8; /* max number of task arguments */
Int TSK_IDLEPRI = 0; /* used for idle task */
Int TSK_MINPRI = 1; /* minimum execution priority */
Int TSK_MAXPRI = 15; /* maximum execution priority */
Int TSK_STACKSTAMP =
TSK_Attrs TSK_ATTRS = { /* default attribute values */
    TSK->PRIORITY, /* priority */
    NULL, /* stack */
    TSK->STACKSIZE, /* stacksize */
#ifdef _55_
    TSK->SYSSTACKSIZE, /* system stacksize in MADUs */
#endif
    TSK->STACKSEG, /* stackseg */
    NULL, /* environ */
    "", /* name */
    TRUE, /* exitflag */
    TRUE, /* initstackflag */
};

enum TSK_Mode { /* task execution modes */
    TSK_RUNNING, /* task currently executing */
    TSK_READY, /* task scheduled for execution */
    TSK_BLOCKED, /* task suspended from execution */
    TSK_TERMINATED, /* task terminated from execution */
};

struct TSK_Stat { /* task status structure */
    TSK_Attrs attrs; /* task attributes */
    TSK_Mode mode; /* task execution mode */
    Ptr sp; /* task stack pointer */
#ifdef _55_
    Ptr ssp; /* task system stack pointer */
#endif
    size_t used; /* task stack used */
#ifdef _55_
    size_t sysused; /* task system stack used */
#endif
};

```

## Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the TSK Manager Properties and TSK Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-3.

### Module Configuration Parameters

Name	Type	Default (Enum Options)
ENABLETSK	Bool	true
OBJMEMSEG	Reference	prog.get("DARAM")
STACKSIZE	Int16	1024
SYSSTACKSIZE	Int16	256
STACKSEG	Reference	prog.get("DARAM")
PRIORITY	EnumInt	1 (1 to 15)
DRIVETSKTICK	EnumString	"PRD" ("User")
CREATEFXN	Extern	prog.extern("FXN_F_nop")
DELETEFXN	Extern	prog.extern("FXN_F_nop")
EXITFXN	Extern	prog.extern("FXN_F_nop")
CALLSWITCHFXN	Bool	false
SWITCHFXN	Extern	prog.extern("FXN_F_nop")
CALLREADYFXN	Bool	false
READYFXN	Extern	prog.extern("FXN_F_nop")

### Instance Configuration Parameters

Name	Type	Default (Enum Options)
comment	String	"<add comments here>"
autoAllocateStack	Bool	true
manualStack	Extern	prog.extern("null","asm")
stackSize	Int16	1024
sysStackSize	Int16	256
stackMemSeg	Reference	prog.get("DARAM")
priority	EnumInt	0 (-1, 0, 1 to 15)
fxn	Extern	prog.extern("FXN_F_nop")
arg0	Arg	0
arg7	Arg	0
envPointer	Arg	0x00000000

Name	Type	Default (Enum Options)
exitFlag	Bool	true
allocateTaskName	Bool	false
order	Int16	0

## Description

The TSK module makes available a set of functions that manipulate task objects accessed through handles of type `TSK_Handle`. Tasks represent independent threads of control that conceptually execute functions in parallel within a single C program; in reality, concurrency is achieved by switching the processor from one task to the next.

When you create a task, it is provided with its own run-time stack, used for storing local variables as well as for further nesting of function calls. The `TSK_STACKSTAMP` value is used to initialize the run-time stack. When creating a task dynamically, you need to initialize the stack with `TSK_STACKSTAMP` only if the stack is allocated manually and `TSK_checkstacks` or `TSK_stat` is to be called. Each stack must be large enough to handle normal subroutine calls as well as a single task preemption context. A task preemption context is the context that gets saved when one task preempts another as a result of an interrupt thread readying a higher-priority task. All tasks executing within a single program share a common set of global variables, accessed according to the standard rules of scope defined for C functions.

Each task is in one of four modes of execution at any point in time: running, ready, blocked, or terminated. By design, there is always one (and only one) task currently running, even if it is a dummy idle task managed internally by TSK. The current task can be suspended from execution by calling certain TSK functions, as well as functions provided by other modules like the SEM Module and the SIO Module; the current task can also terminate its own execution. In either case, the processor is switched to the next task that is ready to run.

You can assign numeric priorities to tasks through TSK. Tasks are readied for execution in strict priority order; tasks of the same priority are scheduled on a first-come, first-served basis. As a rule, the priority of the currently running task is never lower than the priority of any ready task. Conversely, the running task is preempted and re-scheduled for execution whenever there exists some ready task of higher priority.

You can use `Tconf` to specify one or more sets of application-wide hook functions that run whenever a task state changes in a particular way. For the TSK module, these functions are the `Create`, `Delete`, `Exit`, `Switch`, and `Ready` functions. The `HOOK` module adds an additional Initialization function.

A single set of hook functions can be specified for the TSK module itself. To create additional sets of hook functions, use the HOOK Module. When you create the first HOOK object, any TSK module hook functions you have specified are automatically placed in a HOOK object called HOOK\_KNL. To set any properties of this object other than the Initialization function, use the TSK module properties. To set the Initialization function property of the HOOK\_KNL object, use the HOOK object properties. If you configure only a single set of hook functions using the TSK module, the HOOK module is not used.

The TSK\_create topic describes the Create function. The TSK\_delete topic describes the Delete function. The TSK\_exit topic describes the Exit function.

If a Switch function is specified, it is invoked when a new task becomes the TSK\_RUNNING task. The Switch function gives the application access to both the current and next task handles at task switch time. The function should use these argument types:

```
Void mySwitchFxn(TSK_Handle currTask,  
                TSK_Handle nextTask);
```

This function can be used to save/restore additional task context (for example, external hardware registers), to check for task stack overflow, to monitor the time used by each task, etc.

If a Ready function is specified, it is invoked whenever a task is made ready to run. Even if a higher-priority thread is running, the Ready function runs. The Ready function is called with a handle to the task being made ready to run as its argument. This example function prints the name of both the task that is ready to run and the task that is currently running:

```
Void myReadyFxn(TSK_Handle task)  
{  
    String      nextName, currName;  
    TSK_Handle  currTask = TSK_self();  
  
    nextName = TSK_getname(task);  
    LOG_printf(&trace, "Task %s Ready", nextName);  
  
    currName = TSK_getname(currTask);  
    LOG_printf(&trace, "Task %s Running", currName);  
}
```



## TSK Manager Properties

The Switch function and Ready function are called in such a way that they can use only functions allowed within a SWI handler. See Appendix A, Function Callability Table, for a list of functions that can be called by SWI handlers. There are no real constraints on what functions are called via the Create function, Delete function, or Exit function.

The following global properties can be set for the TSK module in the TSK Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- ❑ **Enable TSK Manager.** If no tasks are used by the program other than TSK\_idle, you can optimize the program by disabling the task manager. The program must then not use TSK objects created with either Tconf or the TSK\_create function. If the task manager is disabled, the idle loop still runs and uses the system stack instead of a task stack.

Tconf Name: ENABLETSK Type: Bool

Example: `bios.TSK.ENABLETSK = true;`

- ❑ **Object Memory.** The memory segment that contains the TSK objects created with Tconf.

Tconf Name: OBJMEMSEG Type: Reference

Example: `bios.TSK.OBJMEMSEG = prog.get("myMEM");`

- ❑ **Default stack size.** The default size of the stack (in MADUs) used by tasks. You can override this value for an individual task you create with Tconf or TSK\_create. The estimated minimum task size is shown in the status bar of the DSP/BIOS Configuration Tool. This property applies to TSK objects created both with Tconf and with TSK\_create.

Tconf Name: STACKSIZE Type: Int16

Example: `bios.TSK.STACKSIZE = 1024;`

- ❑ **Default systack size.** This property defines the size (in MADUs) of the system stack.

Tconf Name: SYSSTACKSIZE Type: Int16

Example: `bios.TSK.SYSSTACKSIZE = 256;`

- ❑ **Stack segment for dynamic tasks.** The default memory segment to contain task stacks created at run-time with the TSK\_create function. The TSK\_Attrs structure passed to the TSK\_create function can override this default. If you select MEM\_NULL for this property, creation of task objects at run-time is disabled.

Tconf Name: STACKSEG Type: Reference

Example: `bios.TSK.STACKSEG = prog.get("myMEM");`

- Default task priority.** The default priority level for tasks that are created dynamically with `TSK_create`. This property applies to TSK objects created both with `Tconf` and with `TSK_create`.  
Tconf Name: `PRIORITY` Type: EnumInt  
Options: `1 to 15`  
Example: `bios.TSK.PRIORITY = 1;`
- TSK tick driven by.** Choose whether you want the system clock to be driven by the PRD module or by calls to `TSK_tick` and `TSK_itick`. This clock is used by `TSK_sleep` and functions such as `SEM_pend` that accept a timeout argument.  
Tconf Name: `DRIVETSKTICK` Type: EnumString  
Options: `"PRD", "User"`  
Example: `bios.TSK.DRIVETSKTICK = "PRD";`
- Create function.** The name of a function to call when any task is created. This includes tasks that are created statically and those created dynamically using `TSK_create`. If you are using `Tconf`, do not add an underscore before the function name; `Tconf` adds the underscore needed to call a C function from assembly internally. The `TSK_create` topic describes the Create function.  
Tconf Name: `CREATEFXN` Type: Extern  
Example: `bios.TSK.CREATEFXN =  
          prog.extern("tskCreate");`
- Delete function.** The name of a function to call when any task is deleted at run-time with `TSK_delete`. The `TSK_delete` topic describes the Delete function.  
Tconf Name: `DELETEFXN` Type: Extern  
Example: `bios.TSK.DELETEFXN =  
          prog.extern("tskDelete");`
- Exit function.** The name of a function to call when any task exits. The `TSK_exit` topic describes the Exit function.  
Tconf Name: `EXITFXN` Type: Extern  
Example: `bios.TSK.EXITFXN =  
          prog.extern("tskExit");`
- Call switch function.** Check this box if you want a function to be called when any task switch occurs.  
Tconf Name: `CALLSWITCFXN` Type: Bool  
Example: `bios.TSK.CALLSWITCFXN = false;`

- Switch function.** The name of a function to call when any task switch occurs. This function can give the application access to both the current and next task handles. The TSK Module topic describes the Switch function.

Tconf Name: SWITCHFXN Type: Extern

Example: `bios.TSK.SWITCHFXN =  
          prog.extern("tskSwitch");`

- Call ready function.** Check this box if you want a function to be called when any task becomes ready to run.

Tconf Name: CALLREADYFXN Type: Bool

Example: `bios.TSK.CALLREADYFXN = false;`

- Ready function.** The name of a function to call when any task becomes ready to run. The TSK Module topic describes the Ready function.

Tconf Name: READYFXN Type: Extern

Example: `bios.TSK.READYFXN =  
          prog.extern("tskReady");`

## TSK Object Properties

To create a TSK object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var myTsk = bios.TSK.create("myTsk");
```

The following properties can be set for a TSK object in the TSK Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

### General tab

- comment.** Type a comment to identify this TSK object.

Tconf Name: comment Type: String

Example: `myTsk.comment = "my TSK";`

- Automatically allocate stack.** Check this box if you want the task's private stack space to be allocated automatically when this task is created. The task's context is saved in this stack before any higher-priority task is allowed to block this task and run.

Tconf Name: autoAllocateStack Type: Bool

Example: `myTsk.autoAllocateStack = true;`

- Manually allocated stack.** If you did not check the box to Automatically allocate stack, type the name of the manually allocated stack to use for this task.

For 'C55x, the manually allocated stack must be large enough to accommodate both the stack and the system stack (sysstack) on the

same page. Automatically allocating the stack is recommended, since TSK\_create makes sure this condition is satisfied.

Tconf Name: manualStack Type: Extern

Example: `myTsk.manualStack =  
          prog.extern("myStack");`

- ❑ **Stack size.** Enter the size (in MADUs) of the stack space to allocate for this task. You must enter the size whether the application allocates the stack manually or automatically. Each stack must be large enough to handle normal subroutine calls as well as a single task preemption context. A task preemption context is the context that gets saved when one task preempts another as a result of an interrupt thread readying a higher priority task.

Tconf Name: stackSize Type: Int16

Example: `myTsk.stackSize = 1024;`

- ❑ **System stack size.** This specifies the size (in MADUs) of the task's system stack. The stackSize + sysStackSize must be less than or equal to 0xFFFF. That is, they should be on the same page because the stack pointer and system stack pointer share the same register for their upper bits.

Tconf Name: sysStackSize Type: Int16

Example: `myTsk.sysStackSize = 256;`

- ❑ **Stack Memory Segment.** If you set the "Automatically allocate stack" property to true, specify the memory segment to contain the stack space for this task.

Tconf Name: stackMemSeg Type: Reference

Example: `myTsk.stackMemSeg = prog.get("myMEM");`

- ❑ **Priority.** The priority level for this task. A priority of -1 causes a task to be suspended until its priority is raised programmatically.

Tconf Name: priority Type: EnumInt

Options: -1, 0, 1 to 15

Example: `myTsk.priority = 1;`

## Function tab

- ❑ **Task function.** The function to be executed when the task runs. If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. (The DSP/BIOS Configuration Tool generates assembly code which must use the leading underscore when referencing C functions or labels.) If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally. If you compile C programs with the

-pm or -op2 options, you should precede C functions called by task threads with the `FUNC_EXT_CALLED` pragma. See the online help for the C compiler for details.

Tconf Name: `fxn` Type: Extern

Example: `myTsk.fxn = prog.extern("tskFxn");`

- Task function argument 0-7.** The arguments to pass to the task function. Arguments can be integers or labels.

Tconf Name: `arg0` to `arg7` Type: Arg

Example: `myTsk.arg0 = 0;`

## Advanced tab

- Environment pointer.** A pointer to a globally-defined data structure this task can access. The task can get and set the task environment pointer with the `TSK_getenv` and `TSK_setenv` functions. If your program uses multiple `HOOK` objects, `HOOK_setenv` allows you to set individual environment pointers for each `HOOK` and `TSK` object combination.

Tconf Name: `envPointer` Type: Arg

Example: `myTsk.envPointer = 0;`

- Don't shut down system while this task is still running.** Check this box if you do not want the application to be able to end if this task is still running. The application can still abort. For example, you might clear this box for a monitor task that collects data whenever all other tasks are blocked. The application does not need to explicitly shut down this task.

Tconf Name: `exitFlag` Type: Bool

Example: `myTsk.exitFlag = true;`

- Allocate Task Name on Target.** Check this box if you want the name of this `TSK` object to be retrievable by the `TSK_getname` function. Clearing this box saves a small amount of memory. The task name is available in analysis tools in either case.

Tconf Name: `allocateTaskName` Type: Bool

Example: `myTsk.allocateTaskName = false;`

- order.** Set this property for all `TSK` objects so that the numbers match the sequence in which `TSK` functions with the same priority level should be executed.

Tconf Name: `order` Type: Int16

Example: `myTsk.order = 2;`

**TSK\_checkstacks***Check for stack overflow***C Interface**

**Syntax** TSK\_checkstacks(oldtask, newtask);

**Parameters** TSK\_Handle oldtask; /\* handle of task switched from \*/  
TSK\_Handle newtask; /\* handle of task switched to \*/

**Return Value** Void

**Description**

TSK\_checkstacks calls SYS\_abort with an error message if either oldtask or newtask has a stack in which the last location no longer contains the initial value TSK\_STACKSTAMP. The presumption in one case is that oldtask's stack overflowed, and in the other that an invalid store has corrupted newtask's stack.

TSK\_checkstacks requires that the stack was initialized by DSP/BIOS. For dynamically-created tasks, initialization is controlled by the initstackflag attribute in the TSK\_Attrs structure passed to TSK\_create. Statically configured tasks always initialize the stack.

You can call TSK\_checkstacks directly from your application. For example, you can check the current task's stack integrity at any time with a call like the following:

```
TSK_checkstacks(TSK_self(), TSK_self());
```

However, it is more typical to call TSK\_checkstacks in the task Switch function specified for the TSK manager in your configuration file. This provides stack checking at every context switch, with no alterations to your source code.

If you want to perform other operations in the Switch function, you can do so by writing your own function (myswitchfxn) and then calling TSK\_checkstacks from it.

```
Void myswitchfxn(TSK_Handle oldtask,  
                TSK_Handle newtask)  
{  
    `your additional context switch operations`  
    TSK_checkstacks(oldtask, newtask);  
    ...  
}
```

**Constraints and Calling Context**

- ❑ TSK\_checkstacks cannot be called from an HWI or SWI.

**TSK\_create***Create a task ready for execution***C Interface**

<b>Syntax</b>	<code>task = TSK_create(fxn, attrs, [arg,] ...);</code>									
<b>Parameters</b>	<table> <tr> <td><code>Fxn</code></td> <td><code>fxn;</code></td> <td><code>/* pointer to task function */</code></td> </tr> <tr> <td><code>TSK_Attrs</code></td> <td><code>*attrs;</code></td> <td><code>/* pointer to task attributes */</code></td> </tr> <tr> <td><code>Arg</code></td> <td><code>arg;</code></td> <td><code>/* task arguments */</code></td> </tr> </table>	<code>Fxn</code>	<code>fxn;</code>	<code>/* pointer to task function */</code>	<code>TSK_Attrs</code>	<code>*attrs;</code>	<code>/* pointer to task attributes */</code>	<code>Arg</code>	<code>arg;</code>	<code>/* task arguments */</code>
<code>Fxn</code>	<code>fxn;</code>	<code>/* pointer to task function */</code>								
<code>TSK_Attrs</code>	<code>*attrs;</code>	<code>/* pointer to task attributes */</code>								
<code>Arg</code>	<code>arg;</code>	<code>/* task arguments */</code>								
<b>Return Value</b>	<code>TSK_Handle task;</code> <code>/* task object handle */</code>									

**Description**

TSK\_create creates a new task object. If successful, TSK\_create returns the handle of the new task object. If unsuccessful, TSK\_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS\_error, and SYS\_error is configured to abort).

The fxn parameter uses the Fxn type to pass a pointer to the function the TSK object should run. For example, if myFxn is a function in your program, you can create a TSK object to call that function as follows:

```
task = TSK_create((Fxn)myFxn, NULL);
```

You can use Tconf to specify an application-wide Create function that runs whenever a task is created. This includes tasks that are created statically and those created dynamically using TSK\_create. The default Create function is a no-op function.

For TSK objects created statically, the Create function is called during the BIOS\_start portion of the program startup process, which runs after the main() function and before the program drops into the idle loop.

For TSK objects created dynamically, the Create function is called after the task handle has been initialized but before the task has been placed on its ready queue.

Any DSP/BIOS function can be called from the Create function. DSP/BIOS passes the task handle of the task being created to the Create function. The Create function declaration should be similar to this:

```
Void myCreateFxn(TSK_Handle task);
```

The new task is placed in TSK\_READY mode, and is scheduled to begin concurrent execution of the following function call:

```
(*fxn)(arg1, arg2, ... argN) /* N = TSK_MAXARGS = 8 */
```

As a result of being made ready to run, the task runs the application-wide Ready function if one has been specified.

TSK\_exit is automatically called if and when the task returns from fxn.

If attrs is NULL, the new task is assigned a default set of attributes. Otherwise, the task's attributes are specified through a structure of type TSK\_Attrs, which is defined as follows.

```
struct TSK_Attrs { /* task attributes */
    Int    priority; /* execution priority */
    Ptr    stack;    /* pre-allocated stack */
    size_t stacksize; /* stack size in MADUs */
#ifdef _55_
    size_t sysstacksize; /*C55x sysstack in MADUs */
#endif
    Int    stackseg; /* mem seg for stack alloc */
    Ptr    environ; /* global environ data struct */
    String name;    /* printable name */
    Bool   exitflag; /* prog termination requires */
                /* this task to terminate */
    Bool   initstackflag; /* initialize task stack? */
};
```

The priority attribute specifies the task's execution priority and must be less than or equal to TSK\_MAXPRI (15); this attribute defaults to the value of the configuration parameter Default task priority (preset to TSK\_MINPRI). If priority is less than 0, the task is barred from execution until its priority is raised at a later time by TSK\_setpri. A priority value of 0 is reserved for the TSK\_idle task defined in the default configuration. You should not use a priority of 0 for any other tasks.

The stack attribute specifies a pre-allocated block of stacksize MADUs to be used for the task's private stack; this attribute defaults to NULL, in which case the task's stack is automatically allocated using MEM\_alloc from the memory segment given by the stackseg attribute. If you specify a pre-allocated stack for 'C55x, the buffer must be attrs.stacksize plus attrs.sysstacksize in length.

The stacksize attribute specifies the number of MADUs to be allocated for the task's private stack; this attribute defaults to the value of the configuration parameter Default stack size (preset to 1024). Each stack must be large enough to handle normal subroutine calls as well as a single task preemption context. A task preemption context is the context that gets saved when one task preempts another as a result of an interrupt thread readying a higher priority task.

The sysstacksize attribute specifies a pre-allocated block of the specified number of MADUs to be used for the task's private system stack. This attribute defaults to NULL, in which case the task's system stack is automatically allocated using MEM\_alloc from the memory segment given by the stackseg attribute. The sysstacksize attribute specifies the



number of MADUs to be allocated for the task's private system stack. This attribute defaults to the value of the configuration parameter Default system stack size (preset to 256).

The `stackseg` attribute specifies the memory segment to use when allocating the task stack with `MEM_alloc`; this attribute defaults to the value of the configuration parameter Default stack segment.

The `environ` attribute specifies the task's global environment through a generic pointer that references an arbitrary application-defined data structure; this attribute defaults to `NULL`.

The `name` attribute specifies the task's printable name, which is a `NULL`-terminated character string; this attribute defaults to the empty string `""`. This name can be returned by `TSK_getname`.

The `exitflag` attribute specifies whether the task must terminate before the program as a whole can terminate; this attribute defaults to `TRUE`.

The `initstackflag` attribute specifies whether the task stack is initialized to enable stack depth checking by `TSK_checkstacks`. This attribute applies both in cases where the `stack` attribute is `NULL` (stack is allocated by `TSK_create`) and where the `stack` attribute is used to specify a pre-allocated stack. If your application does not call `TSK_checkstacks`, you can reduce the time consumed by `TSK_create` by setting this attribute to `FALSE`.

All default attribute values are contained in the constant `TSK_ATTRS`, which can be assigned to a variable of type `TSK_Attrs` prior to calling `TSK_create`.

A task switch occurs when calling `TSK_create` if the priority of the new task is greater than the priority of the current task.

`TSK_create` calls `MEM_alloc` to dynamically create an object's data structure. `MEM_alloc` must lock the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2–205.

## Constraints and Calling Context

- ❑ `TSK_create` cannot be called from a SWI or HWI.
- ❑ The `fxn` parameter and the `name` attribute cannot be `NULL`.
- ❑ The `priority` attribute must be less than or equal to `TSK_MAXPRI` and greater than or equal to `TSK_MINPRI`. The `priority` can be less than zero (0) for tasks that should not execute.
- ❑ The string referenced through the `name` attribute cannot be allocated locally.

- ❑ The `stackseg` attribute must identify a valid memory segment.
- ❑ You can reduce the size of your application program by creating objects with `Tconf` rather than using the `XXX_create` functions.

**See Also**

`MEM_alloc`  
`SYS_error`  
`TSK_delete`  
`TSK_exit`

**TSK\_delete***Delete a task***C Interface**

<b>Syntax</b>	TSK_delete(task);
<b>Parameters</b>	TSK_Handle task;     /* task object handle */
<b>Return Value</b>	Void

**Description**

TSK\_delete removes the task from all internal queues and calls MEM\_free to free the task object and stack. task should be in a state that does not violate any of the listed constraints.

If all remaining tasks have their exitflag attribute set to FALSE, DSP/BIOS terminates the program as a whole by calling SYS\_exit with a status code of 0.

You can use Tconf to specify an application-wide Delete function that runs whenever a task is deleted. The default Delete function is a no-op function. The Delete function is called before the task object has been removed from any internal queues and its object and stack are freed. Any DSP/BIOS function can be called from the Delete function. DSP/BIOS passes the task handle of the task being deleted to your Delete function. Your Delete function declaration should be similar to the following:

```
Void myDeleteFxn(TSK_Handle task);
```

TSK\_delete calls MEM\_free to delete the TSK object. MEM\_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Note:**

Unless the mode of the deleted task is TSK\_TERMINATED, TSK\_delete should be called with care. For example, if the task has obtained exclusive access to a resource, deleting the task makes the resource unavailable.

**Constraints and Calling Context**

- The task cannot be the currently executing task (TSK\_self).
- TSK\_delete cannot be called from a SWI or HWI.
- No check is performed to prevent TSK\_delete from being used on a statically-created object. If a program attempts to delete a task object that was created using Tconf, SYS\_error is called.

**See Also**

MEM\_free  
TSK\_create

**TSK\_deltatime***Update task statistics with time difference***C Interface**

<b>Syntax</b>	TSK_deltatime(task);
<b>Parameters</b>	TSK_Handle task;     /* task object handle */
<b>Return Value</b>	Void

**Description**

This function accumulates the time difference from when a task is made ready to the time TSK\_deltatime is called. These time differences are accumulated in the task's internal STS object and can be used to determine whether or not a task misses real-time deadlines.

If TSK\_deltatime is not called by a task, its STS object is never updated in the Statistics View, even if TSK accumulators are enabled in the RTA Control Panel.

TSK statistics are handled differently than other statistics because TSK functions typically run an infinite loop that blocks when waiting for other threads. In contrast, HWI and SWI functions run to completion without blocking. Because of this difference, DSP/BIOS allows programs to identify the "beginning" of a TSK function's processing loop by calling TSK\_settime and the "end" of the loop by calling TSK\_deltatime.

For example, if a task waits for data and then processes the data, you want to ensure that the time from when the data is made available until the processing is complete is always less than a certain value. A loop within the task can look something like the following:

```
Void task
{
    'do some startup work'

    /* Initialize time in task's
       STS object to current time */
    TSK_settime(TSK_self());

    for (;;) {
        /* Get data */
        SIO_get(...);

        'process data'
```

```
    /* Get time difference and
       add it to task's STS object */
    TSK_deltatime(TSK_self());
  }
}
```

In the example above, the task blocks on SIO\_get and the device driver posts a semaphore that readies the task. DSP/BIOS sets the task's statistics object with the current time when the semaphore becomes available and the task is made ready to run. Thus, the call to TSK\_deltatime effectively measures the processing time of the task.

### Constraints and Calling Context

- ❑ The results of calls to TSK\_deltatime and TSK\_settime are displayed in the Statistics View only if Enable TSK accumulators is selected in the RTA Control Panel.

### See Also

TSK\_getsts  
TSK\_settime

**TSK\_disable***Disable DSP/BIOS task scheduler***C Interface****Syntax** TSK\_disable();**Parameters** Void**Return Value** Void**Description**

TSK\_disable disables the DSP/BIOS task scheduler. The current task continues to execute (even if a higher priority task can become ready to run) until TSK\_enable is called.

TSK\_disable does not disable interrupts, but is instead used before disabling interrupts to make sure a context switch to another task does not occur when interrupts are disabled.

TSK\_disable maintains a count which allows nested calls to TSK\_disable. Task switching is not reenabled until TSK\_enable has been called as many times as TSK\_disable. Calls to TSK\_disable can be nested.

Since TSK\_disable can prohibit ready tasks of higher priority from running it should not be used as a general means of mutual exclusion. SEM Module semaphores should be used for mutual exclusion when possible.

**Constraints and Calling Context**

- ❑ Do not call any function that can cause the current task to block or otherwise affect the state of the scheduler within a TSK\_disable/TSK\_enable block. For example, SEM\_pend (if timeout is non-zero), TSK\_sleep, TSK\_yield, and MEM\_alloc can all cause blocking. Similarly, any MEM module call and any call that dynamically creates or deletes an object (XXX\_create or XXX\_delete) can affect the state of the scheduler. For a complete list, see the "Possible Context Switch" column in Section A.1, *Function Callability Table*.
- ❑ TSK\_disable cannot be called from a SWI or HWI.
- ❑ TSK\_disable cannot be called from the program's main() function.
- ❑ Do not call TSK\_enable when TSKs are already enabled. If you do so, the subsequent call to TSK\_disable will not disable TSK processing.

**See Also**SEM Module  
TSK\_enable

**TSK\_enable***Enable DSP/BIOS task scheduler***C Interface****Syntax** TSK\_enable();**Parameters** Void**Return Value** Void**Description**

TSK\_enable is used to reenble the DSP/BIOS task scheduler after TSK\_disable has been called. Since TSK\_disable calls can be nested, the task scheduler is not enabled until TSK\_enable is called the same number of times as TSK\_disable.

A task switch occurs when calling TSK\_enable only if there exists a TSK\_READY task whose priority is greater than the currently executing task.

**Constraints and Calling Context**

- ❑ Do not call any function that can cause the current task to block or otherwise affect the state of the scheduler within a TSK\_disable/TSK\_enable block. For example, SEM\_pend (if timeout is non-zero), TSK\_sleep, TSK\_yield, and MEM\_alloc can all cause blocking. Similarly, any MEM module call and any call that dynamically creates or deletes an object (XXX\_create or XXX\_delete) can affect the state of the scheduler. For a complete list, see the "Possible Context Switch" column in Section A.1, *Function Callability Table*.
- ❑ TSK\_enable cannot be called from a SWI or HWI.
- ❑ TSK\_enable cannot be called from the program's main() function.
- ❑ Do not call TSK\_enable when TSKs are already enabled. If you do so, the subsequent call to TSK\_disable will not disable TSK processing.

**See Also**SEM Module  
TSK\_disable

**TSK\_exit***Terminate execution of the current task***C Interface****Syntax** TSK\_exit();**Parameters** Void**Return Value** Void**Description**

TSK\_exit terminates execution of the current task, changing its mode from TSK\_RUNNING to TSK\_TERMINATED. If all tasks have been terminated, or if all remaining tasks have their exitflag attribute set to FALSE, then DSP/BIOS terminates the program as a whole by calling the function SYS\_exit with a status code of 0.

TSK\_exit is automatically called whenever a task returns from its top-level function.

You can use Tconf to specify an application-wide Exit function that runs whenever a task is terminated. The default Exit function is a no-op function. The Exit function is called before the task has been blocked and marked TSK\_TERMINATED. Any DSP/BIOS function can be called from an Exit function. Calling TSK\_self within an Exit function returns the task being exited. Your Exit function declaration should be similar to the following:

```
Void myExitFxn(Void);
```

A task switch occurs when calling TSK\_exit unless the program as a whole is terminated.

**Constraints and Calling Context**

- ❑ TSK\_exit cannot be called from a SWI or HWI.
- ❑ TSK\_exit cannot be called from the program's main() function.

**See Also**

MEM\_free  
TSK\_create  
TSK\_delete



**TSK\_getenv***Get task environment pointer***C Interface**

**Syntax**                    `environ = TSK_getenv(task);`

**Parameters**                `TSK_Handle task;        /* task object handle */`

**Return Value**              `Ptr                    environ;    /* task environment pointer */`

**Description**

TSK\_getenv returns the environment pointer of the specified task. The environment pointer, environ, references an arbitrary application-defined data structure.

If your program uses multiple HOOK objects, HOOK\_getenv allows you to get environment pointers you have set for a particular HOOK and TSK object combination.

**See Also**

HOOK\_getenv  
HOOK\_setenv  
TSK\_setenv  
TSK\_seterr  
TSK\_setpri

**TSK\_geterr***Get task error number***C Interface**

**Syntax**                    `errno = TSK_geterr(task);`

**Parameters**                `TSK_Handle task;        /* task object handle */`

**Return Value**              `Int                    errno;        /* error number */`

**Description**                Each task carries a task-specific error number. This number is initially `SYS_OK`, but it can be changed by `TSK_seterr`. `TSK_geterr` returns the current value of this number.

**See Also**                    `SYS_error`  
`TSK_setenv`  
`TSK_seterr`  
`TSK_setpri`

**TSK\_getname***Get task name***C Interface**

**Syntax**                    name = TSK\_getname(task);

**Parameters**                TSK\_Handle task;        /\* task object handle \*/

**Return Value**             String            name;        /\* task name \*/

**Description**              TSK\_getname returns the task's name.

For tasks created with Tconf, the name is available to this function only if the "Allocate Task Name on Target" property is set to true for this task. For tasks created with TSK\_create, TSK\_getname returns the attrs.name field value, or an empty string if this attribute was not specified.

**See Also**                    TSK\_setenv  
                              TSK\_seterr  
                              TSK\_setpri

**TSK\_getpri***Get task priority***C Interface****Syntax**                    priority = TSK\_getpri(task);**Parameters**                TSK\_Handle task;        /\* task object handle \*/**Return Value**              Int                    priority;    /\* task priority \*/**Description**                TSK\_getpri returns the priority of task.**See Also**                    TSK\_setenv  
TSK\_seterr  
TSK\_setpri

**TSK\_getsts***Get the handle of the task's STS object***C Interface**

**Syntax**                    `sts = TSK_getsts(task);`

**Parameters**                `TSK_Handle task;        /* task object handle */`

**Return Value**              `STS_Handle sts;        /* statistics object handle */`

**Description**

This function provides access to the task's internal STS object. For example, you can want the program to check the maximum value to see if it has exceeded some value.

**See Also**

`TSK_deltatime`  
`TSK_settime`

**TSK\_isTSK**

*Check to see if called in the context of a TSK*

**C Interface**

**Syntax**                    result = TSK\_isTSK(Void);

**Parameters**                Void

**Return Value**            Bool            result;    /\* TRUE if in TSK context, FALSE otherwise \*/

**Reentrant**                yes

**Description**             This macro returns TRUE when it is called within the context of a TSK or IDL function. It returns FALSE in all other contexts.

TSK\_isTSK() API returns TRUE when the current thread is neither a HWI nor a SWI. Thus, TSK\_isTSK() returns TRUE when it is invoked within a task thread, main(), or a task switch hook.

In previous versions of DSP/BIOS, calling the context checking functions from main() resulted in TRUE for HWI\_isHWI(). And, calling the context checking functions from a task switch hook resulted in TRUE for SWI\_isSWI(). This is no longer the case; they are identified as part of the TSK context.

In applications that contain no task threads, TSK\_isTSK() now returns TRUE from main() and from the IDL threads.

**See Also**                 HWI\_isHWI  
                              SWI\_isSWI

**TSK\_itick***Advance the system alarm clock (interrupt use only)***C Interface****Syntax** TSK\_itick();**Parameters** Void**Return Value** Void**Description**

TSK\_itick increments the system alarm clock, and readies any tasks blocked on TSK\_sleep or SEM\_pend whose timeout intervals have expired.

**Constraints and Calling Context**

- ❑ TSK\_itick cannot be called by a TSK object.
- ❑ TSK\_itick cannot be called from the program's main() function.
- ❑ When called within an HWI, the code sequence calling TSK\_itick must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

**See Also**

SEM\_pend  
TSK\_sleep  
TSK\_tick

**TSK\_self***Returns handle to the currently executing task***C Interface****Syntax** `curtask = TSK_self();`**Parameters** Void**Return Value** TSK\_Handle curtask; /\* handle for current task object \*/**Description** TSK\_self returns the object handle for the currently executing task. This function is useful when inspecting the object or when the current task changes its own priority through TSK\_setpri.

No task switch occurs when calling TSK\_self.

**See Also** TSK\_setpri



**TSK\_setenv***Set task environment***C Interface****Syntax** TSK\_setenv(task, environ);**Parameters** TSK\_Handle task; /\* task object handle \*/  
Ptr environ; /\* task environment pointer \*/**Return Value** Void**Description**

TSK\_setenv sets the task environment pointer to environ. The environment pointer, environ, references an arbitrary application-defined data structure.

If your program uses multiple HOOK objects, HOOK\_setenv allows you to set individual environment pointers for each HOOK and TSK object combination.

**See Also**HOOK\_getenv  
HOOK\_setenv  
TSK\_getenv  
TSK\_geterr

**TSK\_seterr***Set task error number***C Interface****Syntax**                    TSK\_seterr(task, errno);**Parameters**                TSK\_Handle task;        /\* task object handle \*/  
                              Int                errno;        /\* error number \*/**Return Value**              Void**Description**                Each task carries a task-specific error number. This number is initially SYS\_OK, but can be changed to errno by calling TSK\_seterr. TSK\_geterr returns the current value of this number.**See Also**                    TSK\_getenv  
                                  TSK\_geterr

**TSK\_setpri***Set a task's execution priority***C Interface**

**Syntax**                                    `oldpri = TSK_setpri(task, newpri);`

**Parameters**                                `TSK_Handle task;        /* task object handle */`  
`Int                    newpri;    /* task's new priority */`

**Return Value**                            `Int                    oldpri;        /* task's old priority */`

**Description**

TSK\_setpri sets the execution priority of task to newpri, and returns that task's old priority value. Raising or lowering a task's priority does not necessarily force preemption and re-scheduling of the caller: tasks in the TSK\_BLOCKED mode remain suspended despite a change in priority; and tasks in the TSK\_READY mode gain control only if their (new) priority is greater than that of the currently executing task.

The maximum value of newpri is TSK\_MAXPRI(15). If the minimum value of newpri is TSK\_MINPRI(0). If newpri is less than 0, the task is barred from further execution until its priority is raised at a later time by another task; if newpri equals TSK\_MAXPRI, execution of the task effectively locks out all other program activity, except for the handling of interrupts.

The current task can change its own priority (and possibly preempt its execution) by passing the output of TSK\_self as the value of the task parameter.

A context switch occurs when calling TSK\_setpri if a task makes its own priority lower than the priority of another currently ready task, or if the currently executing task makes a ready task's priority higher than its own priority. TSK\_setpri can be used for mutual exclusion.

**Constraints and Calling Context**

- newpri must be less than or equal to TSK\_MAXPRI.
- The task cannot be TSK\_TERMINATED.
- The new priority should not be zero (0). This priority level is reserved for the TSK\_idle task.

**See Also**

TSK\_self  
 TSK\_sleep

**TSK\_settime***Reset task statistics previous value to current time***C Interface**

<b>Syntax</b>	TSK_settime(task);
<b>Parameters</b>	TSK_Handle task;     /* task object handle */
<b>Return Value</b>	Void

**Description**

Your application can call TSK\_settime before a task enters its processing loop in order to ensure your first call to TSK\_deltatime is as accurate as possible and doesn't reflect the time difference since the time the task was created. However, it is only necessary to call TSK\_settime once for initialization purposes. After initialization, DSP/BIOS sets the time value of the task's STS object every time the task is made ready to run.

TSK statistics are handled differently than other statistics because TSK functions typically run an infinite loop that blocks when waiting for other threads. In contrast, HWI and SWI functions run to completion without blocking. Because of this difference, DSP/BIOS allows programs to identify the "beginning" of a TSK function's processing loop by calling TSK\_settime and the "end" of the loop by calling TSK\_deltatime.

For example, a loop within the task can look something like the following:

```
Void task
{
    'do some startup work'

    /* Initialize task's STS object to current time */
    TSK_settime(TSK_self());

    for (;;) {
        /* Get data */
        SIO_get(...);

        'process data'

        /* Get time difference and
           add it to task's STS object */
        TSK_deltatime(TSK_self());
    }
}
```

In the previous example, the task blocks on SIO\_get and the device driver posts a semaphore that readies the task. DSP/BIOS sets the task's statistics object with the current time when the semaphore becomes available and the task is made ready to run. Thus, the call to TSK\_deltatime effectively measures the processing time of the task.

**Constraints and  
Calling Context**

- ❑ TSK\_settime cannot be called from the program's main() function.
- ❑ The results of calls to TSK\_deltatime and TSK\_settime are displayed in the Statistics View only if Enable TSK accumulators is selected within the RTA Control Panel.

**See Also**

TSK\_deltatime  
TSK\_getsts

**TSK\_sleep***Delay execution of the current task***C Interface**

<b>Syntax</b>	TSK_sleep(nticks);
<b>Parameters</b>	Uns            nticks;    /* number of system clock ticks to sleep */
<b>Return Value</b>	Void

**Description**            TSK\_sleep changes the current task's mode from TSK\_RUNNING to TSK\_BLOCKED, and delays its execution for nticks increments of the system clock. The actual time delayed can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

After the specified period of time has elapsed, the task reverts to the TSK\_READY mode and is scheduled for execution.

A task switch always occurs when calling TSK\_sleep if nticks > 0.

**Constraints and Calling Context**

- ❑ TSK\_sleep cannot be called from a SWI or HWI, or within a TSK\_disable / TSK\_enable block.
- ❑ TSK\_sleep cannot be called from the program's main() function.
- ❑ TSK\_sleep should not be called from within an IDL function. Doing so prevents analysis tools from gathering run-time information.
- ❑ nticks cannot be SYS\_FOREVER.

**TSK\_stat***Retrieve the status of a task***C Interface**

**Syntax** TSK\_stat(task, statbuf);

**Parameters** TSK\_Handle task; /\* task object handle \*/  
TSK\_Stat \*statbuf; /\* pointer to task status structure \*/

**Return Value** Void

**Description**

TSK\_stat retrieves attribute values and status information about a task.

Status information is returned through statbuf, which references a structure of type TSK\_Stat defined as follows:

```
struct TSK_Stat {      /* task status structure */
    TSK_Attrs  attrs; /* task attributes */
    TSK_Mode   mode; /* task execution mode */
    Ptr        sp;    /* task stack pointer */
#ifdef _55_
    Ptr        ssp;   /* task system stack pointer */
#endif
    size_t     used; /* task stack used */
#ifdef _55_
    size_t     sysused; /* task system stack used */
#endif
};
```

When a task is preempted by a software or hardware interrupt, the task execution mode returned for that task by TSK\_stat is still TSK\_RUNNING because the task runs when the preemption ends.

The current task can inquire about itself by passing the output of TSK\_self as the first argument to TSK\_stat. However, the task stack pointer (sp) in the TSK\_Stat structure is the value from the previous context switch. In addition, the task system stack pointer (ssp) provided for 'C55x is invalid when calling TSK\_stat for the current task.

TSK\_stat has a non-deterministic execution time. As such, it is not recommended to call this API from SWIs or HWIs.

**Constraints and Calling Context**

❑ statbuf cannot be NULL.

**See Also**

TSK\_create

**TSK\_tick***Advance the system alarm clock***C Interface****Syntax**                    TSK\_tick();**Parameters**                Void**Return Value**              Void**Description**

TSK\_tick increments the system clock, and readies any tasks blocked on TSK\_sleep or SEM\_pend whose timeout intervals have expired. TSK\_tick can be invoked by an HWI or by the currently executing task. The latter is particularly useful for testing timeouts in a controlled environment.

A task switch occurs when calling TSK\_tick if the priority of any of the readied tasks is greater than the priority of the currently executing task.

**Constraints and  
Calling Context**

- ❑ When called within an HWI, the code sequence calling TSK\_tick must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

**See Also**

CLK Module  
SEM\_pend  
TSK\_itick  
TSK\_sleep



**TSK\_time***Return current value of system clock***C Interface**

<b>Syntax</b>	<code>curtime = TSK_time();</code>
<b>Parameters</b>	Void
<b>Return Value</b>	Uns <code>curtime; /* current time */</code>

**Description**

TSK\_time returns the current value of the system alarm clock.

Note that since the system clock is usually updated asynchronously via TSK\_itick or TSK\_tick, curtime can lag behind the actual system time. This lag can be even greater if a higher priority task preempts the current task between the call to TSK\_time and when its return value is used. Nevertheless, TSK\_time is useful for getting a rough idea of the current system time.

**TSK\_yield***Yield processor to equal priority task***C Interface****Syntax** TSK\_yield();**Parameters** Void**Return Value** Void**Description**

TSK\_yield yields the processor to another task of equal priority.

A task switch occurs when you call TSK\_yield if there is an equal priority task ready to run.

Tasks of higher priority preempt the currently running task without the need for a call to TSK\_yield. If only lower-priority tasks are ready to run when you call TSK\_yield, the current task continues to run. Control does not pass to a lower-priority task.

**Constraints and Calling Context**

- ❑ When called within an HWI, the code sequence calling TSK\_yield must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.
- ❑ TSK\_yield cannot be called from the program's main() function.

**See Also**

TSK\_sleep

## 2.30 std.h and stdlib.h functions

This section contains descriptions of special utility macros found in std.h and DSP/BIOS standard library functions found in stdlib.h.

### Macros

- ❑ **ArgToInt.** Cast an Arg type parameter as an integer type.
- ❑ **ArgToPtr.** Cast an Arg type parameter as a pointer type.

### Functions

- ❑ **atexit.** Register an exit function.
- ❑ **\*calloc.** Allocate and clear memory.
- ❑ **exit.** Call the exit functions registered by atexit.
- ❑ **free.** Free memory.
- ❑ **\*getenv.** Get environmental variable.
- ❑ **\*malloc.** Allocate memory.
- ❑ **\*realloc.** Reallocate a memory packet.

### Syntax

```
#include <std.h>
ArgToInt (arg)
ArgToPtr (arg)
```

```
#include <stdlib.h>
int  atexit(void (*fcn)(void));
void *calloc(size_t nobj, size_t size);
void exit(int status);
void free(void *p);
char *getenv(char *name);
void *malloc(size_t size);
void *realloc(void *p, size_t size);
```

### Description

The DSP/BIOS library contains some C standard library functions which supersede the library functions bundled with the C compiler. These functions follow the ANSI C specification for parameters and return values. Consult Kernighan and Ritchie for a complete description of these functions.

The functions calloc, free, malloc, and realloc use MEM\_alloc and MEM\_free (with segid = Segment for malloc/free) to allocate and free memory.

getenv uses the \_environ variable defined and initialized in the boot file to search for a matching environment string.

exit calls the exit functions registered by atexit before calling SYS\_exit.

**Note: RTS Functions Callable from TSK Threads Only**

Many runtime support (RTS) functions use lock and unlock functions to prevent reentrancy. However, DSP/BIOS SWI and HWI threads cannot call LCK\_pend and LCK\_post. As a result, RTS functions that call LCK\_pend or LCK\_post *must not be called in the context of a SWI or HWI thread*. For a list of RTS functions that should not be called from a SWI or an HWI function, see “LCK\_pend” on page 2-180.

---

To determine whether a particular RTS function uses LCK\_pend, refer to the source code for that function shipped with Code Composer Studio. The following table shows some of the RTS functions that call LCK\_pend in certain versions of Code Composer Studio:

---

fprintf	printf	vfprintf	sprintf
vprintf	vsprintf	clock	strftime
minit	malloc	realloc	free
calloc	rand	srand	getenv

---

The C++ new operator calls malloc, which in turn calls LCK\_pend. As a result, the new operator cannot be used in the context of a SWI or HWI thread.

# Function Callability and Error Tables

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This appendix provides tables describing TMS320C55x errors and function callability.

<b>Topic</b>	<b>Page</b>
<b>A.1 Function Callability Table</b> .....	<b>A-2</b>
<b>A.2 DSP/BIOS Error Codes</b> .....	<b>A-11</b>

## A.1 Function Callability Table

The following table indicates what types of threads can call each of the DSP/BIOS functions. The Possible Context Switch column indicates whether another thread may be run as a result of this function. For example, the function may block on a resource or it may make another thread ready to run. The Possible Context Switch column does not indicate whether the function disables interrupts that might schedule higher-priority threads.

Table A-1 Function Callability

Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?	Callable from main()?
ATM_andi	Yes	Yes	Yes	No	Yes
ATM_andu	Yes	Yes	Yes	No	Yes
ATM_cleari	Yes	Yes	Yes	No	Yes
ATM_clearu	Yes	Yes	Yes	No	Yes
ATM_decu	Yes	Yes	Yes	No	Yes
ATM_deci	Yes	Yes	Yes	No	Yes
ATM_inci	Yes	Yes	Yes	No	Yes
ATM_incu	Yes	Yes	Yes	No	Yes
ATM_ori	Yes	Yes	Yes	No	Yes
ATM_oru	Yes	Yes	Yes	No	Yes
ATM_seti	Yes	Yes	Yes	No	Yes
ATM_setu	Yes	Yes	Yes	No	Yes
BUF_alloc	Yes	Yes	Yes	No	Yes
BUF_create	Yes	No	No	Yes	Yes
BUF_delete	Yes	No	No	Yes	Yes
BUF_free	Yes	Yes	Yes	No	Yes
BUF_maxbuff	Yes	No	No	No	Yes
BUF_stat	Yes	Yes	Yes	No	Yes
C55_disableIER0, C55_disableIER1	Yes	Yes	Yes	No	Yes
C55_disableInt	Yes	Yes	Yes	No	Yes
C55_enableIER0, C55_enableIER1	Yes	Yes	Yes	No	Yes
C55_enableInt	Yes	Yes	Yes	No	Yes
C55_I2AckInt	No	No	Yes*	No	No

Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?	Callable from main()?
C55_I2DisableMIR, C55_I2DisableMIR1	Yes	Yes	Yes	No	Yes
C55_I2EnableMIR, C55_I2EnableMIR1	Yes	Yes	Yes	No	Yes
C55_I2SetIntPriority	Yes	Yes	Yes	No	Yes
C55_plug	Yes	Yes	Yes	No	Yes
CLK_countspms	Yes	Yes	Yes	No	Yes
CLK_cpuCyclesPerHtime	Yes	Yes	Yes	No	Yes
CLK_cpuCyclesPerLtime	Yes	Yes	Yes	No	Yes
CLK_gethtime	Yes	Yes	Yes	No	No
CLK_getltime	Yes	Yes	Yes	No	No
CLK_getprd	Yes	Yes	Yes	No	Yes
CLK_reconfig	Yes	Yes	Yes	No	Yes
CLK_setTimerFunc	Yes	Yes	Yes	No	Yes
CLK_start	Yes	Yes	Yes	No	No
CLK_stop	Yes	Yes	Yes	No	No
DEV_createDevice	Yes	No	No	Yes*	Yes
DEV_deleteDevice	Yes	No	No	Yes*	Yes
DEV_match	Yes	Yes	Yes	No	Yes
GBL_getClkin	Yes	Yes	Yes	No	Yes
GBL_getFrequency	Yes	Yes	Yes	No	Yes
GBL_getProclId	Yes	Yes	Yes	No	Yes
GBL_getVersion	Yes	Yes	Yes	No	Yes
GBL_setFrequency	No	No	No	No	Yes
GBL_setProclId	No	No	No	No	No*
GIO_abort	Yes	No*	No*	Yes	No
GIO_control	Yes	No*	No*	Yes	Yes
GIO_create	Yes	No	No	No	Yes
GIO_delete	Yes	No	No	Yes	Yes
GIO_flush	Yes	No*	No*	Yes	No
GIO_new	Yes	Yes	Yes	No	Yes
GIO_read	Yes	No*	No*	Yes	Yes*
GIO_submit	Yes	Yes*	Yes*	Yes	Yes*
GIO_write	Yes	No*	No*	Yes	Yes*
HOOKE_getenv	Yes	Yes	Yes	No	Yes

<b>Function</b>	<b>Callable by TSKs?</b>	<b>Callable by SWIs?</b>	<b>Callable by HWIs?</b>	<b>Possible Context Switch?</b>	<b>Callable from main()?</b>
HOOK_setenv	Yes	Yes	Yes	No	Yes
HST_getpipe	Yes	Yes	Yes	No	Yes
HWI_disable	Yes	Yes	Yes	No	Yes
HWI_dispatchPlug	Yes	Yes	Yes	No	Yes
HWI_enable	Yes	Yes	Yes	Yes*	No
HWI_enter	No	No	Yes	No	No
HWI_exit	No	No	Yes	Yes	No
HWI_isHWI	Yes	Yes	Yes	No	Yes
HWI_restore	Yes	Yes	Yes	Yes*	Yes
IDL_run	Yes	No	No	No	No
LCK_create	Yes	No	No	Yes*	Yes
LCK_delete	Yes	No	No	Yes*	No
LCK_pend	Yes	No	No	Yes*	No
LCK_post	Yes	No	No	Yes*	No
LOG_disable	Yes	Yes	Yes	No	Yes
LOG_enable	Yes	Yes	Yes	No	Yes
LOG_error	Yes	Yes	Yes	No	Yes
LOG_event	Yes	Yes	Yes	No	Yes
LOG_message	Yes	Yes	Yes	No	Yes
LOG_printf	Yes	Yes	Yes	No	Yes
LOG_reset	Yes	Yes	Yes	No	Yes
MBX_create	Yes	No	No	Yes*	Yes
MBX_delete	Yes	No	No	Yes*	No
MBX_pend	Yes	Yes*	Yes*	Yes*	No
MBX_post	Yes	Yes*	Yes*	Yes*	Yes*
MEM_alloc	Yes	No	No	Yes*	Yes
MEM_calloc	Yes	No	No	Yes*	Yes
MEM_define	Yes	No	No	Yes*	Yes
MEM_free	Yes	No	No	Yes*	Yes
MEM_getBaseAddress	Yes	Yes	Yes	No	Yes
MEM_increaseTableSize	Yes	No	No	Yes*	Yes
MEM_redefine	Yes	No	No	Yes*	Yes
MEM_stat	Yes	No	No	Yes*	Yes
MEM_undefine	Yes	No	No	Yes*	Yes
MEM_valloc	Yes	No	No	Yes*	Yes



Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?	Callable from main()?
MSGQ_alloc	Yes	Yes	Yes	No	Yes
MSGQ_close	Yes	Yes	Yes	No	Yes
MSGQ_count	Yes	Yes*	Yes*	No	No
MSGQ_free	Yes	Yes	Yes	No	Yes
MSGQ_get	Yes	Yes*	Yes*	Yes*	No
MSGQ_getAttrs	Yes	Yes	Yes	No	Yes
MSGQ_getDstQueue	Yes	Yes	Yes	No	No
MSGQ_getMsgId	Yes	Yes	Yes	No	Yes
MSGQ_getMsgSize	Yes	Yes	Yes	No	Yes
MSGQ_getSrcQueue	Yes	Yes	Yes	No	No
MSGQ_isLocalQueue	Yes	Yes	Yes	No	Yes
MSGQ_locate	Yes	No	No	Yes	No
MSGQ_locateAsync	Yes	Yes	Yes	No	No
MSGQ_open	Yes	Yes*	Yes*	Yes*	Yes
MSGQ_put	Yes	Yes	Yes	No	No
MSGQ_release	Yes	Yes	Yes	No	No
MSGQ_setErrorHandler	Yes	Yes	Yes	No	Yes
MSGQ_setMsgId	Yes	Yes	Yes	No	Yes
MSGQ_setSrcQueue	Yes	Yes	Yes	No	Yes
PIP_alloc	Yes	Yes	Yes	Yes	Yes
PIP_free	Yes	Yes	Yes	Yes	Yes
PIP_get	Yes	Yes	Yes	Yes	Yes
PIP_getReaderAddr	Yes	Yes	Yes	No	Yes
PIP_getReaderNumFrames	Yes	Yes	Yes	No	Yes
PIP_getReaderSize	Yes	Yes	Yes	No	Yes
PIP_getWriterAddr	Yes	Yes	Yes	No	Yes
PIP_getWriterNumFrames	Yes	Yes	Yes	No	Yes
PIP_getWriterSize	Yes	Yes	Yes	No	Yes
PIP_peek	Yes	Yes	Yes	No	Yes
PIP_put	Yes	Yes	Yes	Yes	Yes
PIP_reset	Yes	Yes	Yes	Yes	Yes
PIP_setWriterSize	Yes	Yes	Yes	No	Yes
PRD_getticks	Yes	Yes	Yes	No	Yes
PRD_start	Yes	Yes	Yes	No	Yes
PRD_stop	Yes	Yes	Yes	No	Yes

Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?	Callable from main()?
PRD_tick	Yes	Yes	Yes	Yes	No
PWRM_changeSetpoint	Yes	Yes*	No	No	No
PWRM_configure	Yes	Yes	Yes	No	Yes
PWRM_getCapabilities	Yes	Yes	Yes	No	Yes
PWRM_getCurrentSetpoint	Yes	Yes	Yes	No	Yes
PWRM_getDependencyCount	Yes	Yes	Yes	No	Yes
PWRM_getNumSetpoints	Yes	Yes	Yes	No	Yes
PWRM_getSetpointInfo	Yes	Yes	Yes	No	Yes
PWRM_getTransitionLatency	Yes	Yes	Yes	No	Yes
PWRM_idleClocks	Yes	Yes	Yes	No	Yes
PWRM_registerNotify	Yes	No	No	Yes*	Yes
PWRM_releaseDependency	Yes	Yes	Yes	No	Yes
PWRM_setDependency	Yes	Yes	Yes	No	Yes
PWRM_sleepDSP	Yes	Yes*	No	No	No
PWRM_unregisterNotify	Yes	Yes	Yes	No	No
QUE_create	Yes	No	No	Yes*	Yes
QUE_delete	Yes	No	No	Yes*	Yes
QUE_dequeue	Yes	Yes	Yes	No	Yes
QUE_empty	Yes	Yes	Yes	No	Yes
QUE_enqueue	Yes	Yes	Yes	No	Yes
QUE_get	Yes	Yes	Yes	No	Yes
QUE_head	Yes	Yes	Yes	No	Yes
QUE_insert	Yes	Yes	Yes	No	Yes
QUE_new	Yes	Yes	Yes	No	Yes
QUE_next	Yes	Yes	Yes	No	Yes
QUE_prev	Yes	Yes	Yes	No	Yes
QUE_put	Yes	Yes	Yes	No	Yes
QUE_remove	Yes	Yes	Yes	No	Yes
RTDX_channelBusy	Yes	Yes	No	No	Yes
RTDX_CreateInputChannel	Yes	Yes	No	No	Yes
RTDX_CreateOutputChannel	Yes	Yes	No	No	Yes
RTDX_disableInput	Yes	Yes	No	No	Yes
RTDX_disableOutput	Yes	Yes	No	No	Yes
RTDX_enableInput	Yes	Yes	No	No	Yes
RTDX_enableOutput	Yes	Yes	No	No	Yes

Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?	Callable from main()?
RTDX_isInputEnabled	Yes	Yes	No	No	Yes
RTDX_isOutputEnabled	Yes	Yes	No	No	Yes
RTDX_read	Yes	Yes	No	No	No
RTDX_readNB	Yes	Yes	No	No	No
RTDX_sizeofInput	Yes	Yes	No	No	Yes
RTDX_write	Yes	Yes	No	No	No
SEM_count	Yes	Yes	Yes	No	Yes
SEM_create	Yes	No	No	Yes*	Yes
SEM_delete	Yes	Yes*	No	Yes*	No
SEM_new	Yes	Yes	Yes	No	Yes
SEM_pend	Yes	Yes*	Yes*	Yes*	No
SEM_pendBinary	Yes	Yes*	Yes*	Yes*	No
SEM_post	Yes	Yes	Yes	Yes*	Yes
SEM_postBinary	Yes	Yes	Yes	Yes*	Yes
SEM_reset	Yes	No	No	No	Yes
SIO_bufsize	Yes	Yes	Yes	No	Yes
SIO_create	Yes	No	No	Yes*	Yes
SIO_ctrl	Yes	Yes	No	No	Yes
SIO_delete	Yes	No	No	Yes*	Yes
SIO_flush	Yes	Yes*	No	No	No
SIO_get	Yes	No	No	Yes*	Yes*
SIO_idle	Yes	Yes*	No	Yes*	No
SIO_issue	Yes	Yes	No	No	Yes
SIO_put	Yes	No	No	Yes*	Yes*
SIO_ready	Yes	Yes	Yes	No	No
SIO_reclaim	Yes	Yes*	No	Yes*	Yes*
SIO_reclaimx	Yes	Yes*	No	Yes*	Yes*
SIO_segid	Yes	Yes	Yes	No	Yes
SIO_select	Yes	Yes*	No	Yes*	No
SIO_staticbuf	Yes	Yes	No	No	Yes
STS_add	Yes	Yes	Yes	No	Yes
STS_delta	Yes	Yes	Yes	No	Yes
STS_reset	Yes	Yes	Yes	No	Yes
STS_set	Yes	Yes	Yes	No	Yes
SWI_andn	Yes	Yes	Yes	Yes*	No

Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?	Callable from main()?
SWI_andnHook	Yes	Yes	Yes	Yes*	No
SWI_create	Yes	No	No	Yes*	Yes
SWI_dec	Yes	Yes	Yes	Yes*	No
SWI_delete	Yes	No	No	Yes*	Yes
SWI_disable	Yes	Yes	No	No	No
SWI_enable	Yes	Yes	No	Yes*	No
SWI_getattr	Yes	Yes	Yes	No	Yes
SWI_getmbox	No	Yes	No	No	No
SWI_getpri	Yes	Yes	Yes	No	Yes
SWI_inc	Yes	Yes	Yes	Yes*	No
SWI_isSWI	Yes	Yes	Yes	No	Yes
SWI_or	Yes	Yes	Yes	Yes*	No
SWI_orHook	Yes	Yes	Yes	Yes*	No
SWI_post	Yes	Yes	Yes	Yes*	No
SWI_raisepri	No	Yes	No	No	No
SWI_restorepri	No	Yes	No	Yes	No
SWI_self	No	Yes	No	No	No
SWI_setattr	Yes	Yes	Yes	No	Yes
SYS_abort	Yes	Yes	Yes	No	Yes
SYS_atexit	Yes	Yes	Yes	No	Yes
SYS_error	Yes	Yes	Yes	No	Yes
SYS_exit	Yes	Yes	Yes	No	Yes
SYS_printf	Yes	Yes	Yes	No	Yes
SYS_putchar	Yes	Yes	Yes	No	Yes
SYS_sprintf	Yes	Yes	Yes	No	Yes
SYS_vprintf	Yes	Yes	Yes	No	Yes
SYS_vsprintf	Yes	Yes	Yes	No	Yes
TRC_disable	Yes	Yes	Yes	No	Yes
TRC_enable	Yes	Yes	Yes	No	Yes
TRC_query	Yes	Yes	Yes	No	Yes
TSK_checkstacks	Yes	No	No	No	No
TSK_create	Yes	No	No	Yes*	Yes
TSK_delete	Yes	No	No	Yes*	No
TSK_deltatime	Yes	Yes	Yes	No	No
TSK_disable	Yes	No	No	No	No

Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?	Callable from main()?
TSK_enable	Yes	No	No	Yes*	No
TSK_exit	Yes	No	No	Yes*	No
TSK_getenv	Yes	Yes	Yes	No	Yes
TSK_geterr	Yes	Yes	Yes	No	Yes
TSK_getname	Yes	Yes	Yes	No	Yes
TSK_getpri	Yes	Yes	Yes	No	Yes
TSK_getsts	Yes	Yes	Yes	No	Yes
TSK_isTSK	Yes	Yes	Yes	No	Yes
TSK_itick	No	Yes	Yes	Yes	No
TSK_self	Yes	Yes	Yes	No	No
TSK_setenv	Yes	Yes	Yes	No	Yes
TSK_seterr	Yes	Yes	Yes	No	Yes
TSK_setpri	Yes	Yes	Yes	Yes*	Yes
TSK_settime	Yes	Yes	Yes	No	No
TSK_sleep	Yes	No	No	Yes*	No
TSK_stat	Yes	Yes*	Yes*	No	Yes
TSK_tick	Yes	Yes	Yes	Yes*	No
TSK_time	Yes	Yes	Yes	No	No
TSK_yield	Yes	Yes	Yes	Yes*	No

Note: \*See the appropriate API reference page for more information.

Table A-2 RTS Function Calls

Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?
calloc	Yes	No	No	Yes*
clock	Yes	No	No	Yes*
fprintf	Yes	No	No	Yes*
free	Yes	No	No	Yes*
getenv	Yes	No	No	Yes*
malloc	Yes	No	No	Yes*
minit	Yes	No	No	Yes*
printf	Yes	No	No	Yes*
rand	Yes	No	No	Yes*
realloc	Yes	No	No	Yes*

Function	Callable by TSKs?	Callable by SWIs?	Callable by HWIs?	Possible Context Switch?
sprintf	Yes	No	No	Yes*
srand	Yes	No	No	Yes*
strftime	Yes	No	No	Yes*
vsprintf	Yes	No	No	Yes*
vprintf	Yes	No	No	Yes*
vsprintf	Yes	No	No	Yes*

Note: \*See section 2.30, *std.h* and *stdlib.h* functions, page 2-511 for more information.

## A.2 DSP/BIOS Error Codes

Table A-3 Error Codes

Name	Value	SYS_Errors[Value]
SYS_OK	0	"(SYS_OK)"
SYS_EALLOC	1	"(SYS_EALLOC): segid = %d, size = %u, align = %u" Memory allocation error.
SYS_EFREE	2	"(SYS_EFREE): segid = %d, ptr = 0x%x, size = %u" The memory free function associated with the indicated memory segment was unable to free the indicated size of memory at the address indicated by ptr.
SYS_ENODEV	3	"(SYS_ENODEV): device not found" The device being opened is not configured into the system.
SYS_EBUSY	4	"(SYS_EBUSY): device in use" The device is already opened by the maximum number of users.
SYS_EINVAL	5	"(SYS_EINVAL): invalid parameter" An invalid parameter was passed.
SYS_EBADIO	6	"(SYS_EBADIO): device failure" The device was unable to support the I/O operation.
SYS_EMODE	7	"(SYS_EMODE): invalid mode" An attempt was made to open a device in an improper mode; e.g., an attempt to open an input device for output.
SYS_EDOMAIN	8	"(SYS_EDOMAIN): domain error" Used by SPOX-MATH when type of operation does not match vector or filter type.
SYS_ETIMEOUT	9	"(SYS_ETIMEOUT): timeout error" Used by device drivers to indicate that reclaim timed out.
SYS_EEOF	10	"(SYS_EEOF): end-of-file error" Used by device drivers to indicate the end of a file.
SYS_EDEAD	11	"(SYS_EDEAD): previously deleted object" An attempt was made to use an object that has been deleted.
SYS_EBADOBJ	12	"(SYS_EBADOBJ): invalid object" An attempt was made to use an object that does not exist.
SYS_ENOTIMPL	13	"(SYS_ENOTIMPL): action not implemented" An attempt was made to use an action that is not implemented.
SYS_ENOTFOUND	14	"(SYS_ENOTFOUND): resource not found" An attempt was made to use a resource that could not be found.
SYS_EUSER	>=256	"(SYS_EUSER): <user-defined string>" User-defined error.





# **C55x DSP/BIOS Register Usage**

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This appendix provides tables describing the TMS320C55x register conventions in terms of preservation across multi-threaded context switching and preconditions.

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<b>B.2 Register Conventions.....</b>	<b>B-2</b>
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## B.1 Overview

In a multi-threaded application using DSP/BIOS, it is necessary to know which registers can or cannot be modified. Furthermore, users need to understand which registers are preserved across task context switches and interrupts.

## B.2 Register Conventions

The following definitions describe the various possible register handling behaviors:

- ❑ **H - HWI.** These registers are saved/restored by the HWI dispatcher and HWI\_enter/HWI\_exit. In general, the "child" function register set (as defined by the C compiler) is not preserved by the HWI dispatcher or the HWI\_enter macro since it is assumed that the HWI function called is written in C and will therefore preserve any "child" registers it uses.
- ❑ **T - TSK.** These registers are saved/restored during a TSK context switch. In general, only the "child" function register set is actively preserved in the task's execution context during a synchronous context switch. This is because it is assumed that the function that invoked the task switch has already saved its "parent" register set. Task context switches that result from preemption by an interrupt will preserve the entire processor state so that execution can safely resume at the instruction following the interrupted instruction.
- ❑ **G - Global.** These registers are shared across all threads in the system. They are not saved and restored during interrupt handling nor during task context switching. To make a temporary change, save the register, make the change, and then restore it.
- ❑ **I - Initialized register.** These registers are set to a particular value during HWI processing and are restored to their incoming value upon return to the interrupted routine.

*Table 2–12 Register Handling*

Register	Register Name	Type	Notes
AC0-AC3	Accumulators	H	
(X)AR0-(X)AR4	Auxiliary Registers	H	
(X)AR5-(X)AR7	Auxiliary Registers	T	These "child" registers are presumed to be saved by an HWI that uses them.

Register	Register Name	Type	Notes
BK03, BK47, BKC	Circular Buffer Size Registers	H	
BRC0, BRC1	Block-repeat counters	H	
BRS1	BRC1 save register	H	
BSA01, BSA23, BSA45, BSA67, BSAC	Circular Buffer Start Address Registers	H	
(X)CDP	Coefficient Data Pointer	H	
CFCT	Control-flow context register	H,T	
CSR	Computed Single Repeat	H	
DBIER0, DBIER1	Debug Interrupt Enable Registers	G	DSP/BIOS does not touch these registers.
(X)DP	Data Page Register	H,T	
IER0, IER1	Interrupt Enable Registers	I	Modified by interrupt handlers, and may not be fully restored upon return.
IFR0, IFR1	Interrupt Flag Registers	G	Initialized by DSP/BIOS at boot time, untouched thereafter.
IVPD, IVPH	Interrupt Vector Table Pointers	G	Initialized by DSP/BIOS at boot time, untouched thereafter.
PC	Program Counter	H, T	
RPTC	Single Repeat Counter	H	
RSA0, RSA1	Block-repeat start address registers	H	
REA0, REA1	Block-repeat end address registers	H	
RETA	Return Address Register	H,T	
(X)SP	Stack Pointer	H,T	Changed to ISR SP during HWI execution, restored upon return.
(X)SSP	System Stack Pointer	H,T	Changed to ISR SSP during HWI execution, restored upon return.
T0, T1	Temporary Registers	H,T	
T2, T3	Temporary Registers	T	These "child" registers are presumed to be saved by an HWI that uses them.
TRN0, TRN1	Transition Registers	H	

### B.3 Status Register Conventions

The status registers (ST0-ST2) are automatically preserved by hardware during interrupt processing such that upon return from an HWI, these status registers are returned to the state they were in prior to the interrupt. ST3 bits are generally propagated except as shown below.

At system boot time and prior to entering an HWI thread handled by the DSP/BIOS HWI dispatcher or coded using HWI\_enter/HWI\_exit, some status bits are configured by DSP/BIOS in order to establish a C-compatible and DSP/BIOS-compatible runtime context for DSP/BIOS functions and HWIs. These settings are consistent with those presumed by the C/C++ compiler.

The following definitions describe the various possible status register bit handling behaviors:

- ❑ **X - Untouched.** DSP/BIOS does not manipulate these bits nor depend on their values.
- ❑ **B-*n* - BIOS.** DSP/BIOS sets the bit(s) to the value *n* at boot time and before entering a HWI that uses the HWI dispatcher or HWI\_enter/HWI\_exit. Proper operation of DSP/BIOS is not guaranteed if an application changes these status bit settings.
- ❑ **P - Propagated.** These bits are not restored upon returning from an interrupt or task context switch. Instead, they are propagated through all context switches. (That is, once they are changed, they remain changed through all contexts.)

*Table 2–13 Status Bit Handling*

Register	Status Bit	Status Bit Name	Type	Notes
ST0	AC0V2	AC2 overflow flag	X	Restored after int
	AC0V3	AC3 overflow flag	X	Restored after int
	TC1	Test/control flag 1	X	Restored after int
	TC2	Test/control flag 2	X	Restored after int
	CARRY	Carry Bit	X	Restored after int
	AC0V0	AC0 overflow flag	X	Restored after int
	AC0V1	AC1 overflow flag	X	Restored after int
ST1	BRAF	Block-repeat active flag	X	Restored after int
	CPL	Compiler mode	B-1	Restored after int

Register	Status Bit	Status Bit Name	Type	Notes
	XF	External flag	X,P	
	HM	Hold mode	X,P	
	INTM	Interrupt Mask	B-0	Restored after int
	M40	Computation mode for the D unit	B-0	Restored after int
	SATD	Saturation mode for the D unit	B-0	Restored after int
	SXMD	Sign-extension mode for the D unit	B-1	Restored after int
	C16	Dual 16-bit arithmetic mode	B-0	Restored after int
	FRCT	Fractional mode	B-0	Restored after int
	C54CM	C54x-compatible mode	B-0	Restored after int
	ASM	Accumulator shift mode	X	Restored after int
ST2	ARMS	AR mode switch	B-1	Restored after int
	DBGM	Debug mode	X	Restored after int
	EALLOW	Emulation access enable	X	Restored after int
	RDM	Rounding mode	B-0	Restored after int
	CDPLC	CDP linear/circular configuration	B-0	Restored after int
	AR0-7LC	ARn linear/circular configuration	B-0	Restored after int
ST3	CAFRZ	Cache freeze	X,P	
	CAEN	Cache enable	X,P	
	CACLR	Cache clear	X,P	
	HINT	Host interrupt	X,P	
	CBERR	CPU bus error	X,P	
	MPNMC	Microprocessor/Microcomputer mode	X,P	
	SATA	Saturation mode for A unit	B-0	Restored after int
	CLKOFF	CLKOUT disable	X,P	
	SMUL	Saturation-on-multiplication mode	B-1	Restored after int
	SST	Saturate-on-store mode	X	Restored after int



# DSP/BIOS for OMAP 2320

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This appendix describes things you need to know about DSP/BIOS in order to use it with the OMAP 2320 platform.

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## C.1 Overview

DSP/BIOS has been enhanced to provide seamless support for the core timers and Level 2 Interrupt Controller (L2IC) present within the OMAP 2320. The CLK module functionality is now driven by the core timers. The HWI module APIs can define and manipulate level 2 interrupts in addition to level 1 interrupts.

The OMAP 2320 is part of a series of next generation "OMAP 4" devices. This series encompasses the 23xx and 24xx devices.

## C.2 OMAP 2320 and the CLK Module

Changes and enhancements have been made to the DSP/BIOS CLK module to enable the use of OMAP 2320 core timers. The OMAP 2320 has 2 core timers, which can be used to drive the low- and high- resolution DSP/BIOS clock functionality.

### C.2.1 Static Configuration

By default, the low-resolution CLK function (see `CLK_gettime`) is enabled and assigned to core Timer 0. Alternately, you can configure Timer 1 for this function. To change the configuration, add the following line to your Tconf configuration file:

```
bios.CLK.TIMERSELECT = "Timer 1"; // "Timer 0" or "Timer 1"
```

You can disable the low-resolution CLK function using the following Tconf script commands:

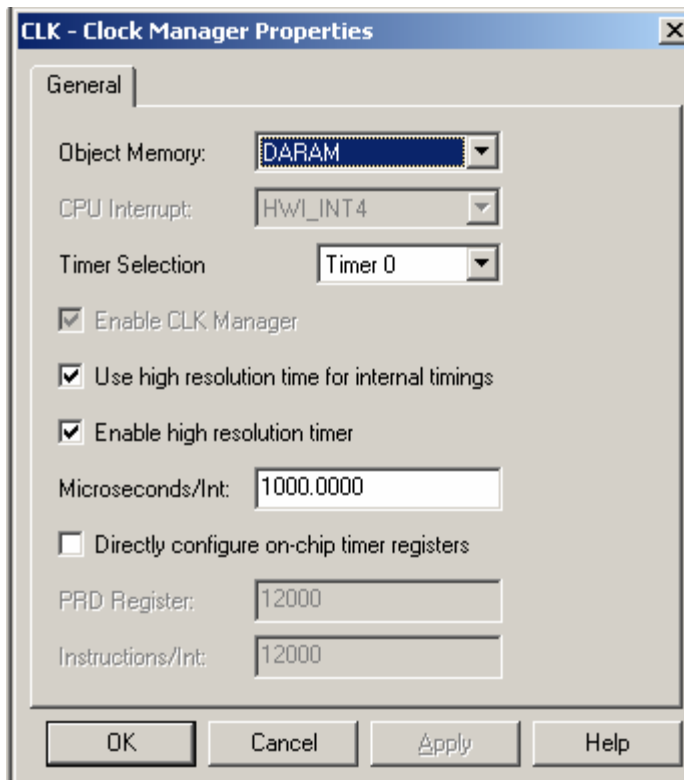
```
bios.CLK.ENABLECLK = 0;  
bios.PRD.USECLK = 0;
```

By default, the high-resolution CLK function (see `CLK_gettime`) is enabled and derived from the low-resolution timer. You can disable this function with the following configuration script command:

```
bios.CLK.ENABLEHETIME = 0; // 0 (disabled) or 1 (enabled)
```



In the Gconf configuration tool, the CLK properties for the OMAP 2320 are as follows:



## C.3 OMAP 2320 and the HWI Module

With the introduction of the OMAP family of dual-core ARM + 'C55x devices, many more interrupt sources have been defined than can be terminated on the legacy 'C55x level 1 interrupt controller, which has a limit of 32 interrupts. To accommodate additional interrupt sources, a new interrupt mechanism has been provided in hardware: the "Level 2 Interrupt Controller" (L2IC).

The additional interrupts are prioritized and multiplexed by the Level 2 Interrupt Controller onto two dedicated level 1 interrupts. DSP/BIOS internally configures all 32 level 2 interrupts to terminate on the single level 1 FIQ interrupt. In the 23xx/24xx OMAP family, many peripherals that formerly interrupted the DSP at level 1 have been moved to level 2.

The DSP/BIOS interface to this interrupt controller is called the Level 2 Interrupt Manager (L2IM). The complexities of the L2IM are concealed by reusing and enhancing existing HWI module APIs. As a result, very few new API elements are needed.

The following sections describe extensions made to the HWI module to support the OMAP 2320.

### C.3.1 Level 2 Interrupt Controller Base Address

By default, the Level 2 Interrupt Controller (L2IC) resides at data memory address 0x7c4800. This coincides with the reset IOMA value of 0x3e. The IO MAP (IOMA) base address is the page index used to access DSP I/O space addresses from DSP memory space.

If you modify IOMA for any reason, you need to tell DSP/BIOS the new base address for the L2IC. The following Tconf configuration property is provided for this purpose:

```
bios.HWI.INTC_BASE = 0x7c4800; // 0x7c4800 is default
```

### C.3.2 Level 2 Interrupt Objects and Properties

There are 64 new HWI interrupt objects defined to correspond to level 2 interrupts 0 through 63. These objects are named HWI\_L2\_INT0 through HWI\_L2\_INT63.

The following parameters have been added to HWI interrupt objects to allow for static configuration of the level 2 interrupt priorities, mirmask, and mir1mask:

- ❑ **iMirMask.** This property is valid for both level 1 and 2 interrupts. It specifies which level 2 interrupts the dispatcher should disable before calling this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptMask0 and interruptMask1, which deal with level 1 interrupts.)
  - The "self" option causes the dispatcher to disable only the current interrupt and causes the appropriate interruptBitMask0, interruptBitMask1, mirmask, and mir1mask values to be generated for the interrupt being configured.
  - The "all" option disables all level 2 interrupts.
  - The "none" option disables no level 2 interrupts.
  - The "bitmask" option causes the mirmask and mir1mask properties to be used to specify the level 2 interrupts to disable.
- ❑ **mirmask.** This property is valid for both level 1 and 2 interrupts. It defines a bitmask of level 2 interrupts 0-31 to be disabled by the DSP/BIOS HWI dispatcher when executing this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptBitMask0, which masks level 1 interrupts.)
- ❑ **mir1mask.** This property is valid for both level 1 and 2 interrupts. It defines a bitmask of level 2 interrupts 32-63 to be disabled by the DSP/BIOS HWI dispatcher when executing this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptBitMask1, which masks level 1 interrupts.)
- ❑ **priority.** Sets the priority from 0 to 63 of a level 2 interrupt. Zero is the highest priority. The default priority for a level 2 interrupt matches its interrupt number. Although this field exists for all HWI interrupt objects, it cannot be configured for level 1 interrupts. You can change the priority at run-time using the C55\_I2SetIntPriority API.

The following Tconf statements configure the level 2 interrupt 0 to have a priority of 63 (lowest priority) and a mirmask of 0xffffffff (no other level 2 interrupts enabled while servicing this interrupt):

```
// valid priority values: 0-63
bios.HWI_L2_INT0.priority = 63;

// use dispatcher and enable setting iMirMask, mirmask
bios.HWI_L2_INT0.useDispatcher = true;

// "bitmask" enables writing to mirmask and mir1mask
bios.HWI_L2_INT0.iMirMask = "bitmask";

// no other L2 interrupts while servicing HWI_L2_INT0
bios.HWI_L2_INT0.mirmask = 0xffffffff;

// no other L2 interrupts while servicing HWI_L2_INT0
bios.HWI_L2_INT0.mir1mask = 0xffffffff;
```

### C.3.3 HWI\_dispatchPlug API

The range of vector IDs allowed is extended from 0-31 to 0-95. The IDs 32-95 correspond to level 2 interrupts 0-63 respectively. The c55.h file now includes definitions for C55\_L2\_INT0 through C55\_L2\_INT63, which map to vector IDs 32-95.

The HWI\_Attrs structure used by HWI\_dispatchPlug has been expanded to include two additional fields: mirmask and mir1mask. Each of these fields contains a 32-bit mask to specify which of the additional level 2 interrupts to mask during the interrupt. The mirmask field controls L2 interrupts 0-31. The mir1mask field controls L2 interrupts 32-63.

```
typedef struct HWI_Attrs {
    Uns    ier0mask; // Level 1 interrupt masks
    Uns    ier1mask;
    Arg    arg;      // fxn arg (default = 0)
    LgUns  mirmask;  // Level 2 interrupt mask 0-31
    LgUns  mir1mask; // Level 2 interrupt mask 32-63
} HWI_Attrs;
```

The default values of mirmask and mir1mask (provided by HWI\_ATTRS) for all interrupts is consistent with the “self” setting.

### C.3.4 HWI\_enter and HWI\_exit APIs

The HWI\_enter and HWI\_exit assembly language macros have been enhanced to support selective interrupt nesting control of level 2 interrupts. This matches the way level 1 interrupts are controlled.

The argument lists for these macros have two additional interrupt mask arguments. In HWI\_enter, these 32-bit bitmasks define which level 2 interrupts are to be masked while executing the HWI body. In HWI\_exit, these masks define which level 2 interrupts are to be restored to their prior state before returning from the interrupt.

The OMAP 2320 macro invocation syntax is shown below:

```
HWI_enter C55_AR_DR_X_MASK, C55_ACC_X_MASK,  
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK,  
IER0DISABLEMASK, IER1DISABLEMASK, MIRDISABLEMASK,  
MIR1DISABLEMASK
```

```
HWI_exit C55_AR_DR_X_MASK, C55_ACC_X_MASK,  
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK,  
IER0RESTOREMASK, IER1RESTOREMASK, MIRRESTOREMASK,  
MIR1RESTOREMASK
```

## C.4 OMAP 2320 and the C55 Module

In addition to extensions to the HWI module, the following extensions have been made to the C55 module to support the OMAP 2320 level 2 interrupts.

### C.4.1 C55\_plug API

For C55\_plug, the range of vector IDs is extended from 0-31 to 0-95. The IDs 32-95 correspond to level 2 interrupts 0-63 respectively. The c55.h file now includes definitions C55\_L2\_INT0 through C55\_L2\_INT63 which map to vector IDs 32-95.

### C.4.2 New APIs

The following APIs have been added to the C55 module for use with OMAP 2320. For details, see the topics for these APIs in the alphabetic reference in Chapter 2.

- ❑ C55\_disableInt. Disable an individual interrupt.
- ❑ C55\_enableInt. Enable an individual interrupt.
- ❑ C55\_I2AckInt. Explicitly acknowledge an L2 interrupt
- ❑ C55\_I2DisableMIR. Disable a mask of L2 interrupts
- ❑ C55\_I2EnableMIR. Enable a mask of L2 interrupts
- ❑ C55\_I2SetIntPriority. Set the priority of a L2 interrupt

## C.5 Building DSP/BIOS Applications for OMAP 2320

In order for the proper DSP/BIOS header files to be used during the build process, you must define the symbol "\_2320\_" at assembly time.

If you are building from the command line, add the following option to your assembler command line:

```
-d_2320_
```

If you are building with Code Composer Studio, follow these steps:

- 1) Open the application's CCStudio project.
- 2) Choose **Project->Build Options** to open the Build Options dialog.
- 3) Go to the Compiler tab and choose the Assembly category
- 4) Add **\_2320\_** to the "Pre-Define NAME (-ad)" field.
- 5) Click **OK**.

## C.6 Usage Examples

The following examples provide examples that use the HWI and C55 APIs related to the OMAP 2320.

### C.6.1 Installing and Enabling a Single Level 2 Interrupt

This C code example plugs and enables the 23xx Level 2 interrupt #1.

```

/*
 * ===== l2_example1.c =====
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void myIsr (Arg id)
{
    LOG_printf(&trace, "My l2 ISR %d", ArgToInt(id));
}

Void main ()
{
    HWI_Attrs attrs = HWI_ATTRS;

    // pass vector ID to myIsr
    attrs.arg = (Arg)C55_L2_INT1;

    // Plug Level 2 Interrupt #1 Vector
    HWI_dispatchPlug(C55_L2_INT1, (Fxn)myIsr, &attrs);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}

```

## C.6.2 Installing and Enabling Multiple Level 2 Interrupts

This C code example plugs and enables level 2 interrupts numbers 10, 11, 12, and 13 and sets their priority levels to 0, 1, 2, 3 respectively (0 = highest priority). The default interrupt nesting behavior (all other interrupts enabled while l2FiqFunc is called) is configured.

```

/*
 * ===== l2_example2.c =====
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void l2FiqFunc(Arg id)
{
    LOG_printf(&trace, "l2_fiq %d\n", ArgToInt(id)%32);
}

Void main()
{
    HWI_Attrs attrs;
    attrs = HWI_ATTRS;

    attrs.arg = (Arg)C55_L2_INT10;
    HWI_dispatchPlug( C55_L2_INT10, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT10, 0);

    attrs.arg = (Arg)C55_L2_INT11;
    HWI_dispatchPlug( C55_L2_INT11, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT11, 1);

    attrs.arg = (Arg)C55_L2_INT12;
    HWI_dispatchPlug( C55_L2_INT12, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT12, 2);

    attrs.arg = (Arg)C55_L2_INT13;
    HWI_dispatchPlug( C55_L2_INT13, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT13, 3);

    C55_l2EnableMIR(0x00003c00);
}

```



### C.6.3 Enabling an L2 Interrupt Using "interrupt" Keyword

This C code example plugs and enables OMAP 23xx level 2 interrupt number 1.

```
/*
 * ===== l2_example3.c =====
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

interrupt void myIsr ()
{
    // Acknowledge this level 2 interrupt to the L2IC
    C55_L2AckInt();

    // ...
    // Your code here
    // ...
}

Void main ()
{
    // Plug Level 2 Interrupt #1 Vector
    C55_plug(C55_L2_INT1, (Fxn)myIsr);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}
```

## C.6.4 Assembly Language ISR Using HWI\_enter, HWI\_exit

This assembly code example uses the MIR mask arguments.

```

;#
;# DSP/BIOS Level 2 interrupt example
;#

; Include files
.include log.h55
.include hwi.h55
.include c55.h55

.global _l2FiqFunc
.global _intCount
.ref _trace
.ref _reportInfo

_myIsr:
HWI_enter C55_ALL_AR_DR_REGS, C55_ALL_ACC_REGS,
C55_ALL_MISC1_REGS, C55_ALL_MISC2_REGS,
C55_ALL_MISC3_REGS,
0x0000,          ; ier0 interrupt mask unchanged
0x0000,          ; ier1 interrupt mask unchanged
0xffffffff      ; all level 2 ints 0-31 masked
0xffffffff      ; all level 2 ints 32-63 masked

;
;           Your code here
;

HWI_exit C55_ALL_AR_DR_REGS, C55_ALL_ACC_REGS,
C55_ALL_MISC1_REGS, C55_ALL_MISC2_REGS,
C55_ALL_MISC3_REGS,
0x0000,          ; ier0 interrupt mask unchanged
0x0000,          ; ier1 interrupt mask unchanged
0xffffffff      ; all level 2 ints 0-31 restored
0xffffffff      ; all level 2 ints 32-63 restored
```

## C.6.5 Statically Configuring a Level 2 Interrupt

This example plugs and enables Level 2 interrupt number 43. All other level 1 and level 2 interrupts are disabled by the DSP/BIOS dispatcher during the execution of "myIsr".

```

/*
 * ===== l2_example4.c =====
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void myIsr (Arg id)
{
    LOG_printf(&trace, "My L2 ISR %d", ArgToInt(id));
}

Void main ()
{
    // Enable Level 2 interrupt number 43
    C55_enableInt(C55_L2_INT43);
}

-----
                          TCONF script
-----
/* ===== l2_example4.tcf ===== */

bios.HWI_L2_INT43.useDispatcher = 1;
                               // use HWI dispatcher
bios.HWI_L2_INT43.fxn = prog.extern("myIsr");
                               // attach to "myIsr" C function
bios.HWI_L2_INT43.arg = 43;
                               // pass interrupt ID as argument
bios.HWI_L2_INT43.iMirMask = "all";
                               // mask all other L2 ints
bios.HWI_L2_INT43.interruptMask0 = "all";
                               // mask L1 ints 0-15
bios.HWI_L2_INT43.interruptMask1 = "all";
                               // mask L1 ints 16-31
bios.HWI_L2_INT43.priority = 15;

```



# DSP/BIOS for OMAP 2420

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This appendix describes things you need to know about DSP/BIOS in order to use it with the OMAP 2420 platform.

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## D.1 Overview

DSP/BIOS has been enhanced to provide seamless support for the General Purpose Timers (GP Timers) and Level 2 Interrupt Controller (L2IC) present within the OMAP 2420. The CLK module functionality is now driven by GP Timers. The HWI module APIs can define and manipulate level 2 interrupts in addition to level 1 interrupts.

The OMAP 2420 is the first in a series of next generation "OMAP 4" devices. This series may also be referred to as OMAP24xx devices.

Documentation for the OMAP 2420 is provided in the *OMAP 2410/2420 Technical Reference Manual* (SWPU064).

## D.2 OMAP 2420 and the CLK Module

A number of changes and enhancements have been made to the DSP/BIOS CLK module to enable the use of OMAP 2420 General Purpose (GP) timers. The OMAP 2420 has 12 General Purpose (GP) timers. Four timers (5, 6, 7, and 8) are designed to be used by the DSP.

### D.2.1 Static Configuration

For OMAP 2420, the high- and low-resolution DSP/BIOS clocks are completely independent of each other. It is possible to disable the low-resolution CLK while still supporting the high-resolution CLK features, and vice versa.

The following CLK module properties have differences for OMAP 2420:

- ❑ **TIMERSELECT.** This property may be set to "Timer 5" or "Timer 6" to set the GP timer used for the low-resolution time. The GP Timer 7 is used for the high-resolution time. Timer 5 (the default) runs at 32 kHz. Timers 6 and 7 run at 12 MHz. For example:

```
bios.CLK.TIMERSELECT = "Timer 5";
```

- ❑ **TIMERS\_BASE.** This property points to the address of GP timer 5 within the DSP address space. This location is set by the DSP MMU configuration shown in Section D.2.2, *GEL Configuration*. The locations of timers 6 and 7 are determined by adding 0x0400 and 0x0800 respectively to the base address. For example, the following statement informs DSP/BIOS that the GP Timer 5 is mapped to IO address 0x7000, the GP Timer 6 is mapped to IO address 0x7400, and the GP Timer 7 is mapped to IO address 0x7800.

```
bios.CLK.TIMERS_BASE = 0x7000;
```

- ❑ **ENABLECLK.** For OMAP 2420, this property enables/disables only the low-resolution timer. For example, these statements disable the low-resolution clock:

```

bios.PRD.USECLK = false;
bios.CLK.ENABLECLK = false;

```

- ❑ **ENABLEHTIME.** For OMAP 2420, this property enables/disables the high-resolution clock independent of the low-resolution clock. For example:

```

bios.CLK.ENABLEHTIME = false;

```

## D.2.2 GEL Configuration

In order for the DSP to access the GP timers, you must configure the DSP MMU to map the GP timers into the DSP address space. This can be done using the following ARM-side GEL commands (which are also provided with CCStudio) or dedicated ARM code.

```

hotmenu ProgramMMU()
{
    /* DSP MMU_SYSCONFIG - Set bit 1 to perform a SOFTRESET */
    *(int *)0x5A000010 |= 0x2;

    /* TLB 0 - GPTIMER5 = 0x7000, Big Endian */
    *(int *)0x5A000050 = 0x00000000;    /* DSP MMU_LOCK */
    *(int *)0x5A000058 = 0x00fdc00e;    /* DSP MMU_CAM */
    *(int *)0x5A00005C = 0x4807c340;    /* DSP MMU_RAM */
    *(int *)0x5A000054 = 0x00000001;    /* DSP MMU_LD_TLB */

    /* TLB 1 - GPTIMER6 = 0x7400, Big Endian */
    *(int *)0x5A000050 = 0x00000010;    /* DSP MMU_LOCK */
    *(int *)0x5A000058 = 0x00fdd00e;    /* DSP MMU_CAM */
    *(int *)0x5A00005C = 0x4807e340;    /* DSP MMU_RAM */
    *(int *)0x5A000054 = 0x00000001;    /* DSP MMU_LD_TLB */

    /* TLB 2 - GPTIMER7 = 0x7c00, Big Endian */
    *(int *)0x5A000050 = 0x00000020;    /* DSP MMU_LOCK */
    *(int *)0x5A000058 = 0x00fde00e;    /* DSP MMU_CAM */
    *(int *)0x5A00005C = 0x48080340;    /* DSP MMU_RAM */
    *(int *)0x5A000054 = 0x00000001;    /* DSP MMU_LD_TLB */

    /* disable TLB updates, disable TWL, enable MMU */
    *(int*)0x5a000044 = 0x02;
}

```

In addition, you must route the appropriate clock sources to each GP timer (32KHz to the low-resolution timer, SYSCLK to the high-resolution timer). This can also be done using the following ARM-side GEL commands or dedicated ARM code.

```
hotmenu RouteGPTClocks() {
    /* CM_FCKLEN1_CORE */
    /* Enable functional clock to GPT 5,6,7 */
    (*(int*)0x48008200) = 0x380;

    /* CM_ICKLEN1_CORE */
    /* Enable interface clock to GPT 5,6,7 */
    (*(int*)0x48008210) = 0x380;

    /* CM_CLKSEL2_CORE */
    /* route 32kHz clock to gpt5,6 and sys_clk to gpt7 */
    (*(int*)0x48008244) = 0x1000;

    /* PRCM_CLKCFG_CTRL */
    /* Validate CLK config in previous step */
    (*(int*)0x48008080) = 1;
}
```



## D.3 OMAP 2420 and the HWI Module

With the introduction of the OMAP family of dual-core ARM + 'C55x devices, many more interrupt sources have been defined than can be terminated on the legacy 'C55x level 1 interrupt controller, which has a limit of 32 interrupts. To accommodate additional interrupt sources, a new interrupt mechanism has been provided in hardware: the "Level 2 Interrupt Controller" (L2IC).

The additional interrupts are prioritized and multiplexed by the Level 2 Interrupt Controller onto two dedicated level 1 interrupts. DSP/BIOS internally configures all 32 level 2 interrupts to terminate on the single level 1 FIQ interrupt. In the 24xx OMAP family, many peripherals that formerly interrupted the DSP at level 1 have been moved out to level 2.

The L2IC contains a 32-bit Interrupt Mask Register (MIR), which defines which level 2 interrupts are enabled or disabled.

The DSP/BIOS interface to the L2IC is implemented as part of the HWI module. The following sections describe extensions made to the HWI module to support the OMAP 2420.

### D.3.1 Level 2 Interrupt Controller Base Address

By default, the Level 2 Interrupt Controller (L2IC) resides at data memory address 0x7e4800. This coincides with the reset IOMA value of 0x3f. The IO MAP (IOMA) base address is the page index used to access DSP I/O space addresses from DSP memory space.

If you modify IOMA for any reason, you need to tell DSP/BIOS the new base address for the L2IC. The following Tconf configuration property is provided for this purpose:

```
bios.HWI.INTC_BASE = 0x7e4800; // 0x7e4800 is default
```

See the *OMAP 2410/2420 Technical Reference Manual* (SWPU064) for details about programming IOMA.

### D.3.2 Level 2 Interrupt Objects and Properties

There are 32 new HWI interrupt objects defined to correspond to level 2 interrupts 0 through 31. These objects are named HWI\_L2\_INT0 through HWI\_L2\_INT31.

The following parameters have been added to HWI interrupt objects to allow for static configuration of the level 2 interrupt priorities and mirmask:

- **iMirMask.** This property is valid for both level 1 and 2 interrupts. It specifies which level 2 interrupts the dispatcher should disable before calling this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptMask0 and interruptMask1, which deal with level 1 interrupts.)
  - The "self" option causes the dispatcher to disable only the current interrupt and causes the appropriate interruptBitMask0, interruptBitMask1, and mirmask values to be generated for the interrupt being configured.
  - The "all" option disables all level 2 interrupts.
  - The "none" option disables no level 2 interrupts.
  - The "bitmask" option causes the mirmask property to be used to specify which level 2 interrupts to disable.
- **mirmask.** This property is valid for both level 1 and 2 interrupts. It defines a bitmask of the level 2 interrupts to be disabled by the DSP/BIOS HWI dispatcher when executing this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptBitMask0 and interruptBitMask1, which mask level 1 interrupts.)
- **priority.** Sets the priority from 0 to 31 of a level 2 interrupt. Zero is the highest priority. The default priority for a level 2 interrupt matches its interrupt number. Although this field exists for all HWI interrupt objects, it cannot be configured for level 1 interrupts. You can change the priority at run-time using the C55\_I2SetIntPriority API.

The following Tconf statements configure the level 2 interrupt 0 to have a priority of 31 (lowest priority) and a mirmask of 0xffffffff (no other level 2 interrupts enabled while servicing this interrupt):

```
// valid priority values: 0-31
bios.HWI_L2_INT0.priority = 31;

// use dispatcher and enable setting iMirMask, mirmask
bios.HWI_L2_INT0.useDispatcher = true;

// setting to "bitmask" enables writing to mirmask
bios.HWI_L2_INT0.iMirMask = "bitmask";

// no other L2 interrupts while servicing HWI_L2_INT0
bios.HWI_L2_INT0.mirmask = 0xffffffff;
```

### D.3.3 HWI\_dispatchPlug API

The range of vector IDs allowed is extended from 0-31 to 0-63. The IDs 32-63 correspond to level 2 interrupts 0-31 respectively. The `c55.h` file now includes definitions for `C55_L2_INT0` through `C55_L2_INT31`, which map to vector IDs 32-63.

The `HWI_Attrs` structure used by `HWI_dispatchPlug` has been expanded to include a `mirmask` field. This field contains a 32-bit mask to specify which additional level 2 interrupts to mask during the interrupt. Each bit in this mask corresponds to a level 2 interrupt. The default value of `mirmask` for all interrupts is to mask only the current level 2 interrupt.

```
typedef struct HWI_Attrs {
    Uns    ier0mask;    // Level 1 interrupt masks
    Uns    ier1mask;
    Arg    arg;        // fxn arg (default = 0)
    LgUns  mirmask;    // Level 2 interrupt mask
} HWI_Attrs;
```

### D.3.4 HWI\_enter and HWI\_exit APIs

The `HWI_enter` and `HWI_exit` assembly language macros have been enhanced to support selective interrupt nesting control of level 2 interrupts. This matches the way level 1 interrupts are controlled.

The argument lists for these macros have an additional interrupt mask argument. In `HWI_enter`, this 32-bit bitmask defines which level 2 interrupts are to be masked while executing the HWI body. In `HWI_exit`, the mask defines which level 2 interrupts are to be restored to their prior state before returning from the interrupt.

The OMAP 2420 macro invocation syntax is shown below:

```
HWI_enter C55_AR_DR_X_MASK, C55_ACC_X_MASK,  
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK,  
IER0DISABLEMASK, IER1DISABLEMASK, MIRDISABLEMASK
```

```
HWI_exit C55_AR_DR_X_MASK, C55_ACC_X_MASK,  
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK,  
IER0RESTOREMASK, IER1RESTOREMASK, MIRRESTOREMASK
```

## D.4 OMAP 2420 and the C55 Module

In addition to extensions to the HWI module, the following extensions have been made to the C55 module to support the OMAP 2420 level 2 interrupts.

### D.4.1 C55\_plug API

For C55\_plug, the range of vector IDs is extended from 0-31 to 0-63. The IDs 32-63 correspond to level 2 interrupts 0-31 respectively. The c55.h file now includes definitions C55\_L2\_INT0 through C55\_L2\_INT31 which map to vector IDs 32-63.

### D.4.2 New APIs

The following APIs have been added to the C55 module for use with OMAP 2420. For details, see the topics for these APIs in the alphabetic reference in Chapter 2.

- ❑ C55\_disableInt. Disable an individual interrupt.
- ❑ C55\_enableInt. Enable an individual interrupt.
- ❑ C55\_I2AckInt. Explicitly acknowledge an L2 interrupt
- ❑ C55\_I2DisableMIR. Disable a mask of L2 interrupts
- ❑ C55\_I2EnableMIR. Enable a mask of L2 interrupts
- ❑ C55\_I2SetIntPriority. Set the priority of a L2 interrupt

## D.5 Building DSP/BIOS Applications for OMAP 2420

In order for the proper DSP/BIOS header files to be used during the build process, you must define the symbol "\_2420\_" at assembly time.

If you are building from the command line, add the following option to your assembler command line:

```
-d_2420_
```

If you are building with Code Composer Studio, follow these steps:

- 1) Open the application's CCStudio project.
- 2) Choose **Project->Build Options** to open the Build Options dialog.
- 3) Go to the Compiler tab and choose the Assembly category
- 4) Add **\_2420\_** to the "Pre-Define NAME (-ad)" field.
- 5) Click **OK**.

## D.6 Usage Examples

The following examples provide examples that use the HWI and C55 APIs related to the OMAP 2420.

### D.6.1 Installing and Enabling a Single Level 2 Interrupt

This C code example plugs and enables the 24xx Level 2 interrupt #1.

```
/*
 * ===== l2_example1.c =====
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void myIsr (Arg id)
{
    LOG_printf(&trace, "My l2 ISR %d", ArgToInt(id));
}

Void main ()
{
    HWI_Attrs attrs = HWI_ATTRS;

    // pass vector ID to myIsr
    attrs.arg = (Arg)C55_L2_INT1;

    // Plug Level 2 Interrupt #1 Vector
    HWI_dispatchPlug(C55_L2_INT1, (Fxn)myIsr, &attrs);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}
```

## D.6.2 Installing and Enabling Multiple Level 2 Interrupts

This C code example plugs and enables level 2 interrupts numbers 10, 11, 12, and 13 and sets their priority levels to 0, 1, 2, 3 respectively (0 = highest priority). The default interrupt nesting behavior (all other interrupts enabled while l2FiqFunc is called) is configured.

```

/*
 * ===== l2_example2.c =====
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void l2FiqFunc(Arg id)
{
    LOG_printf(&trace, "l2_fiq %d\n", ArgToInt(id)%32);
}

Void main()
{
    HWI_Attrs attrs;
    attrs = HWI_ATTRS;

    attrs.arg = (Arg)C55_L2_INT10;
    HWI_dispatchPlug( C55_L2_INT10, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT10, 0);

    attrs.arg = (Arg)C55_L2_INT11;
    HWI_dispatchPlug( C55_L2_INT11, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT11, 1);

    attrs.arg = (Arg)C55_L2_INT12;
    HWI_dispatchPlug( C55_L2_INT12, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT12, 2);

    attrs.arg = (Arg)C55_L2_INT13;
    HWI_dispatchPlug( C55_L2_INT13, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT13, 3);

    C55_l2EnableMIR(0x00003c00);
}

```

### D.6.3 Enabling an L2 Interrupt Using "interrupt" Keyword

This C code example plugs and enables OMAP 24xx level 2 interrupt number 1.

```
/*
 * ===== l2_example3.c =====
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

interrupt void myIsr ()
{
    // Acknowledge this level 2 interrupt to the L2IC
    C55_L2AckInt();

    // ...
    // Your code here
    // ...
}

Void main ()
{
    // Plug Level 2 Interrupt #1 Vector
    C55_plug(C55_L2_INT1, (Fxn)myIsr);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}
```



## D.6.4 Assembly Language ISR Using HWI\_enter, HWI\_exit

This assembly code example uses the MIR mask arguments.

```

;#
;# DSP/BIOS Level 2 interrupt example
;#

; Include files
.include log.h55
.include hwi.h55
.include c55.h55

.global _l2FiqFunc
.global _intCount
.ref _trace
.ref _reportInfo

_myIsr:
HWI_enter C55_ALL_AR_DR_REGS, C55_ALL_ACC_REGS,
C55_ALL_MISC1_REGS, C55_ALL_MISC2_REGS,
C55_ALL_MISC3_REGS,
0x0000,          ; ier0 interrupt mask unchanged
0x0000,          ; ier1 interrupt mask unchanged
0xffffffff      ; all level 2 interrupts masked

;
;           Your code here
;

HWI_exit C55_ALL_AR_DR_REGS, C55_ALL_ACC_REGS,
C55_ALL_MISC1_REGS, C55_ALL_MISC2_REGS,
C55_ALL_MISC3_REGS,
0x0000,          ; ier0 interrupt mask unchanged
0x0000,          ; ier1 interrupt mask unchanged
0xffffffff      ; all level 2 interrupts restored

```

## D.6.5 Statically Configuring a Level 2 Interrupt

This example plugs and enables Level 2 interrupt number 7. All other level 1 and level 2 interrupts are disabled by the DSP/BIOS dispatcher during the execution of "myIsr".

```
/*
 * ===== l2_example4.c =====
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void myIsr (Arg id)
{
    LOG_printf(&trace, "My L2 ISR %d", ArgToInt(id));
}

Void main ()
{
    // Enable Level 2 interrupt number 7
    C55_enableInt(C55_L2_INT7);
}

-----
                        TCONF script
-----
/* ===== l2_example4.tcf ===== */

bios.HWI_L2_INT7.useDispatcher = 1;
                                // use HWI dispatcher
bios.HWI_L2_INT7.fxn = prog.extern("myIsr");
                                // attach to "myIsr" C function
bios.HWI_L2_INT7.arg = 7;
                                // pass interrupt ID as argument
bios.HWI_L2_INT7.iMirMask = "all";
                                // mask all other L2 ints
bios.HWI_L2_INT7.interruptMask0 = "all";
                                // mask L1 ints 0-15
bios.HWI_L2_INT7.interruptMask1 = "all";
                                // mask L1 ints 16-31
```

# DSP/BIOS for 'C5505

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This appendix describes special DSP/BIOS features provided for use with the 'C5505 platform.

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## E.1 Overview

The CLK module supports the TMS320C5505 device's unique 32-bit timers, which share a common interrupt (HWI\_INT4), by allowing separate functions to be configured for each of the three timers.

In order for DSP/BIOS to use one of these timers to drive the CLK module and to allow applications to use the other two timers, several new CLK module configuration parameters and a new runtime API—`CLK_setTimerFunc()`—have been added to DSP/BIOS.

**Important:** DSP/BIOS configures only the timer selected for use by the CLK manager. You must fully configure any other timers you use. Additionally, timer functions you configure must acknowledge the timer's interrupt and clear the timer's interrupt pending status in the timer's "interrupt" register as well as its corresponding status in the "Timer Interrupt Aggregation Flag Register" at IO address 0x1c14.

## E.2 'C5505 and the CLK Module

A rudimentary interrupt dispatcher is invoked whenever any of the three 'C5505 timers generates an interrupt. The CLK interrupt dispatcher then determines which timers have interrupts pending and calls the function configured for each.

Timer interrupt functions configured for any of the three timers must have the following signature:

```
Void timerfunc(Arg arg);
```

These interrupt functions can be set either statically or dynamically.

### E.2.1 Static Configuration

The following CLK module properties are provided specifically for 'C5505 timer support:

- ❑ **TIMER0FUNC.** This property specifies the function to be executed when the timer 0 interrupt occurs. By default, timer 0 is used to drive the DSP/BIOS CLK, and so this timer cannot be configured to run a user function unless you change the CLK module's Timer Selection property to a different timer or disable the CLK manager. To configure this property in a configuration script, follow this example:

```
bios.CLK.TIMER0FUNC = prog.extern("timer0Fxn");
```

- ❑ **TIMER0ARG.** This property specifies the argument to be passed to the corresponding timer function. For example:

```
bios.CLK.TIMER0ARG = 1;
```

- ❑ **TIMER1FUNC.** This property specifies the function to be executed when the timer 1 interrupt occurs. To configure this property in a configuration script, follow this example:

```
bios.CLK.TIMER1FUNC = prog.extern("timer1Fxn");
```

- ❑ **TIMER1ARG.** This property specifies the argument to be passed to the corresponding timer function. For example:

```
bios.CLK.TIMER1ARG = 2;
```

- ❑ **TIMER2FUNC.** This property specifies the function to be executed when the timer 2 interrupt occurs. To configure this property in a configuration script, follow this example:

```
bios.CLK.TIMER2FUNC = prog.extern("timer2Fxn");
```

- ❑ **TIMER2ARG.** This property specifies the argument to be passed to the corresponding timer function. For example:

```
bios.CLK.TIMER2ARG = 4;
```

The DSP/BIOS Configuration Tool lets you choose one of the three timers in the Timer Selection field. This timer is used to drive the DSP/BIOS clock. You can configure user functions and arguments for the other two timers only.

DSP/BIOS automatically plugs the CLK interrupt dispatcher into HWI\_INT4 if *any* of the 3 timer functions are statically set to something other than FXN\_F\_nop. By default, the CLK manager's timer handler makes this happen without the user having to manually set any of the timer interrupt functions.

## E.2.2 Dynamic Configuration

To dynamically set a timer interrupt function, use the following new CLK API:

```
CLK_setTimerFunc(  Uns   timerId,  
                  Void   (*func)(Arg),  
                  Arg    arg);
```

The timerId is 0, 1, or 2 corresponding to the timer being used. By default, the DSP/BIOS CLK manager uses timer 0.

For example, the following statement dynamically sets timer 1's interrupt handler:

```
CLK_setTimerFunc(1, myTimer1Func, 4);
```

When timer 1's interrupt occurs, the CLK interrupt dispatcher calls the configured handler as follows:

```
myTimerFunc(4);
```

See page 2–56 for details.

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