

# xPC Target

**For Use with Real-Time Workshop<sup>®</sup>**

- Modeling
- Simulation
- Implementation

**Getting Started**

*Version 2*



## How to Contact The MathWorks:



www.mathworks.com      Web  
comp.soft-sys.matlab      Newsgroup



support@mathworks.com      Technical support  
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service@mathworks.com      Order status, license renewals, passcodes  
info@mathworks.com      Sales, pricing, and general information



508-647-7000      Phone



508-647-7001      Fax



The MathWorks, Inc.      Mail  
3 Apple Hill Drive  
Natick, MA 01760-2098

For contact information about worldwide offices, see the MathWorks Web site.

### *Getting Started with xPC Target*

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## Introduction

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# Introduction

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This chapter is an overview of the functions and features of xPC Target. An introduction to these features and the xPC Target software environment helps you develop a model for working with xPC Target. This chapter includes the following sections:

What Is xPC Target? (p. 1-2)	Solution for prototyping, testing, and deploying real-time systems using a host PC and a separate target PC
Features of xPC Target (p. 1-4)	Real-time kernel, real-time application, signal acquisition, and parameter tuning
Hardware Environment (p. 1-9)	Target PC types, host and target PC connection, and I/O driver support
Software Environment (p. 1-14)	Host and target PC communication, rapid prototyping process, and deployment process
User Interaction (p. 1-20)	xPC Target GUI, MATLAB command line, Simulink external mode, Web browser, custom GUI with Simulink and Dials & Gauges Blockset, custom GUI with xPC Target API, and custom GUI with xPC Target COM API

## What Is xPC Target?

xPC Target is a solution for prototyping, testing, and deploying real-time systems using standard PC hardware. It is an environment that uses a target PC, separate from a host PC, for running real-time applications.

In this environment you use your desktop computer as a host PC with MATLAB<sup>®</sup>, Simulink<sup>®</sup>, and Stateflow<sup>®</sup> (optional), to create a model using Simulink blocks and Stateflow charts. After creating your model, you can run simulations in nonreal time.

xPC Target lets you add I/O blocks to your model and then use the host PC with Real-Time Workshop<sup>®</sup>, Real-Time Workshop Embedded Coder (optional), Stateflow Coder (optional), and a C/C++ compiler to create executable code. The executable code is downloaded from the host PC to the target PC running the xPC Target real-time kernel. After downloading the executable code, you can run and test your target application in real time:

- **Hardware requirements** — The xPC Target software requires a host PC, target PC, and, for I/O, the target PC must also have I/O boards supported by xPC Target. However, the target PC can be a desktop PC, industrial PC, PC/104, PC/104+, or CompactPCI computer.
- **Software requirements** — The xPC Target software requires either a Microsoft Visual C/C++ compiler (Version 5.0, 6.0, or 7.0) or a Watcom C/C++ compiler (Version 10.6 or 11.0). In addition, xPC Target requires MATLAB, Simulink, and Real-Time Workshop.
- **xPC Target Embedded Option requirements** — The xPC Target Embedded Option is a separate product that requires an additional license from The MathWorks. With this additional license, you can deploy an unlimited number of real-time applications for stand-alone operation. This option allows you to
  - Boot the target PC from an alternate device other than a floppy disk drive, such as a hard disk drive or flash memory.
  - Create stand-alone applications for the target PC, independent from the host PC, that can boot from a floppy drive or an alternate device.



- Deploy stand-alone GUI applications running on the host PC to control, change parameters, and acquire signal data from a target application. This feature uses the xPC Target API with any programming environment, or the xPC Target COM API with any programming environment, such as Visual Basic, that can use COM objects. Without the xPC Target Embedded Option, you can create, but not deploy, stand-alone GUI applications running on a host PC that does not contain your licensed copy of xPC Target, to control, change parameters, and acquire signal data from a target application.
- **Documentation and help** — The xPC Target software ships with Getting Started documentation. This guide and the remaining documentation are available online through the MATLAB Help browser window, or as PDF files that you can view online or print.

## Expected Background

Users who read this book should be familiar with

- Using Simulink and Stateflow to create models as block diagrams, and simulating those models in Simulink
- The concepts and use of Real-Time Workshop to generate executable code

When using Real-Time Workshop and xPC Target, you do not need to program in C or other programming languages to create, test, and deploy real-time systems.

**If you are a new user** — Begin with Chapter 1, “Introduction.” This chapter gives you an overview of the xPC Target features and xPC Target environment. Next, read and try the examples in Chapter 3, “Basic Tutorial.”

**If you are an experienced user** — After you are familiar with using xPC Target, read or browse the following chapters in the xPC Target User’s Guide documentation: Chapter 6, “Software Environment and Demos,” and Chapter 2, “Targets and Scopes in the MATLAB Interface,” for more detailed information about the commands in xPC Target.

## Features of xPC Target

The xPC Target software environment includes many features to help you prototype, test, and deploy real-time systems. This section includes the following topics:

- “Real-Time Kernel” on page 1-4 — BIOS, BIOS-extension, kernel, and loader
- “Real-Time Application” on page 1-6 — Memory model and task execution time
- “Signal Acquisition” on page 1-7 — Signal monitoring, signal logging to the MATLAB workspace, and signal tracing on the host PC or target PC screen
- “Parameter Tuning” on page 1-8 — Interactive scripts and batch procedures

### Real-Time Kernel

xPC Target does not require DOS, Windows, Linux, or any another operating system on the target PC. Instead, you boot the target PC with a boot disk that includes the xPC Target kernel.

However, the xPC Target Embedded Option requires DOS and a DOS license at boot time. For more information, see the xPC Target User’s Guide documentation.

### Target Boot Disk

The boot disk eliminates the need to install software, modify existing software configurations, or access the hard disk on the target PC. This arrangement allows you to use the target PC for testing real-time applications, and then when you are finished with your tests, you can use the target PC again as a desktop computer. Software is not permanently installed on the target PC unless you deliberately install a stand-alone application on the hard disk or flash memory using the xPC Target Embedded Option.

## Target PC BIOS

Selecting a current BIOS allows you to customize settings for better control over the real-time behavior of the system. For example, you can suppress checking for a keyboard and switch off any power save features.

The xPC Target kernel runs only on a PC-compatible system, and a key component of every PC-compatible system is the BIOS. The BIOS is the only software component that is needed by the xPC Target kernel.

After the BIOS is loaded, it searches the target boot disk for a bootable image (executable). This bootable image includes a 16-bit part and a 32-bit part. The 16-bit part runs first because the CPU is still in real mode. It prepares the descriptor tables and, in addition to other things, switches the CPU to protected mode. Next, the 32-bit part runs. It prepares the target PC environment for running the kernel and finally starts the kernel.

After loading the kernel, the target PC does not make calls to the BIOS or DOS functions. The resources on the CPU motherboard (for example, interrupt controller, UART, and counters) are addressed entirely through I/O addresses.

## Real-Time Kernel

After the kernel starts running, it displays a welcome message with information about the host-target connection. The kernel activates the application loader and waits to download a target application from the host PC. The loader receives the code, copies the different code sections to their designated addresses, and sets the target application ready to start. You can now use xPC Target functions and other utilities to communicate with the target application.

It is important to note that after the CPU switches to protected mode (32-bit), none of the xPC Target components switches the CPU back to real mode (16-bit).

The generated real-time application and the real-time kernel are compiled as Windows NT applications with a flat memory model. This provides full 32-bit power without time-consuming 16-bit segment switching and DOS extenders.

## Target PC Heap

The initialization code of the target application reserves the remaining unused RAM as heap. The memory available for the heap is displayed on the left side of the target screen as **Memory**. By default, it is 4 MB less than the entire RAM installed (1 MB for the application; 3 MB for the kernel). Normally, the largest part of the heap is used by signal logging because logging acquires and stores data during the entire run.

You can define the amount of memory available for data logging in the **Configuration Parameters** dialog box. See “Entering the Real-Time Workshop Parameters” on page 3-40.

## Real-Time Application

Real-Time Workshop, Real-Time Workshop Embedded Coder, Stateflow Coder, xPC Target, and a C compiler create a real-time application (target application) from a Simulink and Stateflow model. Target applications created with Real-Time Workshop and xPC Target run in real time on a standard PC without using a Windows operating system.

The target application runs in real time on the target PC and has the following characteristics:

- **Memory model** — The target application is compiled as a Windows NT application with the flat memory model. This executable is then converted to an image suitable for xPC Target, and it provides full 32-bit power without time-consuming 16-bit segment switching and DOS extenders. It also does not rely on DOS or any other Microsoft operating system.
- **Task execution time**— The target application is capable of high-speed, real-time task execution. A small block diagram can run with a sample time as fast as 10  $\mu$ s (100 kHz). Model size, complexity, and target PC hardware affect maximum speed (minimal sample time) of execution.

For more information on creating a target application, see “xPC Target Application” on page 3-38.

## Signal Acquisition

The xPC Target real-time kernel stores signal data from the target application in RAM on the target PC. Alternatively, you can have the xPC Target real-time kernel store signal data in a file on the target PC. In either case, you can use this signal data to analyze and visualize signals. xPC Target supports the following types of signal acquisition:

- **Signal monitoring** — This is the process for acquiring signal data without time information. In this mode, you can get the current values of one or more signals. The data is not acquired in the real-time task but in the background task. The advantage of this process is that collecting data does not add any computational load to running the real-time application.

For example, if you have a LED gauge in a Simulink model on the host PC, you could use signal monitoring to display the status of the signal.

- **Signal logging** — This is the process of acquiring signal data while a target application is running, and then visualizing the collected data after the target application stops running. The data is collected in the real-time task and acquired samples are associated with a time stamp. After the run finishes or you manually stop the run, the host PC makes a request to upload data from the target PC. You can then visualize signals by plotting data on the host PC, or you can save data to a disk.
- **Signal tracing** — This is the process of acquiring and visualizing signal data while a target application is running. The data is collected in the real-time task and acquired samples are associated with a time stamp. It allows you to acquire signal data and visualize it on the target PC or to upload the signal data and visualize it on the host PC while the target application is running. The flexibility of this acquisition type is very similar to the behavior of a digital oscilloscope.

For information on the various ways to acquire signal data with xPC Target, see “User Interaction,” “Signal Monitoring with MATLAB,” “Signal Logging,” and “Signal Tracing” in Chapter 3 of the xPC Target User’s Guide documentation.

## Parameter Tuning

Most Simulink blocks have parameters (such as the amplitude and frequency of a sine wave) that you can change before or while your target application is running:

- **Interactive** — xPC Target supports interactive tuning of parameters while the target application is running in real time. The changes to parameters are immediately reflected in the signal outputs.
- **Scripts and batch procedures** — xPC Target also includes commands to change parameters during a run or between runs. By writing a script that incrementally changes a parameter and monitors a signal output and running it on the host PC, you can optimize the value of that parameter.

For information on the various ways to tune parameters with xPC Target, see “User Interaction” and “Parameter Tuning” in Chapter 3 of the xPC Target User’s Guide documentation.

## Hardware Environment

The hardware environment consists of a host computer, target computer, I/O boards in the target computer, and a serial or network connection between the host and target computers. Knowing the different types of computers and I/O supported by xPC Target will help you to set up a development environment that meets your needs. This section includes the following topics:

- “Host PC” on page 1-9 — Desktop PC or notebook PC
- “Target PC” on page 1-10 — Desktop PC, industrial PC, PC 104, or CompactPCI
- “Host-Target Connection” on page 1-11 — RS-232 serial or TCP/IP network
- “I/O Driver Support” on page 1-12 — Analog, digital, CAN, GPIB, RS-232, UDP, counters, timers, and signal conditioning

### Host PC

You can use any PC that runs a Microsoft Windows platform supported by The MathWorks as the host PC. It must also contain a 3.5 inch floppy disk drive, and a free serial port or an Ethernet adapter card.

The host PC can be one of the following:

- Desktop PC
- Notebook PC

For more details on the requirements of the host PC, see “Host PC” on page 2-7.

## Target PC

xPC Target supports one or more target PCs with one host. A target PC can be almost any PC with an Intel 386/486/Pentium or AMD K5/K6/Athlon processor as the target computer. It must also contain a 3.5 inch floppy disk drive, and a free serial port or an Ethernet adapter card. Using the xPC Target Embedded Option, you can transfer files from the 3.5 inch disk to a hard disk or flash memory.

A target PC can be one of the following:

- **Desktop PC** — This computer is booted from a special target boot disk created by xPC Target.

When you boot the target PC from the target boot disk, xPC Target uses the resources on the target PC (CPU, RAM, and serial port or network adapter) without changing the files already stored on the hard drive.

After you are done using your desktop computer as a target PC, you can reboot your computer without the target boot disk and resume normal use of your desktop computer.

- **Industrial PC** — This computer is booted from a special target boot disk, or, using the xPC Target Embedded Option, from a hard disk or flash memory. When using an industrial target PC, you can select PC104, PC104+, CompactPCI, or single-board computer (SBC) hardware.

You do not need any special target hardware. However, the target PC must be a fully PC-compatible system and contain a serial port or an Ethernet controller compatible with xPC Target.

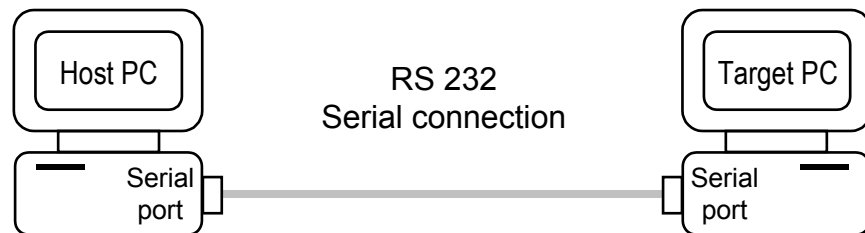
For more details on the requirements of the target PC, see “Target PC” on page 2-9.



## Host-Target Connection

xPC Target supports two connection and communication protocols between the host PC and the target PC: serial and network.

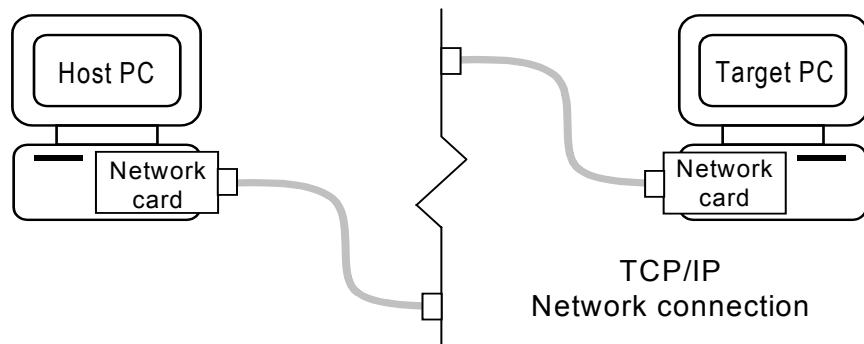
**Serial** — The host and target computers are connected directly with a serial cable using their RS-232 ports. This cable is wired as a **null modem** link that can be up to 5 meters long and with a transfer rate between 1200 and 115200 baud. A null modem cable is provided with the xPC Target software.



For detailed information on setting up the hardware and software for serial communication, see “Serial Communication” on page 2-20.

**Network** — The host and target computers are connected through a network. The network can be a LAN, the Internet, or a direct connection using a crossover Ethernet cable. Both the host and target computers are connected to the network with Ethernet adapter cards using the TCP/IP protocol for communication.

When using a network connection, the target PC can use the Ethernet adapter card provided with xPC Target or one of the supported cards. The data transfer rate can be 10 megabits/second or 100 megabits/second. For a list of supported cards, see “Hardware for Network Communication” on page 2-28.



For detailed information on setting up the hardware and software for network communication, see “Network Communication” on page 2-27.

## I/O Driver Support

xPC Target supports a wide range of I/O boards. The list of supported I/O boards includes ISA, PCI, PC/104, PC/104+, and CompactPCI hardware. The drivers are represented by Simulink blocks. Your interaction with the drivers is through these Simulink blocks and the parameter dialog boxes.

**I/O board library** — The I/O board library contains Simulink blocks for xPC Target. You drag and drop blocks from the I/O library and connect I/O drivers to your model the same way you would connect any standard Simulink block.

**I/O support** — The I/O device library supports over 150 standard boards. I/O boards plug into the target PC expansion bus, PC104 stack, or industrial PC chassis. There is also support for modules that plug into IP or PMC carrier boards. xPC Target supports the following I/O functions:

- **Analog input (A/D) and analog output (D/A)** — Connect sensors and actuators to your target application.
- **Digital input and output** — Connect to switches, on/off devices, and communicate information in parallel.
- **RS-232/422/485 support** — Use the COM1 or COM2 ports for serial communication with external devices. You can also access multiple RS-232, RS-422, and RS-485 serial ports using Quatech devices. See Chapter 2, “Serial Communications Support,” in the xPC Target I/O Reference documentation.

- **CAN support** — You can use CAN-AC2, CAN-AC2-PCI, and CAN-AC2-104 boards from Softing GmbH AG with xPC Target CAN drivers to interface with a CAN field bus network. This interface provides communication through a CAN network between target applications and remote sensors and actuators.

The xPC Target CAN drivers are compatible with CAN specifications 2.0A and 2.0B and use dynamic object mode. See Chapter 4, “CAN I/O Support,” and Chapter 5, “CAN I/O Support for FIFO,” in the xPC Target I/O Reference documentation.

- **GPIB support** — Special RS-232 drivers support communication with a GPIB control module from National Instruments to external devices with a GPIB connector. See Chapter 3, “GPIB I/O Support,” in the xPC Target I/O Reference documentation.
- **UDP support** — Communicate with another system using the standard UDP/IP network protocol. See Chapter 6, “UDP I/O Support,” in the xPC Target I/O Reference documentation.
- **Counter-Timers** — Use the counter-timer blocks for measuring pulse and frequency with modulation applications.
- **Watchdog** — Monitor an interrupt or memory location, and reset the computer if an application does not respond. See Chapter 8, “WDG-CSM,” and Chapter 32, “VSBC-6,” in the xPC Target I/O Reference documentation.
- **Incremental encoder** — Change motion into numerical information for determining position, direction of rotation, and velocity.
- **Shared memory** — Use shared memory blocks with multiprocessing applications.

For information on using specific I/O driver blocks and advanced I/O support, see the xPC Target I/O Reference documentation.

## Software Environment

The software environment is a place to design, build, and test a target application in nonreal time and real time. It also includes communication between the host and target computers. This section includes the following topics:

- “Host-Target Communication” on page 1-14 — Control the target application, upload signal data, and download parameter values.
- “Rapid Prototyping Process” on page 1-15 — Design and build a target application on a host PC and download the target application to a target PC. Run and test the target application with interactive tuning of parameters and acquisition of data.
- “xPC Target Embedded Option” on page 1-17 — Boot the kernel from a device other than the floppy disk drive, but download the target application from the host PC. Or boot the kernel/application from the floppy disk drive or another device, and run the target application completely separately from the host PC.

### Host-Target Communication

Whether using a serial connection (RS-232) or a network connection (TCP/IP), information is exchanged between the host PC and target PC. This information includes

- **Target application** — Download a target application from the host to the target computer.
- **Control** — Change properties and control the target application. This includes starting and stopping the target application, changing sample and stop times, and getting information about the performance of the target application and CPU.
- **Signal data** — Upload signal data from the host computer for analysis after the target application is finished running, or view signal data during the run.
- **Parameter values** — Download parameter values to the target computer between runs or during a run.

## Rapid Prototyping Process

Design and build a target application on a host PC, and then run and test the target application on a target PC. xPC Target functions include interactive control of the target application, acquisition of signal data, and tuning of parameters while running in real time.

The rapid prototyping process includes the following sequence of tasks:

- 1 Create a Simulink and Stateflow model** — You create block diagrams in Simulink using simple drag-and-drop operations, and then you enter values for the block parameters and select sample rates. If you use continuous-time components, you also need to select an integration algorithm.
- 2 Simulate the model in nonreal time** — Simulink uses a computed time vector to step the model. After the outputs are computed for a given time value, Simulink immediately repeats the computations for the next time value. This process is repeated until it reaches the stop time.

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**Note** Because this computed time vector is not connected to a hardware clock, the outputs are calculated in nonreal time as fast as your computer can run. The time to run a simulation can differ significantly from real time.

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- 3 Create an executable target application** — Real-Time Workshop, Stateflow Coder, xPC Target, and a C compiler create the target application that runs on the target PC. This real-time application uses the initial parameters from the Simulink model that were available at the time of code generation.
- 4 Execute the target application in real time** — The target PC is booted using an xPC Target boot disk that loads the xPC Target real-time kernel. After booting the target PC, you can build and download a real-time application.

xPC Target provides the software that makes use of real-time resources on the target PC hardware. Based on your selected sample rate, xPC Target uses interrupts to step the model at the proper rate. With each new interrupt, the target application computes all the block outputs from your model.

- 5 Acquire signals** — Acquire signal data using xPC Target scopes. xPC Target supports 10 scopes of each scope type (host, target, and file). You can create xPC Target scopes and acquire data from the target application by
- xPC Target — Use the xPC Target Remote Control Tool and Scope Manager windows to create scopes, and use the Simulink viewer to add signals.
  - MATLAB — Enter commands in the MATLAB Command Window.
  - Simulink — Add xPC Target Scope blocks to your Simulink model.

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**Note** xPC Target does not support normal Simulink Scope blocks in external mode. Instead, use xPC Target Scope blocks.

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- Target PC — Use commands in the target PC command window.
  - Web browser — Use the xPC Target Web browser interface.
  - Simulink GUI — Add Gauge blocks from the Dials & Gauges blockset to a Simulink user interface model with xPC Target From blocks.
- 6 Tune parameters** — You can tune parameters by
- xPC Target — Use the xPC Target Remote Control Tool and Simulink viewer to change parameters.
  - MATLAB — Enter commands in the MATLAB window.
  - Simulink — Use your Simulink model with external mode.
  - Target PC — Use commands in the target PC command window.
  - Web browser — Use the xPC Target Web browser interface.
  - Simulink GUI — Add Dial blocks from the Dials & Gauges blockset to a Simulink user interface model with xPC Target To blocks.

## xPC Target Embedded Option

Often, control system and digital signal processing applications are developed for use in production where a limited number of deployed systems is required. Whether you deploy one or one hundred systems, the xPC Target Embedded Option provides a convenient approach that allows you to implement your system on low-cost PC hardware.

When you have completed development and testing, you can use the target application as a real-time system that runs on a dedicated target PC without the need to connect to the host computer.

The xPC Target Embedded Option has two modes of operation. In each case, the target PC boots into DOS, starts the DOS program `xpcboot.com` from `autoexec.bat`, and then starts the kernel from `xpcboot.com`:

- “DOSLoader Mode” on page 1-18 — Run the kernel from a device other than the floppy disk, such as a hard disk or flash disk, and download the target application from the host PC.
- “StandAlone Mode” on page 1-19 — Run both the kernel and the target application from the floppy disk on the target PC, or optionally boot from a device other than the floppy disk. The target application runs completely independently from the host PC.

In contrast, when using the normal `BootFloppy` mode, you do not need DOS to load and run the xPC Target kernel.

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**Note** The xPC Target Embedded Option is a separate product that requires an additional license from The MathWorks. With this additional license you can deploy an unlimited number of real-time applications for stand-alone operation.

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For more information on the xPC Target Embedded Option, see the xPC Target User’s Guide documentation.

## DOSLoader Mode

DOSLoader mode allows you to boot your target computer from devices other than a 3.5 inch floppy disk. For example, the boot device can be a hard disk drive or flash memory. The target application is still downloaded from the host PC.

You can also use this mode to boot from a floppy disk, but there is no advantage to using this method over using a normal target boot disk. The advantage to using DOSLoader mode with the extra work to create a bootable DOS disk is that you can boot from an alternative device:

- 1** Select DOSLoader mode from the Configuration node in the **xPC Target Hierarchy** pane of the xPC Target Explorer tool.
- 2** Create a new target boot disk.
- 3** Copy DOS system files and utilities to the target boot disk.
- 4** In the `autoexec.bat` file, temporarily remove the line that executes `xpcboot.com`.
- 5** Boot the target PC with a bootable DOS disk from the floppy disk.
- 6** Copy files to the alternate boot device. In the `autoexec.bat` file, add the line that loads `xpcboot.com`.
- 7** Remove the target boot disk and reboot the target PC from the alternate boot device.
- 8** Build a target application and download it to the target PC.

For more information on the xPC Target Embedded Option, see Chapter 5, “Embedded Option,” in the xPC Target User’s Guide documentation.



## StandAlone Mode

StandAlone mode combines the target application with the kernel and boots them together on the target PC from a 3.5 inch floppy disk, hard disk drive, or flash memory. The host PC does not have to be connected to the target PC.

- 1** Select StandAlone mode from the Configuration node in the **xPC Target Hierarchy** pane of the xPC Target Explorer tool.
- 2** Build a kernel/target application.
- 3** Copy DOS system files, utilities, kernel/application files, and helper files to the boot disk.

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**Note** If you are booting from an alternate boot device, in the `autoexec.bat` file, remove the line that loads `xpcboot.com`.

---

- 4** Boot the target PC with a bootable DOS disk from the floppy disk.

---

**Note** If you are booting from an alternate boot device, copy files to the alternate boot device. In the `autoexec.bat` file, add the line that loads `xpcboot.com`. Remove the target boot disk and reboot the target PC from the alternate boot device.

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For more information on the xPC Target Embedded Option, see Chapter 5, “Embedded Option,” in the xPC Target User’s Guide documentation.

## User Interaction

The xPC Target environment has a modifiable interface to the target PC. You can use this interface from MATLAB or Simulink, and you can use other development environments to create stand-alone client applications independent of MATLAB. Because of this open environment, there are several ways to interact with your target application from the host and target PCs. This section includes the following topics:

- “xPC Target Explorer” on page 1-22 — Use the xPC Target Explorer to set xPC Target environment properties, create a boot disk for the target PC, download and control a target application, add and view xPC Target scopes, and change tunable parameters.
- “xPC Target Remote Control Tool” on page 1-23 — Use the xPC Target Remote Control Tool to set xPC Target environment properties (by calling the `xpcexplr` tool), control the target application, add xPC Target scopes, and change tunable parameters.
- “MATLAB Command-Line Interface” on page 1-24 — Enter xPC Target functions on the host PC.
- “Simulink External Mode Interface” on page 1-25 — Connect a Simulink block diagram to the target application using Simulink External Mode, and then use the block diagram for parameter tuning.
- “Simulink with xPC Target Scope Blocks” on page 1-26 — Add xPC Target Scope blocks to your model for signal tracing.
- “Target PC Command-Line Interface” on page 1-27 — Enter xPC Target functions on the target PC.
- “Web Browser Interface” on page 1-27 — Use Microsoft Internet Explorer or Netscape Navigator to connect to the target PC from any computer on the network with the target PC.
- “Custom GUI with Simulink, Dials, and Gauges” on page 1-28 — Create a model with the Dials & Gauges Blockset and xPC Target To and From blocks. This user interface (UI) model runs in Simulink on the host PC.
- “Custom GUI with xPC Target API” on page 1-28 — Create a client application that interfaces with a target application using any development environment that can call functions from a DLL.

- “Custom GUI with xPC Target COM API” on page 1-29 — Create a client application that interfaces with a target application using Visual Basic or any development environment that can incorporate COM objects.

The following table compares the interfaces supported by xPC Target.

<b>Interface</b>	<b>Environment properties</b>	<b>Control</b>	<b>Signal Acquisition</b>	<b>Parameter Tuning</b>
xPC Target Explorer	X	X	X	X
xPC Target Remote Control Tool	X	X	X	X
MATLAB Command-Line Interface	X	X	X	X
Simulink External Mode Interface		X		X
Simulink with xPC Target Scope Blocks			X	
Target PC Command-Line Interface		X	X	X
Web Browser Interface		X	X	X
Custom GUI with Simulink, Dials, and Gauges			X	X
Custom GUI with xPC Target API		X	X	X
Custom GUI with xPC Target COM API		X	X	X

## xPC Target Explorer

xPC Target offers a graphical user interface (GUI) for configuring the host and target PCs and interacting with a target application. To open the xPC Target GUI, in the MATLAB Command Window, type `xpcexplr`.

The xPC Target Explorer is an all-in-one user interface that includes the following functionality. It includes the functionality of both the xPC Setup (`xpcsetup`) and xPC Target Remote Control (`xpcrctool`) tools.

- **Environment** — Use the xPC Target Explorer Configuration node to change properties in the xPC Target environment. Properties include communication between the host and target computers, type and location of your C compiler, and target PC properties.

For more information on environment properties, see “Serial Communication” and “Network Communication” in Chapter 2, and the function `getxpcenv` in the xPC Target User’s Guide documentation.

- **Control** — Use the xPC Target Explorer to display a Simulink model and build and download that model. After the associated target application is downloaded to the target PC, you can use xPC Target Explorer to run it. Use xPC Target Explorer to change start and sample times without regenerating code, and get statistical performance information during or after the last run.

For more information, see Chapter 4, “xPC Target Explorer” in the xPC Target User’s Guide documentation.

- **Signal acquisition** — Use the xPC Target Explorer Model Hierarchy node to interactively add scopes of type host, target, or file, and add or remove signals. You can also set the triggering mode of a scope. A scope created on the target PC acquires data from the target application and stores the data for display on the host PC or target PC:
  - For scopes of type host — The xPC Target Explorer periodically uploads data packets and displays them in the xPC Target Host Scope Viewer.
  - For scopes of type target — The scope displays signal traces on the target PC screen. Because xPC Target uses highly optimized graphic routines, signal tracing has the same fast display and update rates that you normally observe when using a digital oscilloscope.

- For scopes of type file — The scopes stores signal data to a file in the target PC file system. You can copy the contents of the file to a host PC to plot or otherwise inspect the data.

For more information on using scopes with the xPC Target Explorer, see Chapter 4, “xPC Target Explorer” in the xPC Target User’s Guide documentation.

- **Parameter tuning** — Use the xPC Target Explorer Model Hierarchy node to interactively change tunable parameters in your target application.

For more information, see Chapter 4, “xPC Target Explorer” in the xPC Target User’s Guide documentation.

## xPC Target Remote Control Tool

xPC Target offers a graphical user interface (GUI) for interacting with a target application. This GUI is built using xPC Target functions and MATLAB Handle Graphics®. To open the xPC Target GUI, in the MATLAB Command Window, type `xpcrcctool`.

The xPC Target Remote Control Tool includes the following functions:

- **Environment** — Use the xPC Target Explorer window to change properties in the xPC Target environment. Properties include communication between the host and target computers, type and location of your C compiler, and target PC properties.

For more information on environment properties, see “Serial Communication” and “Network Communication” in Chapter 2, and the function `getxpcenv` in the xPC Target User’s Guide documentation.

- **Control** — Build, download, and run a target application. Change start and sample times without regenerating code, and get statistical performance information during or after the last run.
- **Signal acquisition** — Use the xPC Target Simulink Viewer to interactively add scopes of type host, target, or file, and add or remove signals. Use the xPC Target Scope Manager to set the triggering mode of a scope. A scope created on the target PC acquires data from the target application and stores the data for display on the host PC or target PC:
  - For scopes of type host — The Host Scope Manager periodically uploads data packets and displays them in a MATLAB figure.

- For scopes of type target — The scope displays signal traces on the target PC screen. Because xPC Target uses highly optimized graphic routines, signal tracing has the same fast display and update rates that you normally observe when using a digital oscilloscope.
- For scopes of type file — The scopes stores signal data to a file in the target PC file system. You can copy the contents of the file to a host PC to plot or otherwise inspect the data.
- **Parameter tuning** — Use the xPC Target Simulink Viewer to interactively change tunable parameters in your target application.

## **MATLAB Command-Line Interface**

You can interact with the xPC Target environment through the MATLAB command-line interface. Enter xPC Target functions in the MATLAB window on the host PC. You can also write your own M-file scripts that use xPC Target functions for batch processing.

xPC Target has more than 90 MATLAB functions for controlling the target application from the host computer. These functions define, at the most basic level, what you can do with the xPC Target environment.

The GUIs provided with xPC Target are for completing the most common tasks. They use the xPC Target functions but do not extend their functionality. The command-line interface provides an interactive environment that you can extend.

The MATLAB command-line interface includes the following functions:

- **Environment** — Create a boot disk and directly change the environment properties without using a graphical interface.  
For more information on environment properties, see “Creating a Target Boot Disk with Command-Line Interface”, and Chapter 6, “Software Environment and Demos,” in the xPC Target User’s Guide documentation.
- **Control** — Reboot the target PC, download a target application, start and stop target applications, and change start and sample times without regenerating code. Get statistical performance information during or after

the last run. Add/remove scopes, add/remove signals to scopes, and define triggers for scope display.

For more information, see “Control with MATLAB Commands” and Chapter 6, “Software Environment and Demos,” in the xPC Target User’s Guide documentation.

- **Signal acquisition** — Trace signals for viewing while the target application is running and monitor signal values without time information. Transfer logged signal data to the MATLAB workspace by uploading from the target PC to the host PC between runs. For stand-alone target PCs, if you write signal data to a file, use the `ftp` utility to transfer that file to a remote PC. For more information, see “Signal Monitoring with MATLAB,” “Signal Tracing with MATLAB,” and “Signal Logging with MATLAB” in Chapter 3, and Chapter 2, “Targets and Scopes in the MATLAB Interface,” in the xPC Target User’s Guide documentation.
- **Parameter tuning** — Change parameters while the target application is running, and use xPC Target functions to change parameters in between runs.

For more information, see “Parameter Tuning with MATLAB” in Chapter 3 and Chapter 2, “Targets and Scopes in the MATLAB Interface,” in the xPC Target User’s Guide documentation.

## Simulink External Mode Interface

Use Simulink in external mode to connect your Simulink block diagram to your target application. The block diagram becomes a graphical user interface to the target application running in real time. By changing parameters in the Simulink blocks, you also change parameters in the target application.

The Simulink external mode interface includes the following functions:

- **Control** — Control is limited to connecting the Simulink block diagram to the target application, and starting and stopping the target application. For more information, see “Control with Simulink External Mode” on page 3-56.
- **Parameter tuning** — Select external mode, and change parameters in the target application by changing parameters in the **Block Parameters** dialog boxes. Once you change a value, the new value is immediately downloaded

to the target PC and replaces the existing parameter while the target application continues to run.

For more information, see “Parameter Tuning with Simulink External Mode” in Chapter 3 of the xPC Target User’s Guide documentation.

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**Note** xPC Target does not support data acquisition through Simulink external mode. Instead, use xPC Target Scope blocks for signal acquisition. See “Simulink with xPC Target Scope Blocks” on page 1-26.

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## **Simulink with xPC Target Scope Blocks**

An alternative to interactively adding scopes to the target PC is to add xPC Target Scope blocks to your Simulink model. After the download process, these blocks create scopes on the target PC during initialization of the target application. You can choose to display data on either the host PC or target PC. You can also choose to save signal data to a file in the target PC file system and transfer that file to another PC.

**Signal acquisition** — Add scopes to the target PC by adding xPC Target Scope blocks to your Simulink model. In the **Block Parameters** dialog box, select the scope mode and set the trigger.

For more information, see “Adding an xPC Target Scope Block” on page 3-15, “Entering Parameters for an xPC Target Scope Block” on page 3-19, “Entering Parameters for an xPC Target Scope of Type File” on page 3-29, and “Signal Tracing with xPC Target Scope Blocks” in Chapter 3 of the xPC Target User’s Guide documentation.



## Target PC Command-Line Interface

You can interact with the xPC Target environment through the target PC command window. Enter commands in the command line on the target PC. This interface is useful with stand-alone applications that are not connected to the host PC.

The target PC command-line interface includes the following functions:

- **Control**— Start and stop the target application, and change the stop time and sample time.  
For more information, see Chapter 7, “Using the Target PC Command-Line Interface,” in the xPC Target User’s Guide documentation.
- **Signal acquisition** — Acquiring signal data is limited to viewing signal traces and signal monitoring on the target PC screen.
- **Parameter tuning** — You can only change scalar parameters in your model.

## Web Browser Interface

If the target PC is connected to a network (TCP/IP), you can use a Web browser to interact with the target application from any computer connected to the network. If the target PC is connected to the host PC with an RS-232 cable, and is using the TCP/IP to RS-232 gateway, you can use a Web browser on the host PC.

The Web browser interface includes the following functions:

- **Control** — Start and stop the target application, and change the stop time and sample time.  
For more information, see Chapter 10, “xPC Target Web Browser Interface,” in the xPC Target User’s Guide documentation.
- **Signal acquisition** — Signal tracing is limited to viewing a snapshot of a screen captured from the target PC screen. Add scopes of type target, add or remove signals, and set triggering modes. You can also monitor signal values.  
For more information, see “Signal Logging with a Web Browser” in Chapter 3 of the xPC Target User’s Guide documentation.

- **Parameter tuning** — Change parameters in an HTML form, and then submit that form to make the changes in your target application.

For more information, see “Parameter Tuning with a Web Browser” in Chapter 3 of the xPC Target User’s Guide documentation.

## **Custom GUI with Simulink, Dials, and Gauges**

If you have a license for the Dials & Gauges Blockset, you can use dials, gauges, and xPC Target interface blocks to create a user interface (UI) model in Simulink. This Simulink model runs in normal mode and in nonreal time. The xPC Target interface blocks connect this Simulink model to the target application, which runs in real time.

The Dials & Gauges Blockset interface includes the following functions:

- **Signal acquisition** — Use Gauge blocks to display signal data.
- **Parameter tuning** — Use Dial blocks to change model parameters.

For more information see the xPC Target User’s Guide documentation.

## **Custom GUI with xPC Target API**

Create a GUI application interface to a target application using any development environment that can link in a DLL.

Use the GUI application to control the application, tune parameters, and acquire signal data from a target application. The custom GUI runs on the host PC and communicates with the target application on the target PC using RS-232 or TCP/IP communication. A GUI application can be a console or Windows application using ActiveX components.

For more information, see the xPC Target API documentation.

## **Custom GUI with xPC Target COM API**

Create a GUI application that interfaces with a target application using Visual Basic or any development environment that can incorporate COM objects. These COM objects connect graphic elements to parameters for parameter tuning, and they connect signals for acquiring data from your target application. To create a custom GUI application connected to an xPC Target application, use the following process:

- 1** Create a Simulink model.
- 2** Optionally, tag parameters and signals in the Simulink model.
- 3** Build the target application.
- 4** If you tag parameters and signals, build the model-specific COM library.
- 5** Create a GUI application that references the COM library.

For more information, see the xPC Target API User's and Reference documentation.



# Installation and Configuration

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The software environment for xPC target uses two separate computers. Because of this complexity, installation and configuration are more involved. This chapter includes the following sections:

Required Products (p. 2-2)	Read about products from The MathWorks and third-party products that you need to use with xPC Target
Related Products (p. 2-6)	Read about products from The MathWorks that allow you to use state logic in your models and animate signal data
System Requirements (p. 2-7)	Select a host PC and target PC
Installation on the Host PC (p. 2-12)	Get a valid license for xPC Target, and a separate license for the xPC Target Embedded Option. Install the xPC Target software by downloading it from the Web.
Serial Communication (p. 2-20)	Select RS-232 communication for an easy and inexpensive installation
Network Communication (p. 2-27)	Select TCP/IP communication for faster data transfer rates and longer connections
Target Boot Disk (p. 2-40)	Boot the xPC Target kernel on the target PC and establish a connection with the host PC
Testing and Troubleshooting the Installation (p. 2-45)	Test the installation

This chapter describes xPC Target interactions using a number of interfaces, including xPC Target Explorer. For additional information on using xPC Target Explorer, see Chapter 4, “xPC Target Explorer” in the xPC Target User’s Guide documentation.

### Required Products

xPC Target is a PC-compatible product that you install on a host computer running a Microsoft Windows operating system. xPC Target requires the following products from The MathWorks:

- “MATLAB” — Control and interact with the xPC Target software environment and target application using a command-line interface.
- “Simulink” — Model dynamic physical systems and controllers using block diagrams.
- “Real-Time Workshop” — Convert Simulink blocks and Stateflow charts into C code.
- “C Compiler” — Use a third-party C compiler and Real-Time Workshop to build a target application.
- “xPC Target Embedded Option” — Deploy stand-alone target applications and custom GUI applications that communicate with the target application. Note that you can create custom GUI applications without xPC Target Embedded Option.

### MATLAB

MATLAB provides a command-line interface for xPC Target.

With xPC Target, you have full control of the target computer and target application using xPC Target functions and the command-line interface or M-file scripts. You use the xPC Target functions for

- **Real-time application control** — Download, start, and stop the target application.
- **Signal acquisition and analysis** — Save signal data while the target application is running and analyze the data after the application has completed running, or display signal data while the target application is running in real time.
- **Parameter tuning** — Change parameters while the target application is running in real time.

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**Note** Version 2.6 of xPC Target requires MATLAB Version 7.0.

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- **MATLAB documentation** — For information on using MATLAB, see the MATLAB Getting Started documentation. It explains how to work with data and how to use functions. For a reference describing the functions supplied with MATLAB, see the online MATLAB Function Reference.

## Simulink

Simulink provides an environment where you model your dynamic physical system and controller as a block diagram. You create the block diagram by using a mouse to connect blocks and a keyboard to edit block parameters.

You can use xPC Target with most Simulink blocks, including discrete-time and continuous-time systems. When you use a continuous-time system and generate code with Real-Time Workshop, you must use a fixed-step integration algorithm.

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**Note** C code S-functions are supported by Real-Time Workshop. However, M-code S-functions are not supported.

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**xPC Target I/O driver blocks** — With xPC Target, you can replace the model of your physical system with I/O driver blocks connected to the actual physical system, or you can replace the model of your controller with the actual controller. The xPC Target I/O library supports more than 400 driver blocks. As additional drivers become available, you can download updates from the MathWorks Web site at

<http://www.mathworks.com/support/product/XP/productnews/productnews.html>

The I/O device drivers are written as Simulink C code S-functions.

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**Note** Version 2.6 of xPC Target requires Simulink Version 6.0.

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**Simulink documentation** — For information on using Simulink, see the Using Simulink documentation. It explains how to connect blocks to build models and change block parameters. It also provides a reference that describes each block in the standard Simulink library.

### Real-Time Workshop

Real-Time Workshop provides the utilities to convert your Simulink models into C code and then, with a third-party C/C++ compiler, compile the code into a real-time executable.

Features of Real-Time Workshop include support for multirate systems, as well as loop-rolling and S-function inlining, which allow you to optimize your code for size and efficiency. With xPC Target, you can build and download your target application to the target computer using the `build` command in Real-Time Workshop.

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**Note** Version 2.6 of xPC Target requires Real-Time Workshop Version 6.0.

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**Real-Time Workshop documentation** — For information on code generation, see the Real-Time Workshop documentation.

### C Compiler

The C compiler creates executable code from the C code generated from Real-Time Workshop and the C code S-functions you create. xPC Target uses this executable code to create an executable image (target application) that runs with the xPC Target kernel on the target computer.

In addition to the products from The MathWorks, you need to install a C compiler. Real-Time Workshop and xPC Target support the following C compilers:

- **Microsoft Visual C/C++** — Version 2.6 of xPC Target requires Microsoft Visual Studio C/C++ Version 5.0, 6.0, or 7.0. For optimal performance, use the professional versions of these tools in your environment. If you are going to write stand-alone GUI applications with the C or COM API, you can use Visual C/C++ to build your target application. To deploy a stand-alone GUI application that you create with the C or COM API, you need the xPC Target Embedded Option. Without the xPC Target Embedded Option, you can write, but not deploy, stand-alone GUI applications running on the host PC to control, change parameters, and acquire signal data from a target application.



- **Watcom C/C++** — Version 2.6 of xPC Target requires Watcom C/C++ Version 10.6 or 11.0. xPC Target does not support the Open Watcom C/C++ compiler.

## **xPC Target Embedded Option**

You do not need this product for rapid prototyping, but with this additional license, you can

- Boot the target PC from an alternate device other than a floppy disk drive such as a hard disk drive or flash memory.
- Deploy a stand-alone GUI application that you create with the C or COM API. Without the xPC Target Embedded Option, you can create, but not deploy, stand-alone GUI applications running on the host PC to control, change parameters, and acquire signal data from a target application.

The xPC Target Embedded Option is a separate product that requires an additional license from The MathWorks. Information about the xPC Target Embedded Option is included with the xPC Target documentation.

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**Note** Version 2.6 of xPC Target requires xPC Target Embedded Option Version 2.5 from Release 14.

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### Related Products

The MathWorks provides several products that are relevant to the kinds of tasks you can perform with xPC Target.

For more information about any of these products, see either

- The online documentation for that product
- The MathWorks Web site, at <http://www.mathworks.com>; see the “products” section

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**Note** The products listed below all include functions that extend the capabilities of MATLAB and Simulink.

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Product	Description
Dials & Gauges Blockset	Monitor signals and control simulation parameters with graphical instruments
Real-Time Workshop Embedded Coder	Generate production code for embedded systems
Signal Processing Blockset	Design and simulate signal processing systems
SimMechanics	Model and simulate mechanical systems
Stateflow	Design and simulate event-driven systems
Stateflow Coder	Generate C code from Stateflow charts
Virtual Reality Toolbox	Create and manipulate virtual reality scenes from within MATLAB and Simulink

## System Requirements

The hardware and software requirements are different for the host and target computers. This section includes the following topics:

- “Host PC” on page 2-7 — Desktop or notebook PC
- “Target PC” on page 2-9 — Desktop, industrial PC, PC/104, PC/104+, or CompactPCI

Note that the BIOS settings of a PC system can affect how the PC works with xPC Target. If you experience problems using xPC Target with the target or host PC, you should check the system BIOS settings. These settings are beyond the control of xPC Target. Refer to “xPC Target and the Target PC BIOS” in Chapter 13 of the xPC Target User’s Guide documentation for guidelines on BIOS settings.

### Host PC

The host PC is usually your desktop computer where you install MATLAB, Simulink, Stateflow, Stateflow Coder, Real-Time Workshop, xPC Target, and xPC Target Embedded Option. A notebook computer is also a viable host PC.

### Software Requirements for the Host PC

The following table lists the minimum software xPC Target requires on your host PC. For a list of optional software products related to xPC Target, see <http://www.mathworks.com/products/xpctarget/related.jsp>.

<b>Software</b>	<b>Description</b>
Operating system	Microsoft Windows platform supported by The MathWorks
MATLAB	MATLAB Version 7.0
Simulink	Simulink Version 6.0
Real-Time Workshop	Real-Time Workshop Version 6.0
C language compiler	Microsoft Visual C/C++ Professional Edition Versions 5.0, 6.0, or 7.0 Watcom C/C++ Versions 10.6 or 11.0
xPC Target	xPC Target Version 2.6

## Hardware Requirements for the Host PC

The following table lists the minimum resources xPC Target requires on the host PC.

Hardware	Description
Communication	One free serial port (COM1 or COM2) with a 9-pin or 25-pin D-sub connector, or an Ethernet card connected to a network
CPU	Pentium, Athlon, or later
Peripherals	Hard disk drive with 60 MB of free space One 3.5 inch floppy disk drive CD-ROM drive
RAM	128 MB or more

## Target PC

The target PC has to be a PC-compatible system. You can use a second desktop computer as the target PC, but you can also use an industrial system like a PC/104 or CompactPCI as the target computer.

## Software Requirements for the Target PC

The following table lists the minimum software xPC Target requires on your target PC system.

Software	Description
Operating system	None. The xPC Target kernel has no effect on any operating system installed on the target PC.
BIOS	PC compatible

### Hardware Requirements for the Target PC

The following table lists the minimum resources xPC Target requires on the target PC system.

Hardware	Description
Chip set	PC compatible with UART, programmable interrupt controller, keyboard controller, and counter
Communication	One free serial port (COM1 or COM2) with a 9-pin or 25-pin D-sub connector, or an Ethernet card connected to a network. The xPC Target software includes a serial null modem cable and an Ethernet card for the target PC.
CPU	Intel 386/486/ Pentium, or AMD K5/K6/Athlon with or without a floating-point processor or unit, or later, CPU.
Keyboard and mouse	Needed to control the target PC when you create stand-alone applications  Note that if a keyboard is not connected, the BIOS might display an error message (keyboard failure). With a current BIOS, you can use the BIOS setup to skip the keyboard test.
Monitor	The MathWorks recommends using a monitor, but it is not necessary. You can get all the target information using xPC Target functions on the host PC.
Peripheral	One 3.5 inch floppy disk drive. A hard disk drive is not required.  Note that if you install the xPC Target Embedded Option, you can copy files to a hard disk or flash memory and boot from that device.
RAM	8 MB or more

**Random Access Memory (RAM)** — xPC Target works with PC-compatible computers that use inexpensive dynamic RAM, unlike many non-PC-compatible target computers that use expensive static RAM. You can acquire several megabytes of data during a run depending on how much memory you install in the target PC.

**PC-compatible target computers** — xPC Target supports the following PC-compatible hardware (form factors):

- PC ISA
- PC PCI
- PC/104 and PC/104+
- CompactPCI

**I/O boards** — You can install inexpensive I/O boards in the PCI or ISA slots of the target PC. These boards provide a direct interface to the sensors, actuators, or other devices for real-time control or signal processing applications.

For a list of I/O functions supported by xPC Target, see “I/O Driver Support” on page 1-12.

# Installation on the Host PC

You install the xPC Target software entirely on the host PC. Installing software on the target PC is not necessary. The xPC Target software is distributed as a file you download from the Web. This section includes the following topics:

- “Getting or Updating Your License” on page 2-12 — Valid License File or Personal License Password (PLP)
- “Web Download Installation” on page 2-13 — xPC Target Version 2.6 as a single file with the MathWorks installer from the Web
- “Files on the Host PC Computer” on page 2-15 — Directories that contain general xPC Target files
- “Setting Your Initial Working Directory” on page 2-15 — MATLAB working directory outside the MATLAB root directory
- “Running MATLAB Remotely” on page 2-16 — Active X control registration if you are running MATLAB remotely (accessing MATLAB over the network)
- “Configuring the xPC Target Host PC” on page 2-17 — Host PC configuration through xPC Target Explorer

## Getting or Updating Your License

Before you install xPC Target or the xPC Target Embedded Option, you must have a valid License File or Personal License Password (PLP). The License File or Personal License Password identifies the products you purchased from The MathWorks and are permitted to install and use.

When you purchase a product, The MathWorks sends you a License File or Personal License Password (PLP) in an e-mail message. If you have not received a PLP number, contact The MathWorks.

**Internet**      <http://www.mathworks.com/accesslogin>

Log in to Access Login using your e-mail address and password. Go to the My Licenses panel to determine your PLP number.

**E-mail**      <mailto:service@mathworks.com>. Include your license number.



**Telephone** 508-647-7000. Ask for Customer Service.

**Fax** 508-647-7001. Include your license number.

The xPC Target family of software includes options that you can purchase and add later to the xPC Target environment.

**xPC Target Embedded Option** — With the xPC Target Embedded Option, you can boot the target PC from a device other than a floppy disk and deploy stand-alone target applications separate from the host PC.

## Web Download Installation

xPC Target Version 2.6 is distributed as a single file with the MathWorks installer from the Web. The remaining required software is distributed on the Mathworks Release 14 CD with the general installation program.

After you get a valid Personal License Password (PLP), you can install the xPC Target software (see “Getting or Updating Your License” on page 2-12):

- 1 In a Web browser window, enter the following address:

`http://www.mathworks.com/`

- 2 From the list on the right side of the page, select **Downloads**.

- 3 Under **Access Login Users**, select **download products**.

The **Access Login** page appears.

- 4 Enter your e-mail address and password.

- 5 Click the **Log In** button.

The **downloads** page appears.

- 6 Select the Release 14 option, the **Windows** check box, and then click the **Continue** button. From the **Select Your Products** list, select the **xPC Target** check box, and then click the **Continue** button.

- 7 On the next Web page, download all the required files to a temporary directory.

Your browser downloads the files `Installer.exe` and `xpc.cab` to your computer.

- 8 Double-click the file `Installer.exe`.

The install program copies extracted files to a temporary directory and starts the MATLAB installation program.

- 9 Follow the instructions on each dialog box, and from the product list, select the **xPC Target** check box.

After MATLAB finishes the installation, the install program deletes all the files from the temporary directory.

The xPC Target installation is now complete.

Your next task is to set up the xPC Target environment for either serial or network communication. See “Serial Communication” on page 2-20 or “Network Communication” on page 2-27.

## Files on the Host PC Computer

When using xPC Target, you might find it helpful to know where files are located:

- **MATLAB working directory** — Simulink models (`model.mdl`), xPC Target applications (`model.dlm`)

Select a working directory outside the MATLAB root. See “Setting Your Initial Working Directory” on page 2-15.

- **Real-Time Workshop Build directory** — The Real-Time Workshop C code files (`model.c`, `model.h`) are in a subdirectory called `modelname_xpc_rtw`.

xPC Target uses the directories and files located in

`C:\MATLABROOT\Toolbox\rtw\targets\xpc:`

- **target** — Files and functions related to the xPC Target kernel and build process
- **xpc** — Host PC functions related to all of xPC Target, methods for target objects, and methods for scope objects
- **xpcdemos** — Simulink models and M-file demos

## Setting Your Initial Working Directory

You should set your MATLAB working directory outside the MATLAB root directory. The default MATLAB root directory is `c:\matlab`.

If your MATLAB working directory is below or inside the MATLAB root, files created by Simulink and Real-Time Workshop are mixed with the MATLAB directories. This mixing of files could cause file management problems.

### From the Desktop Icon

Your initial working directory is specified in the shortcut file you use to start MATLAB. To change this initial directory, use the following procedure:

- 1 Right-click the MATLAB desktop icon or, from the program menu, right-click the MATLAB shortcut.
- 2 Click **Properties**. In the **Start in** text box, enter the directory path you want MATLAB to use initially. Make sure you choose a directory outside the MATLAB root directory.
- 3 Click **OK**, and then start MATLAB. To check your working directory, in the MATLAB Command Window, type

```
pwd
```

### From Within MATLAB

To temporarily set your MATLAB working directory, use the following procedure:

- 1 In the MATLAB window, type

```
cd c:\<MATLAB working directory>
```

- 2 To check your working directory, type

```
pwd or cd
```

To permanently set your working directory, see “From the Desktop Icon” on page 2-16.

### Running MATLAB Remotely

If you are running MATLAB remotely (accessing MATLAB over the network), register Active X controls before you start xPC Target Explorer.

- 1 In the MATLAB Command Window, type

```
xpc_register_ocx
```

This function registers the Active X controllers that xPC Target Explorer requires.

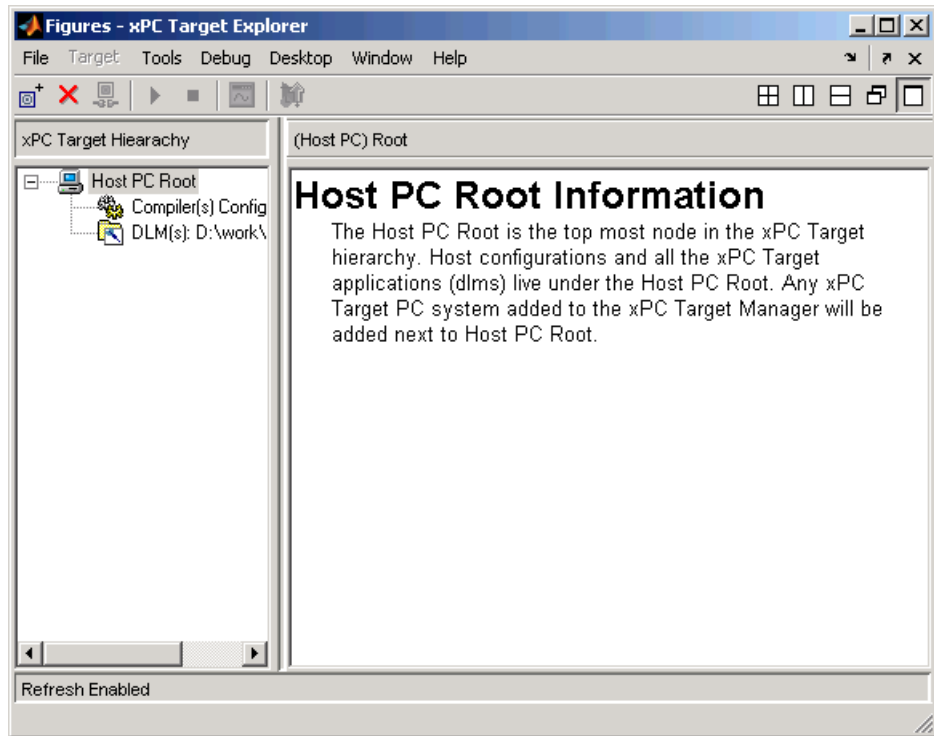
- 2** Type  
    `rehash toolbox`
- 3** Close xPC Target Explorer.
- 4** Close MATLAB.
- 5** Restart MATLAB.
- 6** Restart xPC Target Explorer.

You are now ready to start xPC Target Explorer.

## **Configuring the xPC Target Host PC**

Configure the host PC for your compiler.

- 1** If xPC Target Explorer is not already open, in the MATLAB Command Window, type  
    `xpcexplr`  
  
xPC Target Explorer appears.



- 2 In the **xPC Target Explorer** window, select the **Compiler(s) Configuration** node.  
  
In the right pane, the compiler parameters appear.
- 3 At the **Select C Compiler** drop-down list, select the compiler you have installed on the host PC. The examples in this chapter use **VisualC**.
- 4 Enter the path (or browse) to the compiler for **Compiler Path**. For example,  
`C:\Program Files\Microsoft Visual Studio`

Host PC Root Host Compiler Configuration

Select C compiler:

Compiler Path:

# Serial Communication

Before you can create and run a target application, you need to set up the connection between your host and target computers. You can use either serial or network communication. This section includes the following topics:

- “Hardware for Serial Communication” on page 2-20 — Use a null modem cable to connect the host PC to the target PC.
- “Environment Properties for Serial Communication” on page 2-21 — Enter information about the C/C++ compiler you installed on the host PC and the COM port you connected to the null modem cable.

For network communication, see “Network Communication” on page 2-27.

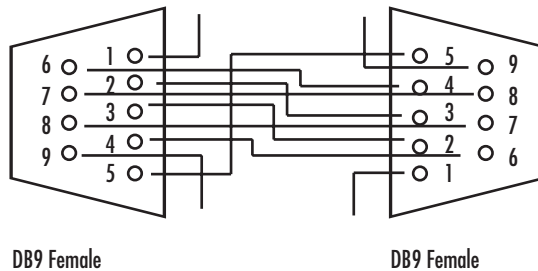
## Hardware for Serial Communication

Before you install the xPC Target software and configure it for serial communication, you must install the following hardware:

- **Null modem cable** — Connect the host and target computers with the null modem cable supplied by The MathWorks with the xPC Target software. You can use either the COM1 or COM2 port.
- **I/O boards** — If you use I/O boards on the target PC, you need to install the boards correctly. See the manufacturer’s literature for installation instructions.

## Null Model Cable Wiring

xPC Target software ships with a null modem cable that you can use to connect the host and target computers for serial communications. The following diagram illustrates the wiring for this cable for a 9 pin DB9 connector.





## Environment Properties for Serial Communication

The xPC Target environment is defined by a group of properties. These properties give xPC Target information about the software and hardware products that it works with. You might change some of these properties often, while others you will rarely want to change.

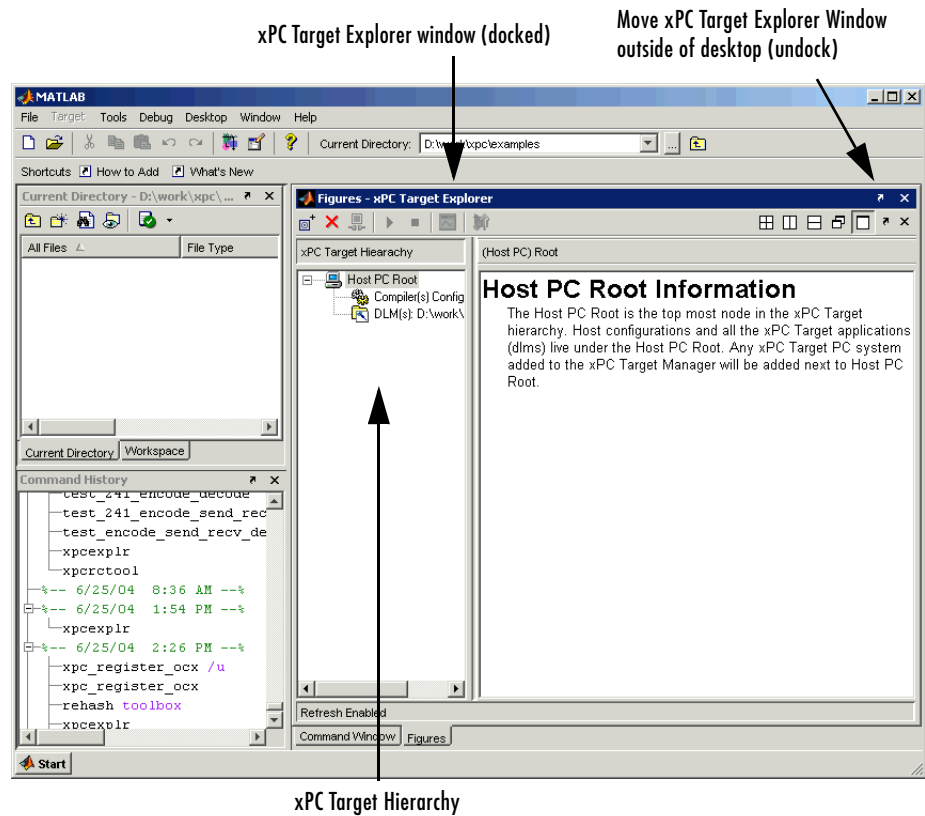
After you have installed xPC Target, you can specify the environment properties for the host and target computers. Note that you must specify these properties before you can build and download a target application.

The following procedure describes how to set up serial communication environment properties through the xPC Target Explorer. If you want to use the `xpcsetup` tool instead, see Chapter 15, “Obsoleted xPC Target User Interfaces.”

- 1 In the MATLAB Command Window, type

```
xpcexplr
```

The **xPC Target Explorer** window opens.



By default, the xPC Target Explorer window is docked inside the MATLAB desktop. You can dock or undock the window, or move it to any other pane in the MATLAB desktop.

Note the contents of the left pane of the xPC Target Explorer. This is the **xPC Target Hierarchy** pane.


This pane contains all the objects in your xPC Target hierarchy. As you add objects to your system, xPC Target Explorer adds corresponding nodes to the **xPC Target Hierarchy** pane. The foremost node is the Host PC node. It

represents the host PC. The right pane displays information that reflects an item selected in the left pane.

xPC Target Explorer associates serial communication environment properties with the target PC.

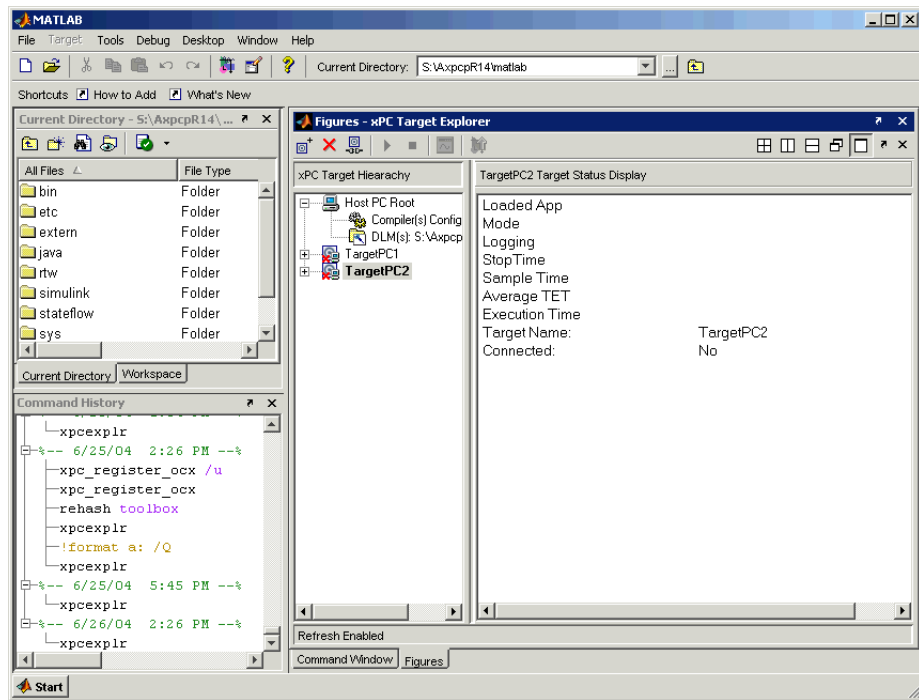
**2** In the xPC Target Explorer, right-click the Host PC node.

**3** Select **Add Target**.

A target PC node, named Target PC1, appears in the **xPC Target Hierarchy**, at the same level as the Host PC node. It appears with the icon  (note the X to denote that the host PC is not connected to the target PC).

**4** As necessary, repeat step 2 and step 3 for each additional target PC you want to add to your system.

Additional target PC nodes appear in the **xPC Target Hierarchy**. As you add other target PCs, the PC number increments. The following figure illustrates two target PC nodes.



- 5 In the xPC Target Explorer, expand a target PC node.

A Configuration node appears. Under this are nodes for Communication, Settings, and Appearance. The parameters for the target PC node are grouped in these categories.

- 6 Select Communication.

The **Communication Component** pane appears to the right.

---

**Note** When you first select a subnode under a target PC node, the target PC node becomes boldfaced. In a multitarget environment, this visual aid helps you easily see the target PC you are working with.

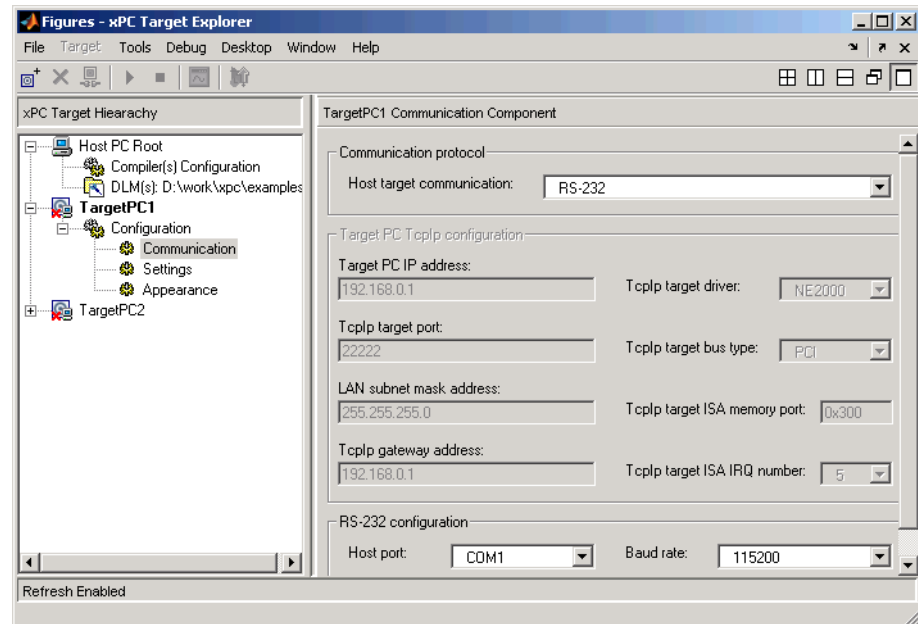
---

- 7 From the **Host target communication** list, select RS232.

The pane changes to one that contains only those parameters pertinent to serial communication.

- 8 From the **Host port** list, select either COM1 or COM2 for the connection on the host PC. xPC Target determines the COM port you use on the target PC automatically.
- 9 From the **Baud rate** list, select the baud rate for the serial connection between the host PC and this target PC. The default is 115200.
- 10 Repeat step 5 to step 9 for any target PC for which you have a serial connection between the host PC and target PC.

The following figure illustrates the xPC Target Explorer settings for the serial connection of one target PC.



You do not have to exit and restart MATLAB after making changes to the xPC Target environment, even if you change the communication between the host

and target from RS-232 to TCP/IP. However, you do have to recreate the target boot disk and rebuild the target application from the Simulink model.

For more information on the xPC Target environment, see Chapter 6, “Software Environment and Demos,” in the xPC Target User’s Guide documentation.

Your next task is to create a target boot disk. See “Target Boot Disk” on page 2-40.

## Network Communication

Before you can create and run a target application, you need to set up the connection between the host and target computers. You can use either serial or network communication. This section includes the following topics:

- “Advantages of Network Communication” on page 2-27
- “Hardware for Network Communication” on page 2-28
- “Ethernet Card for a PCI Bus” on page 2-32
- “Ethernet Card for an ISA Bus” on page 2-32
- “Environment Properties for Network Communication” on page 2-33

For serial communication, see “Serial Communication” on page 2-20.

### Advantages of Network Communication

A host-to-target connection using network TCP/IP communication has advantages over serial RS-232 communication:

- **Higher data throughput** — Network communication using Ethernet can transfer data up to 100 Mbit/second instead of the maximum data transfer rate of 115 kBaud with serial communication.
- **Longer distances between host and target computer** — By using repeaters and gateways you do not restrict the distance between your host and target computers to the length of a serial cable. Communication over the Internet is also possible.

This manual does not include information for installing network cards or the TCP/IP protocol on your host computer. For correct installation and setup of your network cards and the TCP/IP protocol, contact your system administrator.

### Hardware for Network Communication

You must install the following hardware before you install the xPC Target software and configure it for network communication:

- **Network adapter card** — When using xPC Target with TCP/IP, you must have a network adapter card correctly installed on both the host PC and the target PC. Connect the host and target computers with an unshielded twisted pair (UTP) cable to your local area network (LAN). The target PC network adapter card must have a static IP address. The host PC network adapter card can have a dynamic host configuration protocol (DHCP) address. The host PC can be any computer on the network. When using xPC Target with TCP/IP, you must configure the DHCP server to reserve all static IP addresses to prevent these addresses from being assigned to other systems.

You can also directly connect your computers. Use a crossover UTP cable with RJ45 connectors to connect them. Both computers must have static IP addresses. If the host PC also has a network adapter card, that card can have a DHCP address.

- **I/O boards** — If you use I/O boards on your target PC, you need to install the boards correctly.



## Ethernet Card Provided with xPC Target

The MathWorks supplies a PCI bus Ethernet card with the xPC Target software for you to use in a desktop target PC. The following table will help to identify the card that was shipped with your software and the parameter you need to select in the xPC Target Explorer. Both cards support a data transfer rate of 100 Mb/s.

Board	Identification	Setup Parameter
SMC 1208BT	Card includes both BNC and RJ45 connectors and an SMC label on the packaging.	NE2000
Intel Pro/100S	Card has only an RJ45 connector and an Intel label on the back of the card.	I82559

- 1 In the MATLAB Command Window, type  

```
xpcexplr
```

The **xPC Target Explorer** window opens.
- 2 In the xPC Target Explorer **xPC Target Hierarchy** pane, select the Communication node of the target PC for which you want to check the boot disk. For example, select the Communication node for Target PC1.
- 3 From the **Host target communication** list, select TCP/IP.
- 4 From the **TcpIp target driver** list, and depending on the Ethernet card that was shipped with your software, select either NE2000 or I82559.

If you cannot use the Ethernet card provided with xPC Target, see “Ethernet Chips Supported by xPC Target” on page 2-30 for your TCP/IP communication options.

### Ethernet Chips Supported by xPC Target

If you do not want to use the Ethernet card provided with xPC Target, you can use your own Ethernet card. xPC Target supports Ethernet cards with the following data transfer rates:

- 100 Mbits/second
- 10 Mbits/second

These Ethernet cards must contain an approved Ethernet chip, as listed in the following lists.

100 Mbits/second Ethernet cards with the following chips:

- **I82559** — Ethernet control chip from Intel for PCI bus cards with 10/100 Mb/s. In the xPC Target Explorer, and from the **TcpIp target driver** list, select I82559.
- **I82559ER** — Ethernet control chip from Intel for PCI bus cards with 10/100 Mb/s. In the xPC Target Explorer, and from the **TcpIp target driver** list, select I82559.
- **I82550** — Ethernet control chip from Intel for PCI bus cards with 10/100 Mb/s. In the xPC Target Explorer, and from the **TcpIp target driver** list, select I82559.
- **AMD79C971 PCNET**— Fast Ethernet controller chips and other chips in the AMD 79C97x family. In the xPC Target Explorer, and from the **TcpIp target driver** list, select RTLANCE.

10 Mb/s Ethernet cards with the following chips:

- **NE2000** — In the xPC Target Explorer, select NE2000.
- **SMC91C9X** — In the xPC Target Explorer, select SMC91C9X.

The following are cases where you might not be able to use the Ethernet card provided with xPC Target:

- You do not have an available PCI slot in your target PC.
- You do not have a PCI bus in your target PC.
- You need to use an Ethernet card other than the card provided with xPC Target.

If one of the above cases applies, purchase one of the boards from the following list. These boards are compatible with xPC Target.

<b>Board Type</b>	<b>Board Number</b>	<b>xPC Target Driver</b>
PCI	SMC EZ Card 10 SMC1208T (RJ45)	NE2000
	SMC EZ Card 10 SMC1208BT (RJ45, BNC)	NE2000
	SMC EZ Card 10 SMC1208BTA (RJ45, BNC, AUI)	NE2000
	Intel PRO/100 S	I82559
ISA	SMC EZ Card 10 SMC1660T (RJ45)	NE2000
	SMC EZ Card 10 SMC1660BT (RJ45, BNC)	NE2000
	SMC EZ Card 10 SMC1660BTA (RJ45, BNC, AUI)	NE2000
PC/104	RealTime Devices USA CM202 (RJ45, BNC, AUI)	NE2000
	WinSystems Inc. PCM-NE2000-16 (RJ45)	NE2000
	WinSystems Inc. PCM-NE2000-16-BNC (BNC)	NE2000
SBC	Versallogic VSBC-6	SMC91C9X

### **Ethernet Card for a PCI Bus**

If your target PC has a PCI bus, The MathWorks recommends that you use an Ethernet card for the PCI bus. The PCI bus has a faster data transfer rate and requires minimal effort to configure. The MathWorks also supplies one PCI bus Ethernet card with the xPC Target software for your target PC.

To install the PCI bus Ethernet card supplied with the xPC Target software, use the following procedure:

- 1 Turn off your target PC.
- 2 If the target PC already has an unsupported Ethernet card, remove the card.
- 3 Plug the Ethernet card from The MathWorks into a free PCI bus slot.
- 4 Connect your target PC Ethernet card to your LAN using an unshielded twisted-pair cable.

Your next task is to set up the xPC Target environment for network communication. See “Environment Properties for Network Communication” on page 2-33.

### **Ethernet Card for an ISA Bus**

Your target PC might not have an available PCI bus slot, or your target PC might not contain a PCI bus (older motherboards, passive ISA backplanes, or PC/104 computers). In these cases, you can use an Ethernet card for an ISA bus.

If you are using an ISA bus, you need to reserve, from the BIOS, an interrupt for this board.

The MathWorks does not provide an ISA bus board. For a list of known compatible network adapter cards, see “Hardware for Network Communication” on page 2-28.

To install an ISA bus Ethernet card, use the following procedure:

- 1 Turn off your target PC.

- 2 On your ISA bus card, assign an IRQ and I/O-port base address by moving the jumpers or switches on the card. Write down these settings, because you need to enter them in the xPC Target Explorer.

You should set the IRQ line to 11 and the I/O-port base address to around 0x300. If one of these hardware settings would lead to a conflict in your target PC, select another IRQ or I/O-port base address.

---

**Note** If your ISA bus card does not contain jumpers to set the IRQ line and the base address, use the utility on the installation disk supplied with your card to manually assign the IRQ line and base address. Do not configure the card as a PnP-ISA device.

---

- 3 If the target PC already has an unsupported Ethernet card, remove the card. Plug the compatible network card into a free ISA bus slot.
- 4 Connect the target PC network card to your local area network (LAN) using a coaxial cable or an unshielded twisted-pair cable.

If you use an Ethernet card for an ISA bus within a target PC that has a PCI bus, you must reserve the chosen IRQ line number for the Ethernet card in the PCI BIOS. Refer to your BIOS setup documentation to set up the PCI BIOS.

Your next task is to set up the xPC Target environment for network communication. See “Environment Properties for Network Communication” on page 2-33.

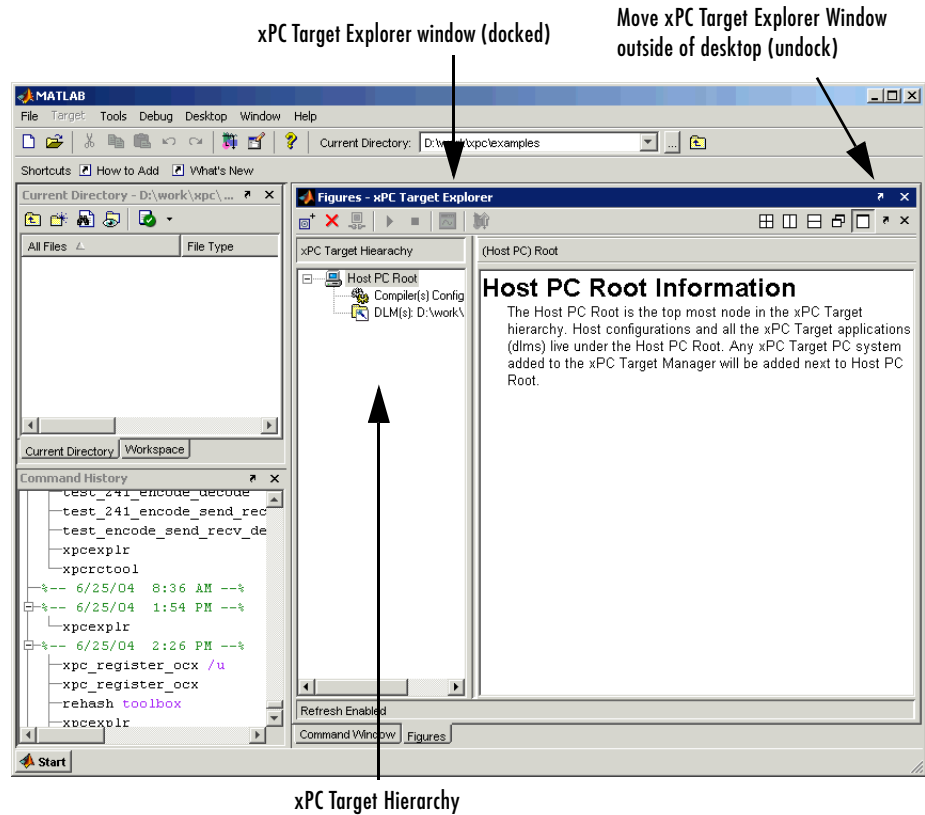
## Environment Properties for Network Communication

The xPC Target environment is defined by a group of properties. These properties give xPC Target information about the software and hardware that it works with. You might change some of these properties often, while others you will rarely want to change.

After you have installed xPC Target, you can specify the environment properties for the host and target computers. Note that you must specify these properties before you can build and download a target application

- 1 In the MATLAB Command Window, type  
`xpcexplr`

The **xPC Target Explorer** window opens.




By default, the xPC Target Explorer window is docked inside the MATLAB desktop. You can dock or undock the window, or move it to any other pane in the MATLAB desktop.

Note the contents of the left pane of the xPC Target Explorer. This is the **xPC Target Hierarchy** pane.

This pane contains all the objects in your xPC Target hierarchy. As you add objects to your system, xPC Target Explorer adds corresponding nodes to the **xPC Target Hierarchy** pane. The foremost node is the Host PC node. It represents the host PC. The right pane displays information that reflects an item selected in the left pane.

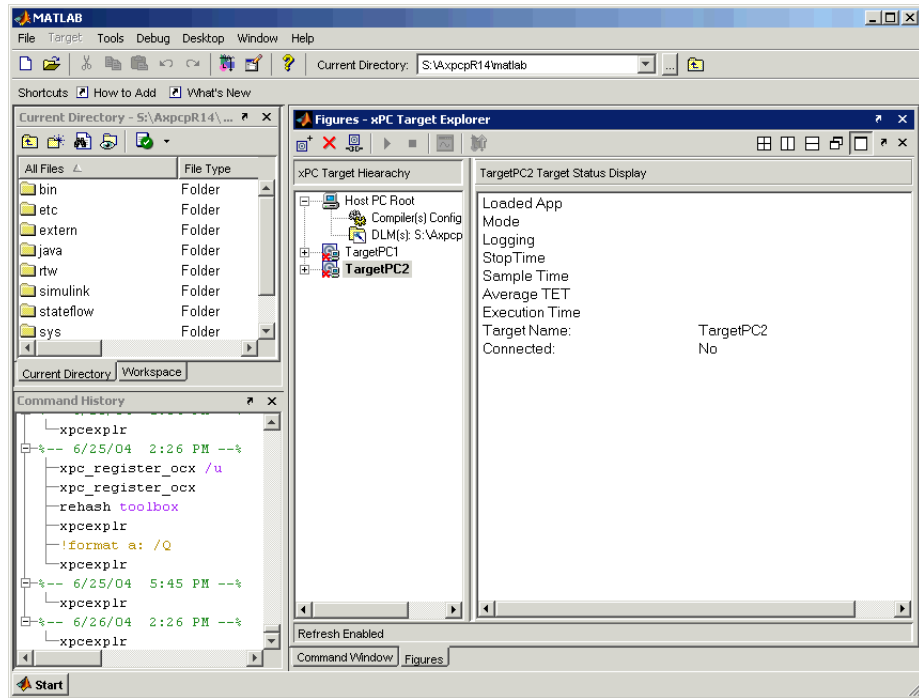
xPC Target Explorer associates network communication environment properties with the target PC.

- 2 In the xPC Target Explorer, right-click the Host PC node.
- 3 Select **Add Target**.

A target PC node, named Target PC1, appears in the **xPC Target Hierarchy**, at the same level as the Host PC node. It appears with the icon  (note the X to denote that the host PC is not connected to the target PC).

- 4 As necessary, repeat step 2 and step 3 for each additional target PC you want to add to your system.

Additional target PC nodes appear in the **xPC Target Hierarchy**. As you add other target PCs, the PC number increments. The following figure illustrates two target PC nodes.



- 5 In the xPC Target Explorer, expand a target PC node.

A Configuration node appears. Under this are nodes for Communication, Settings, and Appearance. The parameters for the target PC node are grouped in these categories.

- 6 Select Communication.

The **Communication Component** pane appears to the right.

- 7 From the **Host target communication** list, select TcpIp.

The pane changes to one that contains only those parameters pertinent to network communication.



- 8 You must enter the following properties with the correct values according to your LAN environment. Ask your system administrator for values for the following settings:
  - **Target PC IP address** — This is the IP address for your target PC. An example of an IP address is 192.168.0.1.
  - **LAN subnet mask address** — This is the Subnet Mask address of your LAN. An example of a Subnet Mask address is 255.255.0.0.
- 9 Optionally enter the following properties, depending on your specific circumstances:
  - **TcpIp target port** — This property is set by default to 22222. This value should not cause any problems, because this number is higher than the reserved area (telnet, ftp, ...) and it is only relevant on the target PC. If necessary, you can change this property value to any value higher than 20000 and less than 65536.
  - **TcpIp gateway address** — This property is set by default to 255.255.255.255. This means that you do not use a gateway to connect to your target PC.

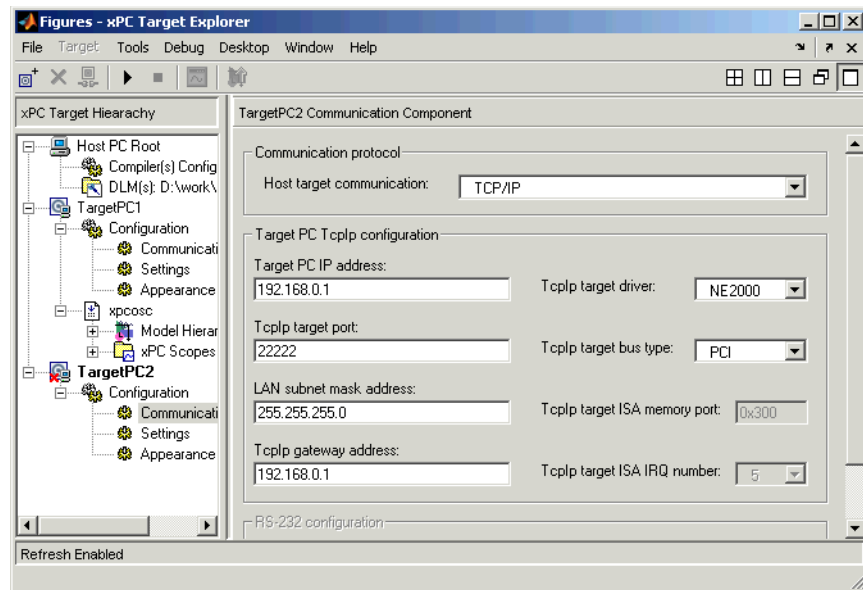
If you communicate with the target PC from within your LAN, you might not need to define a gateway and change this setting.

If you communicate from a host PC located in a LAN different from your target PC, you need to define a gateway and enter its IP address. This is especially true if you want to work over the Internet. Ask your system administrator for the IP address of the appropriate gateway.
- 10 Enter the following properties specific for the Ethernet card on your target PC:
  - **TcpIp target driver** — From the list, select NE2000, SMC91C9X, I82559, or RTLANCE. This property is set by default to NE2000.
  - **TcpIp target bus type** — This property is set by default to PCI. If **TcpIp target bus type** is set to PCI, then the properties **TcpIp target ISA memory port** and **TcpIp target ISA IRQ number** have no effect on TCP/IP communication and are disabled (grayed out). If you are using an ISA bus Ethernet card, set **TcpIp target bus type** to ISA and enter values for **TcpIp ISA memory port** and **TcpIp target ISA IRQ number**.

- **TcpIp target ISA memory port** and **TcpIp target ISA IRQ number** — If you are using an ISA bus Ethernet card, you must enter values for the properties **TcpIp target ISA memory port** and **TcpIp target ISA IRQ number**. The values of these properties must correspond to the jumper settings or ROM settings on your ISA bus Ethernet card.
- 11 Repeat step 5 to step 10 for any target PC for which you have a network connection between the host PC and target PC.

xPC Target updates the environment with new properties as you enter them.

The following figure illustrates the **Configuration Component** pane for a network connection.



You do not have to exit and restart MATLAB after making changes to the xPC Target environment, even if you change the communication between the host and target from RS-232 to TCP/IP. However, you do have to recreate the target boot disk and rebuild the target application from the Simulink model.

For more information on the xPC Target Environment, see Chapter 6, “Software Environment and Demos,” in the xPC Target User’s Guide documentation.

Your next task is to create a target boot disk. See “Target Boot Disk” on page 2-40.

# Target Boot Disk

The target boot disk includes the xPC Target kernel specific for either serial or network communication. If you installed the xPC Target Embedded Option, and you select stand-alone mode, the target boot disk includes the target application. This section includes the following topics:

- “Creating a Target Boot Disk with a Graphical User Interface” on page 2-40
- “Creating a Target Boot Disk with Command-Line Interface” on page 2-42
- “Current Properties on the Target Boot Disk” on page 2-43

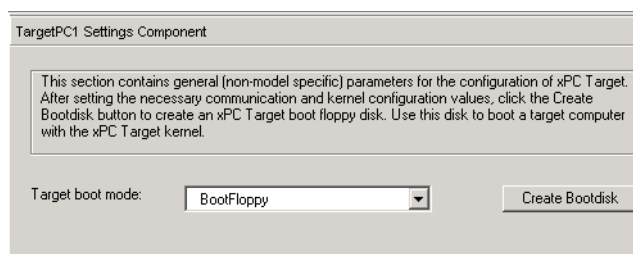
## Creating a Target Boot Disk with a Graphical User Interface

You use the target boot disk to load and run the xPC Target kernel. After you make changes to the xPC Target environment properties, you need to create or update a target boot disk.

To create a target boot disk for the current xPC Target environment, use the following procedure. This procedure describes how to create a target boot disk for the target Target PC1. Alternatively, see “Creating a Target Boot Disk with Command-Line Interface” on page 2-42.

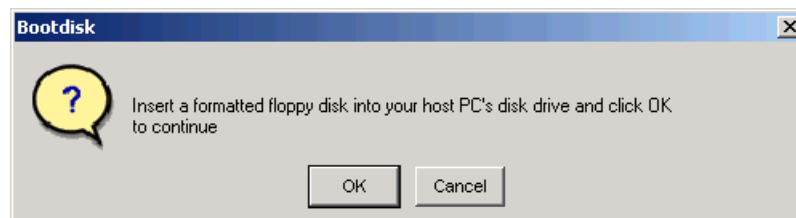
- 1 If the xPC Target Explorer is not open, open it now. At the MATLAB Command Window, type  

```
xpcexplr
```
- 2 In the xPC Target Explorer **xPC Target Hierarchy** pane, select a target PC Configuration node. For example, select the Configuration node for Target PC1.  
  
A **TargetBoot** pane appears in the right-most pane.
- 3 From the **Target boot mode** list, select a boot disk mode. For example, select BootFloppy.



- 4 Click the **Create Bootdisk** button.

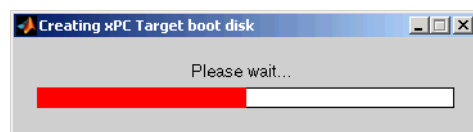
The following message box opens.



- 5 Insert a formatted 3.5 inch floppy disk into the host PC disk drive, and then click **OK**.

All data on the disk will be erased as xPC Target writes the xPC Target kernel and other required files to the 3.5 inch disk.

xPC Target displays the following dialog box while creating the boot disk. The process takes about 1 to 2 minutes.



- 6 When the 3.5 inch disk drive stops, remove the 3.5 inch disk.
- 7 Insert the boot disk into your target PC disk drive and reboot that PC.

Your next task is to install the software on the target PC and test your installation. See “Testing and Troubleshooting the Installation” on page 2-45.

### **Creating a Target Boot Disk with Command-Line Interface**

You use the target boot disk to load and run the xPC Target kernel. After you make changes to the xPC Target environment properties, you need to create or update a boot disk.

To create a target boot disk for the current xPC Target environment, use the following procedure:

- 1 In the MATLAB window, type

```
xpcbootdisk
```

xPC Target displays the following message.

```
Insert a formatted floppy disk into your host PC s  
disk drive and press any key to continue.
```

- 2 Insert a formatted floppy disk into the host PC disk drive, and then press any key.

The write procedure starts and, while creating the boot disk, the MATLAB window displays the following status information. On Windows NT systems, the status information is displayed only at the end of the write process.

```
Creating xPC Target boot disk ... Please wait  
  
xPC Target boot disk successfully created.
```

Your next task is to install the software on the target PC and test your installation. See “Testing and Troubleshooting the Installation” on page 2-45.

## Current Properties on the Target Boot Disk

To check whether a target boot disk corresponds to the current xPC Target environment, use one of the following procedures.

---

**Note** If you upgrade your xPC Target software, you need to recreate the target boot disk.

---

### Checking the Target Boot Disk with an xPC Target GUI

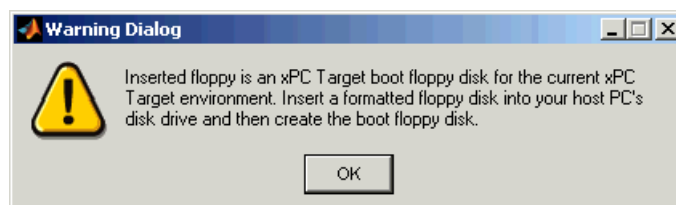
- 1 If the xPC Target Explorer is not open, open it now. At the MATLAB Command Window, type  

```
xpcexplr
```
- 2 In the xPC Target Explorer **xPC Target Hierarchy** pane, select the Configuration node of the target PC for which you want to check the boot disk. For example, select the Configuration node for Target PC1.

A **TargetBoot** pane appears in the right-most pane.

- 3 From the **TargetBoot** list, select a boot disk mode. For example, select BootFloppy.

If the boot disk properties correspond to the current properties, the following warning appears and no data is written to the disk.



### Checking the Target Boot Disk with MATLAB Commands

- 1 Insert the target boot disk into your host PC drive. In the MATLAB window, type

```
xpcbootdisk
```

MATLAB displays the message

```
Insert a formatted floppy disk into your host PC s  
disk drive and press a key to continue
```

- 2 Press any key.

If the boot disk properties correspond to the current properties, MATLAB displays the following message and no data is written to the disk.

```
Inserted floppy is a xPC Target boot floppy disk for the current  
xPC Target environment
```



## Testing and Troubleshooting the Installation

Use this section to test and troubleshoot connection and communication problems between your host and target computers. This section includes the following topics:

- “Testing the Installation” on page 2-45
- “Test 1, Ping Target System Standard Ping” on page 2-47
- “Test 2, Ping Target System xPC Target Ping” on page 2-49
- “Test 3, Reboot Target Using Direct Call” on page 2-49
- “Test 4, Build and Download Application” on page 2-50

### Testing the Installation

xPC Target uses a test script to test the entire installation. After you install the xPC Target software, set the environment settings, and create a target boot disk, you can test your installation:

- 1 Insert your target boot disk into your target PC disk drive.
- 2 To reboot the target PC, press the reset button on the PC.

After loading the BIOS, xPC Target boots the kernel and displays the following screen on the target PC.

<pre>Loaded App: 1MB free Memory:    124MB Mode:      loader Logging:   - StopTime: - SampleTime: - AverageTET: - Execution: -</pre>	<pre>----- * xPC Target 2.6, (c)1996-2004 The MathWorks, Inc. * ----- System: Host-Target Interface is RS232 (COM1/2) System: COM2 detected, BaudRate: 115200</pre>
--	---

- 3 In the MATLAB Current Directory window, select a directory outside the MATLAB root directory.

---

**Note** During the build process, Real-Time Workshop does not allow files to be saved within the MATLAB tree root. If you select a current directory within the MATLAB tree, the xPC Target test procedure fails when trying to build a target application.

---

- 4 In the MATLAB Command Window, type

```
xpctest
```

MATLAB runs the test script and displays messages indicating the success or failure of a test. If you use RS-232 communication, the first test is skipped.

```
### xPC Target Test Suite 2.6
### Host-Target interface is: TCP/IP (Ethernet)
### Test 1, Ping target system using standard ping: ... OK
### Test 2, Ping target system using xpctargetping: ... OK
### Test 3, Reboot target using direct call: ..... OK
### Test 4, Build and download xPC Target application: ... OK
### Test 5, Check host-target communication for commands: .. OK
### Test 6, Download xPC Target application using OOP: ... OK
### Test 7, Execute xPC Target application for 0.2s: ... OK
### Test 8, Upload logged data and compare with simulation:. OK
### Test Suite successfully finished
```

If all of the tests succeed, you are ready to build and download a target application to the target PC. See Chapter 3, “Basic Tutorial.”

If any of the tests fails, see the appropriate test section:

- “Test 1, Ping Target System Standard Ping” on page 2-47
- “Test 2, Ping Target System xPC Target Ping” on page 2-49
- “Test 3, Reboot Target Using Direct Call” on page 2-49
- “Test 4, Build and Download Application” on page 2-50

## Test 1, Ping Target System Standard Ping

If you are using a network connection, this is a standard system ping to your target computer. If this test fails, try troubleshooting with the following procedure:

- 1 Open a DOS shell and type the IP address of the target computer:

```
ping xxx.xxx.xxx.xxx
```

DOS should display a message similar to the following:

```
Pinging xxx.xxx.xxx.xxx with 32 bytes of data:  
Reply from xxx.xxx.xxx.xxx: bytes=32 time<10 ms TTL=59
```

- 2 Check the messages on your screen.

**Ping command fails** — If the DOS shell displays the following message,

```
Pinging xxx.xxx.xxx.xxx with 32 byte of data:  
Request timed out.
```

the ping command failed, and the problem might be with your network cables.

To solve this problem, check your network cables. You might have a faulty network cable, or if you are using a coaxial cable, the terminators might be missing.

**Ping command fails, but cables are okay** — If the cables are okay, the problem might be that you entered an incorrect property in the **xPC Target Explorer** window.

To solve this problem, in the MATLAB window, type

```
xpcexplr
```

For the problem target PC, check that **Target PC IP address**, **LAN subnet mask address**, and **TcpIp gateway address** have the correct values. On the host PC, open the **xPC Target Explorer** window, change the TCP/IP options, and then create a new boot floppy disk. On the target PC, reboot with the new boot floppy disk.

For a PCI bus:

- Check that **TcpIp target bus type** is set to PCI instead of ISA.

For an ISA bus:

- Check that **TcpIp target bus type** is set to ISA instead of PCI.
- Check that **TcpIp target ISA memory port** is set to the correct I/O-port base address, and check that the address does not lead to a conflict with another hardware resource.
- Check that **TcpIp target ISA IRQ number** is set to the correct IRQ line, and check that the line number does not lead to a conflict with another hardware resource.
- If the target PC motherboard contains a PCI chip set, check if the IRQ line used by the ISA bus Ethernet card is reserved within the BIOS setup.

**Ping succeeds, but test 1 with the command xpctest fails** — The problem might be that you have incorrect IP and gateway addresses entered in the xPC Target Explorer.

To solve this problem, in the MATLAB window, type

```
xpcexplr
```

For the problem target PCs, enter the correct addresses. Recreate the target boot disk by inserting a floppy disk into the host disk drive, and then clicking the **Create BootDisk** button.

If you still cannot solve your problem, see “If You Still Need More Help” on page 2-50.

## Test 2, Ping Target System xPC Target Ping

This test is an xPC Target ping to your target computer. If this test fails, try troubleshooting with the following procedure:

- 1 In the MATLAB window, type

```
tg=xpctarget.xpc
```

- 2 Check the messages in the MATLAB window.

MATLAB should respond with the following messages:

```
xPC Object
Connected           = Yes
Application         = loader
```

**Target object does not connect** — If you do not get the preceding messages, the problem might be that you have a bad target boot disk.

To solve this problem, create another target boot disk with a new floppy disk. See “Target Boot Disk” on page 2-40.

If you still cannot solve your problem, see “If You Still Need More Help” on page 2-50.

## Test 3, Reboot Target Using Direct Call

This test tries to boot your target computer using an xPC Target command. If this test fails, try troubleshooting with the following procedure:

- 1 In the MATLAB window, type

```
xpctest noreboot
```

This command reruns the test without using the reboot command and displays the message

```
### Test 3, Reboot target using direct call: ... SKIPPED
```

- 2 Observe the messages in the MATLAB window during the build process.

**Reboot fails, but build okay when reboot skipped** — If the command `xpctest` skips the reboot command but successfully builds and loads the target application, the problem could be that some target hardware does not support the xPC Target reboot command. In this case, you cannot use this command to reboot your target computer. You need to reboot using a hardware reset button.

If you still cannot solve your problem, see “If You Still Need More Help” on page 2-50.

### Test 4, Build and Download Application

This test tries to build and download the model `xpcosc.mdl`. If this test fails, try troubleshooting with the following procedure:

- 1 In the MATLAB window, check the error messages.

These messages help you locate where there is a problem.

- 2 If you get the error message

`xPC Target loader not ready`

Reboot your target computer. This error message is sometimes displayed even if the target screen shows the loader is ready.

If you still cannot solve your problem, see “If You Still Need More Help” on page 2-50.

### If You Still Need More Help

If you cannot solve your problem, contact The MathWorks directly for help.

**Internet**      <http://www.mathworks.com/support/>

**E-mail**        <mailto:support@mathworks.com>

**Telephone**    508-647-7000

Ask for Technical Support.

# Basic Tutorial

---

This chapter explains the basic functions of xPC Target by using a simple Simulink model. Since this model does not have I/O blocks, you can try these procedures whether or not you have I/O hardware on your target PC. This chapter includes the following sections:

Simulink Model (p. 3-2)

Create a simple Simulink model with a square wave input and output blocks for tracing and logging signal data

Simulating the Model (p. 3-34)

Check the behavior of your Simulink model by simulating the model in nonreal time

xPC Target Application (p. 3-38)

Create a boot disk and boot the target PC, create a target application, and download the target application to a target PC

Running the Target Application (p. 3-51)

Test the behavior of your target application by running the application in real time

## Simulink Model

Before you can create a target application, you need to create a Simulink model. xPC Target then uses the Simulink model, Real-Time Workshop, and a third-party compiler to create the target application. This section includes the following topics:

- “Creating a Simple Simulink Model” on page 3-2 — Create a simple second-order system with a sine wave input.
- “Adding a Simulink Outport Block” on page 3-8 — Add an Outport block to log signal data to the MATLAB workspace for analysis.
- “Entering Parameters for the Outport Blocks” on page 3-10 — Enter and select parameters in the **Configuration Parameters** dialog box.
- “Adding an xPC Target Scope Block” on page 3-15 — Add an xPC Target Scope block to visualize signals while running the target application.
- “Entering Parameters for an xPC Target Scope Block” on page 3-19 — Enter scope parameters in the **Block Parameters** dialog box before building the target application.

### Creating a Simple Simulink Model

This tutorial uses a simple Simulink model to explain the tasks you need to do with xPC Target. If you are an experienced Simulink user, you can skip creating this model.

The model includes a transfer function and a signal generator block. If you want to visualize signals while simulating your model, you need to add a standard Simulink Scope block:

- 1** In the MATLAB Command Window, type  

```
simulink
```

The Simulink library window opens.

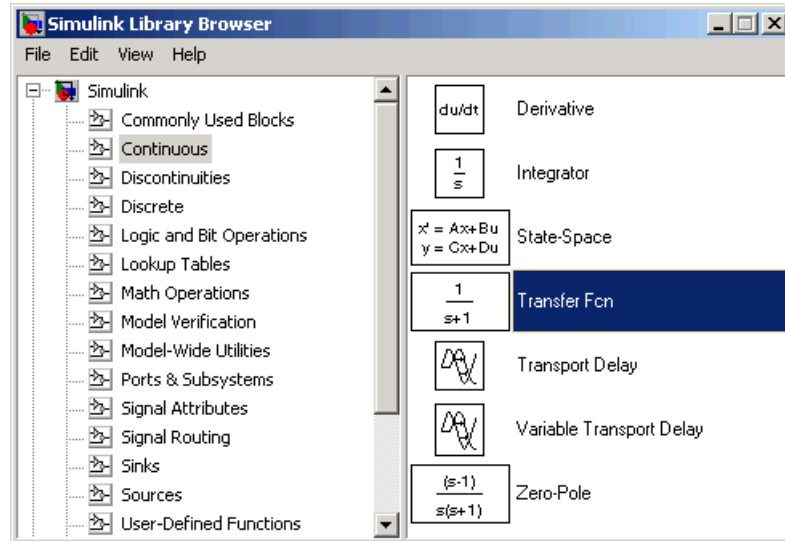
- 2** From the **File** menu, point to **New**, and then click **Model**.

A blank Simulink model window opens.



- 3 In the left pane, double-click **Simulink**, and then click **Continuous**.

In the right pane, the Simulink library shows a list of blocks.



- 4 Click and drag the Transfer Fcn block to the Simulink model window.
- 5 Adjust the Numerator and the Denominator values to reflect the example.
- 6 In the Simulink Library Browser window, click and drag the following blocks to your model.
- Click Sources, and add a Signal Generator block.
  - Click Sinks, and add a Scope block.
  - Click Signal Routing, and add a Mux block.

---

**Note** If you provide a name for a signal in the Signal name property of the **Signal Properties** dialog box, that name appears in the target PC GUI scope graph after you build and download the model to the target PC. By default, if you do not enter a name for the signal in this dialog box, the scope graph displays the signal identifier rather than a name.

---

- 7 Double-click the Signal Generator block. The **Block Parameters** dialog box opens. From the **Wave form** list, select square.

In the **Amplitude** text box, enter

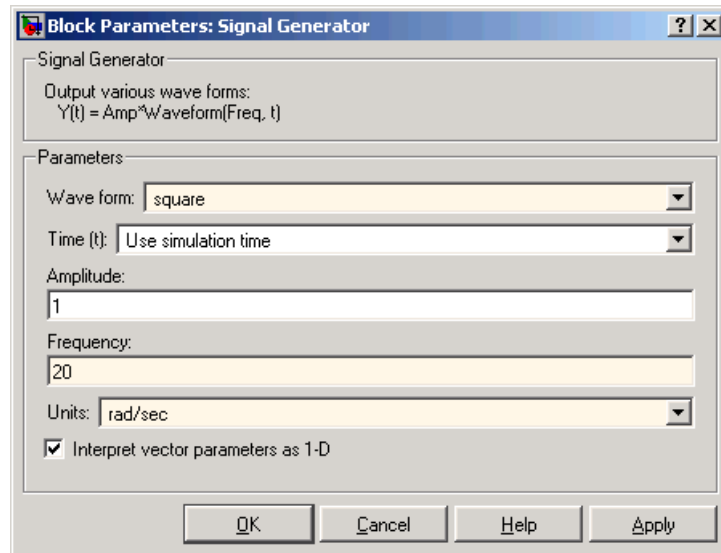
1

In the **Frequency** text box, enter

20

From the **Units** list, select rad/sec.

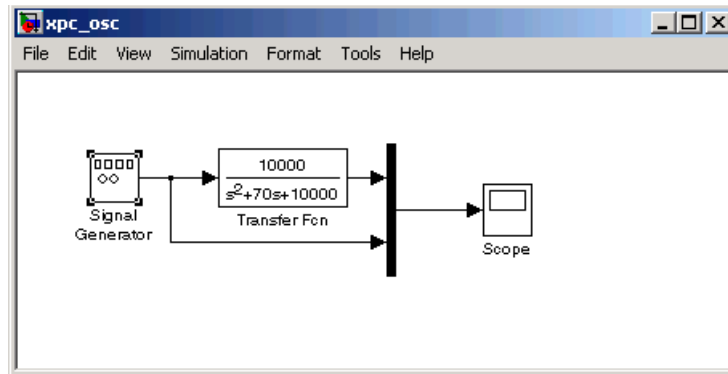
Your **Block Parameters** dialog box will look similar to the following figure.



- 8 Double-click the Transfer Fcn block.
- 9 Edit the **Numerator** and **Denominator** parameters to match those in the following figure.

- 10 Connect the Signal Generator block to the Transfer Fcn block, and connect the input and output signals to the scope block using the Mux block.

Your model should look similar to the figure shown.



- 11 From the **File** menu, click **Save As** and enter a filename. For example, enter `xpc_osc` and then click **OK**.

Since xPC Target does not support data uploading with external mode, you cannot use the Simulink Scope block to visualize signals from an xPC Target application running in real time. Instead, use an xPC Target Scope block. See “Adding an xPC Target Scope Block” on page 3-15.

For information on creating a Simulink model and adding signal and scope blocks, see the Using Simulink documentation.

## Entering Parameters for the Scope Block

You enter or change scope parameters to specify the  $x$ -axis and  $y$ -axis in a Scope window. Other properties include the number of graphs in one Scope window and the sample time for models with discrete blocks.

After you add a Scope block to your Simulink model, you can enter the scope parameters for signal tracing:

- 1 In the Simulink window, double-click the Scope block.

A Scope window opens.

- 2 Click the **Parameters** button.



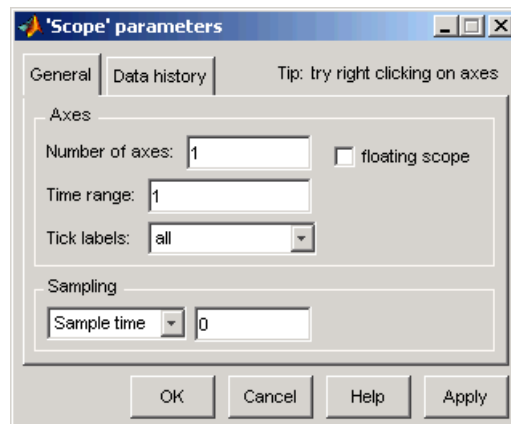
A **Scope parameters** dialog box opens.

- 3 Click the **General** tab. In the **Number of axes** box, enter the number of graphs you want in one Scope window. For example, enter 1 for a single graph. Do not select the **floating scope** check box.

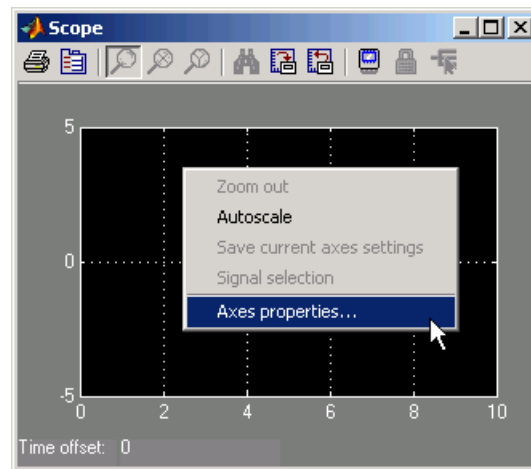
In the **Time range** box, enter the upper value for the time range. For example, enter 1 second. From the **Tick labels** list, choose all.

From the **Sampling** list, choose Sample time and enter 0 in the text box. Entering 0 indicates that Simulink evaluates this block as a continuous-time block. If you have discrete blocks in your model, enter the **Fixed step size** you entered in the **Configuration Parameters** dialog box.

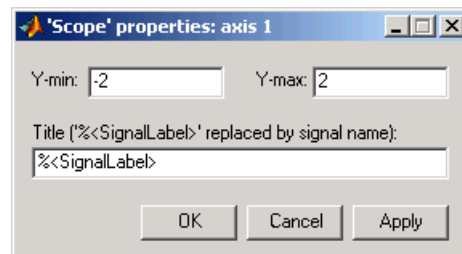
Your **Scope parameters** dialog box will look similar to the figure shown below.



- 4 Do one of the following:
  - Click **Apply** to apply the changes to your model and leave the dialog box open.
  - Click **OK** to apply the changes to your model and close the **Scope parameters** dialog box.
- 5 In the Scope window, point to the  $y$ -axis shown in the figure below, and right-click.



- 6 From the pop-up menu, click **Axes Properties**.
- 7 The **Scope properties: axis 1** dialog box opens. In the **Y-min** and **Y-max** text boxes, enter the range for the  $y$ -axis in the Scope window. For example, enter -2 and 2 as shown in the figure below.



8 Do one of the following:

- Click **Apply** to apply the changes to your model and leave the dialog box open.
- Click **OK** to apply the changes to your model and close the **Axes Parameters** dialog box.

## Adding a Simulink Output Block

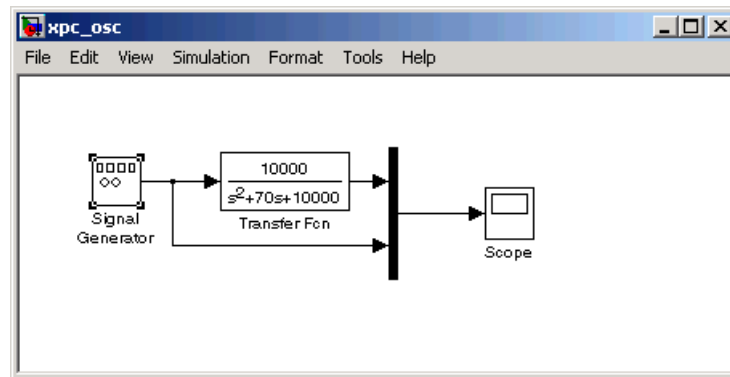
If you want to log signal data to the MATLAB workspace for analysis and later save that data to a disk, you need to add a Simulink Output block and activate logging from the **Configuration Parameters** dialog box.

The following procedure uses the Simulink model `xpc_osc.mdl` as an example. To create this model, see “Creating a Simple Simulink Model” on page 3-2.

1 In the MATLAB window, type

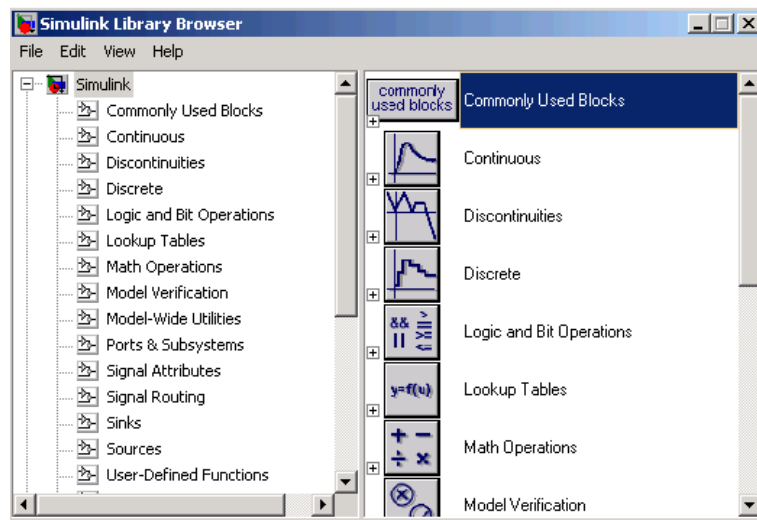
```
xpc_osc
```

The Simulink block diagram opens for the model `xpc_osc.mdl`.

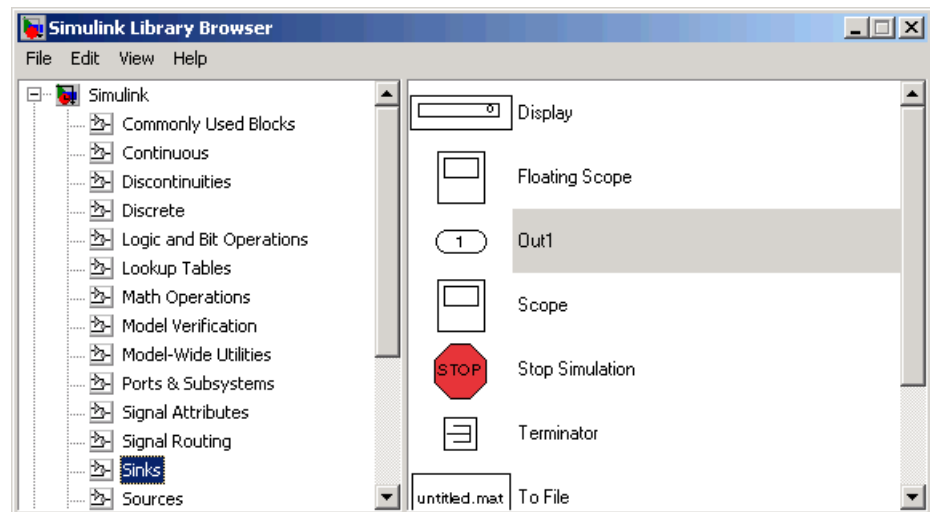


2 In the Simulink window, from the **View** menu, click **Library Browser**.

The **Simulink Library Browser** window opens.

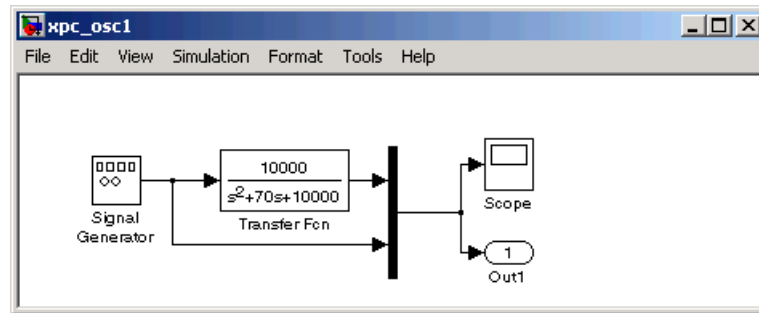


- 3** In the left pane, double-click **Simulink**, and then click **Sinks**.  
In the right pane, the browser shows a list of sink blocks.



- Click and drag the Out1 block to your model and connect it to the output of the Mux block.

Your model should look similar to the figure shown.



- From the **File** menu, click **Save As** and enter a filename. For example, enter xpc\_osc1 and then click **OK**.

Your next task is to enter parameters for the Output block. See “Entering Parameters for the Output Blocks” on page 3-10.

## Entering Parameters for the Output Blocks

During a simulation, Simulink saves signal data to MATLAB variables using Output blocks. The default MATLAB variables are tout, xout, and yout. While running a real-time application, xPC Target uses these same variables to pass signal data to target object parameters. A target object is a structure in the MATLAB workspace that xPC Target uses to interact with a target application. The default target object is tg, and the default parameters are tg.Time, tg.States, and tg.Output.

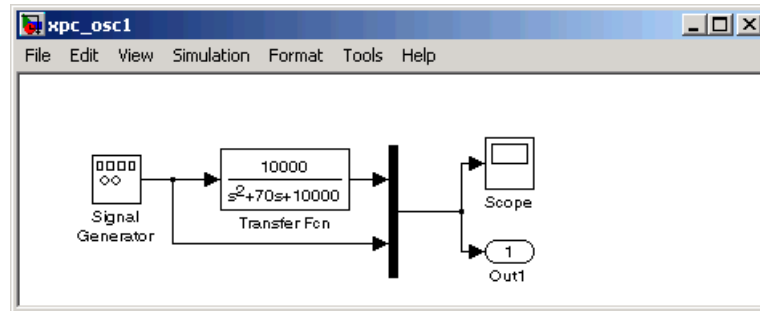
After you add an Output block to your Simulink model, you can enter parameters. This procedure uses the model xpc\_osc1.mdl with an Output block as an example. To add an Output block, see “Adding a Simulink Output Block” on page 3-8.



- 1 In the MATLAB window, type

```
xpc_osc1
```

A Simulink window with the model xpc\_osc1 opens.



- 2 In the Simulink window, from the **Simulation** menu, click **Configuration Parameters**.

The **Configuration Parameters** dialog is displayed for the model.

- 3 Click the **Solver** node.

Simulink displays the **Solver** pane. The **Simulation** section of this pane defines the initial stop and sample time for your target application.

- 4 In the **Solver options** section, enter 0 seconds in the **Start time** box. In the **Stop time** box, enter an initial stop time. For example, enter 20 seconds. To change this time after creating your target application, change the target object property `tg.Stoptime` to the new time using the MATLAB command-line interface. To specify an infinite stop time, enter `inf`.

- 5 From the **Type** list, select **Fixed-step**. Real-Time Workshop does not support variable-step solvers.

The **Solver** pane dialog changes.

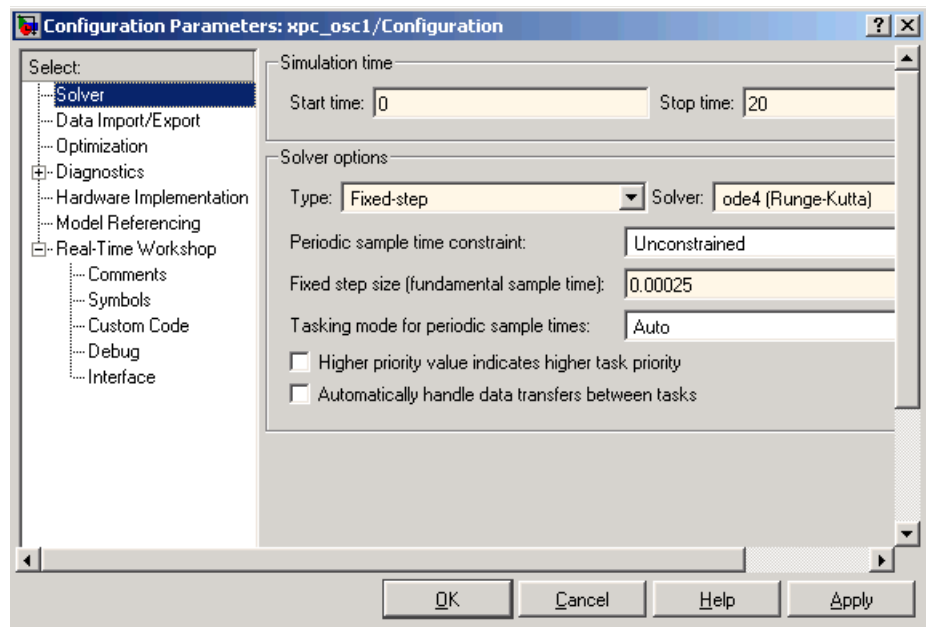
- 6 From the **Solver** list, select a solver. For example, select the general-purpose solver `ode4` (Runge-Kutta).

- 7 In the **Fixed step size** box, enter the sample time for the target application. For example, enter 0.00025 second (250 microseconds). You can change this value after creating the target application.

If you find that 0.000250 second results in overloading the CPU on the target PC, try a larger **Fixed step size** such as 0.002 seconds.

If your model contains discrete states, which would lead to a hybrid model with both continuous and discrete states, the sample times of the discrete states can only be multiples of the **Fixed step size**. If your model does not contain any continuous states, enter 'auto', and the sample time is taken from the model.

The **Solver** pane should look similar to the figure shown below.



- 8 Click the **Data Import/Export** node.

The **Data Import/Export** pane opens. This pane defines the model signals logged during a simulation of your model or while running your target application.

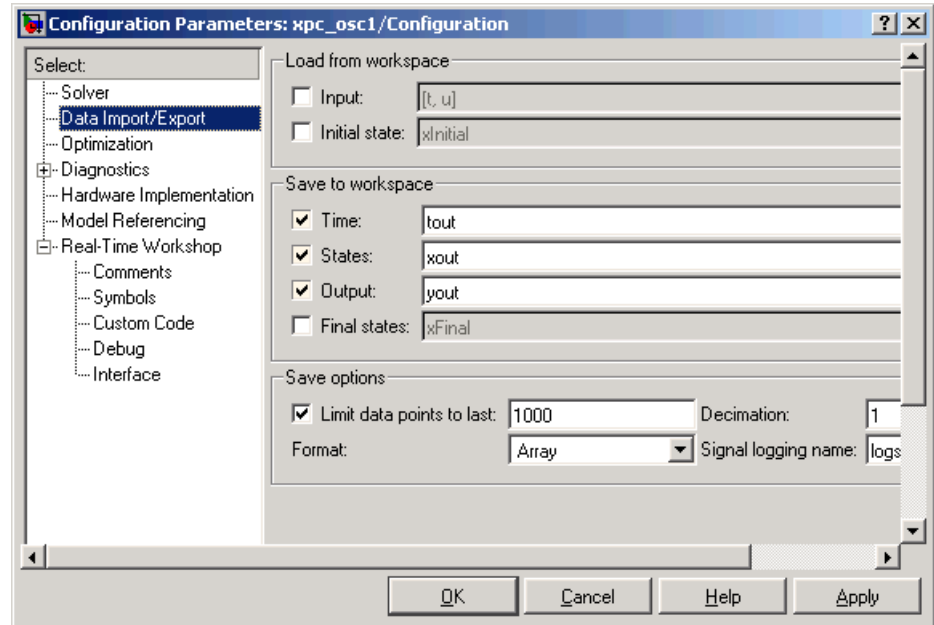
- 9 In the **Save to workspace** section of this pane, select the **Time**, **States**, and **Output** check boxes.

---

**Note** When your target application is running in real time, data is not saved to the variables `tout` and `yout`. Instead, data is saved to the target object properties `TimeLog`, `StateLog`, and `OutLog`. However, you must still select the **Time**, **States**, and **Output** check boxes for data to be logged to the target object properties.

---

The **Data Import/Export** pane should look similar to the figure shown.



Normally you select all the **Save to workspace** check boxes. However, you might want to consider clearing some or all of them in the following cases:

- **Many states** — If your model contains many states (for example, more than 20 states), the storage of the state vector requires a lot of target memory. If you clear the **States** check box, logging of states is turned off and more memory is available for the target application. An alternative to logging all the state signals is to select individual states of interest by adding Output blocks to your model.
- **Small sample time** — If you choose a very short sample time, this setting might overload the CPU. If you clear the **Save to workspace** check boxes, logging is turned off and more computing time is available for calculating the model.

**10** Click **OK**.

**11** From the **File** menu, click **Save**. The model is saved as `xpc_osc1.mdl`.

Your next task is to add an xPC Target Scope block to your Simulink model. See “Adding an xPC Target Scope Block” on page 3-15.

## Adding an xPC Target Scope Block

xPC Target does not support the standard Simulink Scope blocks, but it does support xPC Target Scope blocks, which have unique capabilities when you use them with an xPC Target application. Do not confuse these xPC Target Scope blocks with standard Simulink Scope blocks.

Adding xPC Target Scope blocks to your Simulink model can save you time. When you build the model, the resulting target application contains the xPC Target Scope blocks you added to the model. After you download the target application, the xPC Target Scope block automatically displays on the target PC monitor. If you do not add xPC Target Scope blocks to your model and you want to monitor signals on the target application without rebuilding it, you need to add xPC Target scopes and define and select signals for the scopes (see Chapter 3, “Signals and Parameters” of the xPC Target User’s Guide documentation). The signal information is saved with your model.

After you create a Simulink model, you can add an xPC Target Scope block. The following procedure uses the Simulink model `xpc_osc1.mdl` as an example to show how to connect an xPC Target Scope block to your model:

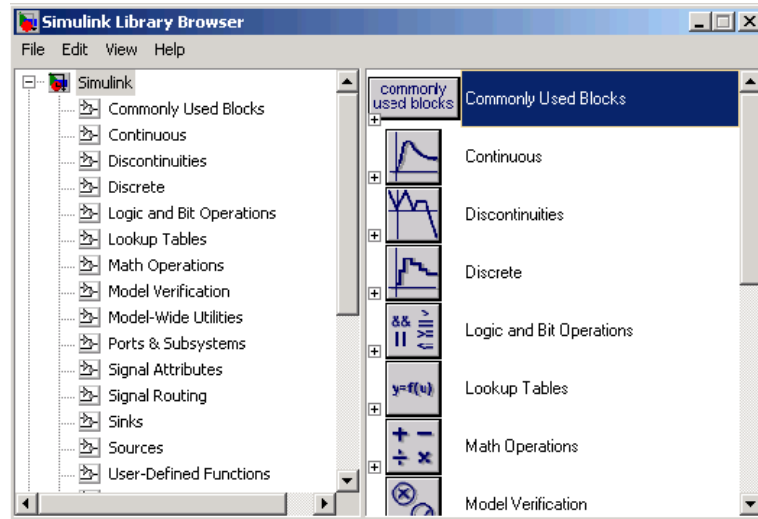
- 1 In the MATLAB window, type

```
xpc_osc1
```

The Simulink block diagram opens for the model `xpc_osc1.mdl`.

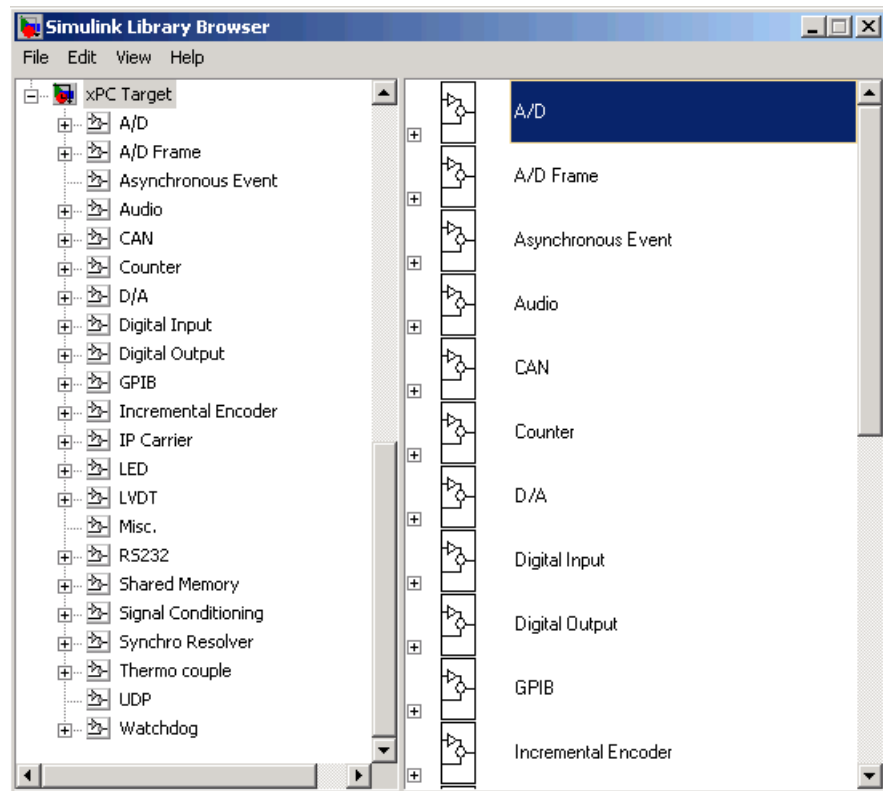
- 2 In the Simulink window, from the **View** menu, click **Library Browser**.

The **Simulink Library Browser** window opens.



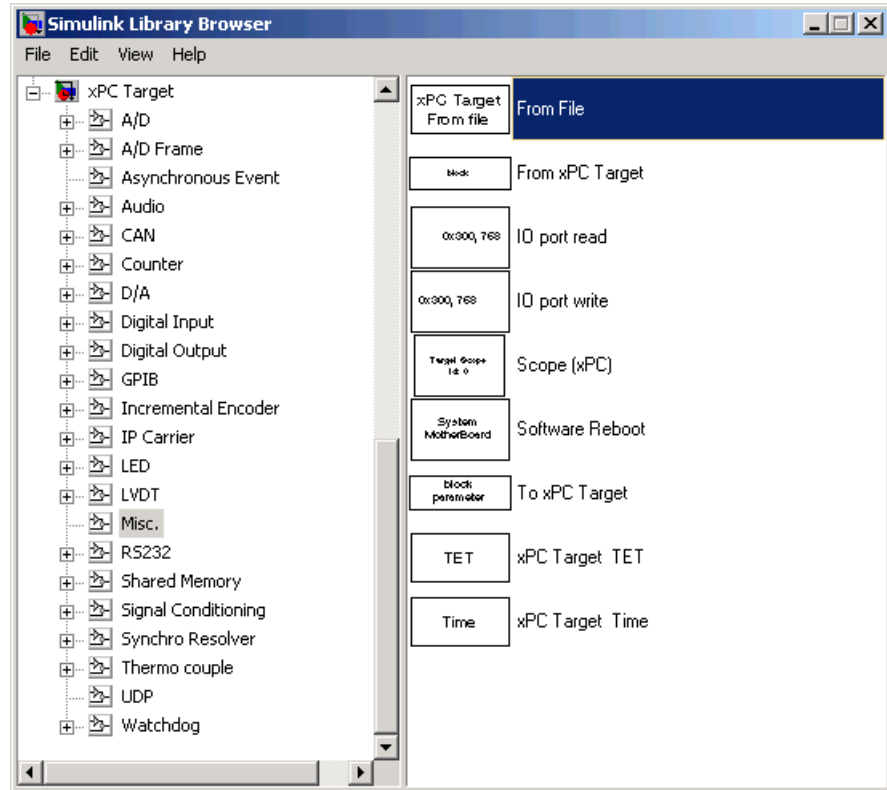
**3** In the left pane, browse to and double-click **xPC Target**.

A list of I/O functions opens.



**4** Click **Misc.**

A list of miscellaneous group blocks opens.



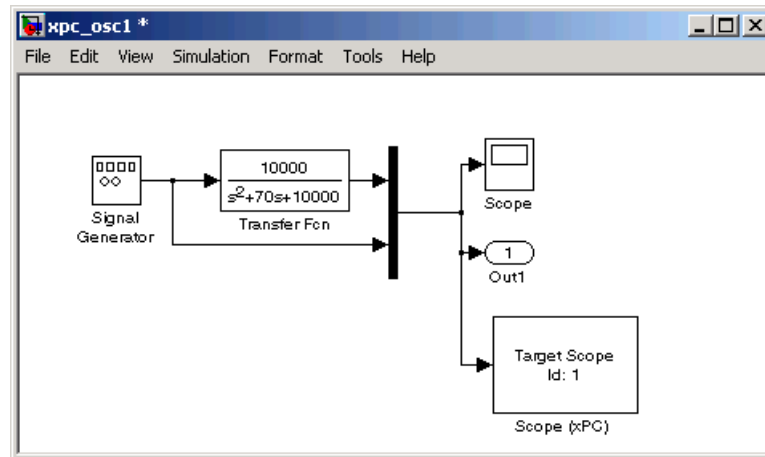
**5** Click and drag **Scope (xPC)** to your Simulink block diagram.

Simulink adds a new Scope block to your model with a scope identifier of 1.

**6** Connect the xPC Target Scope block to the Simulink Scope block.



The model `xpc_osc1.mdl` should look like the figure shown.



- From the **File** menu, click **Save As**. Enter a filename. For example, enter `xpc_osc2` and then click **OK**.

Your next task is to define the xPC Target Scope block parameters. See “Entering Parameters for an xPC Target Scope Block” on page 3-19.

## Entering Parameters for an xPC Target Scope Block

xPC Target Scope block parameters define the signals to trace on the scope and trigger modes. When the target application is downloaded to the target PC, the xPC Target kernel automatically creates the scope on the target. No additional definitions are necessary if you want a default scope on the target. This section describes how you can configure the xPC Target Scope block for other scope behavior.

After you add an xPC Target Scope block to your Simulink model, you can enter parameters for this block. To add an xPC Target Scope block, see “Adding an xPC Target Scope Block” on page 3-15. To enter the parameters for an xPC Target Scope block to write signal data to a file on the target PC, see “Entering Parameters for an xPC Target Scope of Type File” on page 3-29.

There are three types of scopes, target, host, and file. The xPC Target Scope block dialog changes depending on which scope type you are configuring. The following sections describe the procedure depending on the scope type:

- “Entering Parameters for an xPC Target Scope of Type Target” on page 3-20
- “Entering Parameters for an xPC Target Scope of Type Host” on page 3-26
- “Entering Parameters for an xPC Target Scope of Type File” on page 3-29

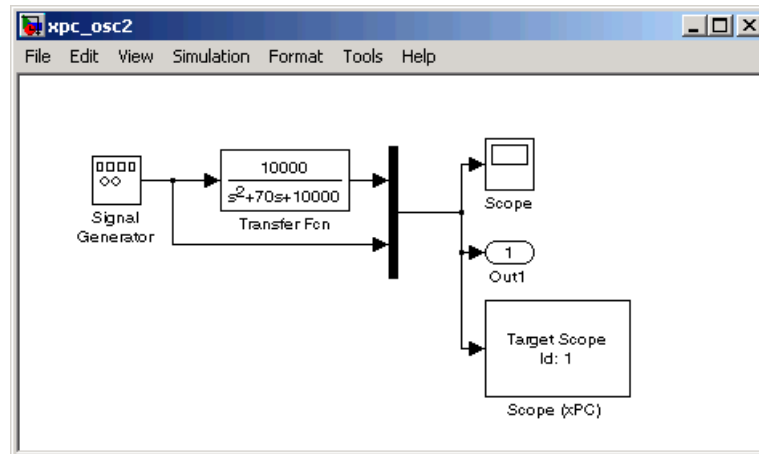
### Entering Parameters for an xPC Target Scope of Type Target

This procedure uses the model `xpc_osc2.mdl` as an example.

- 1 In the MATLAB window, type

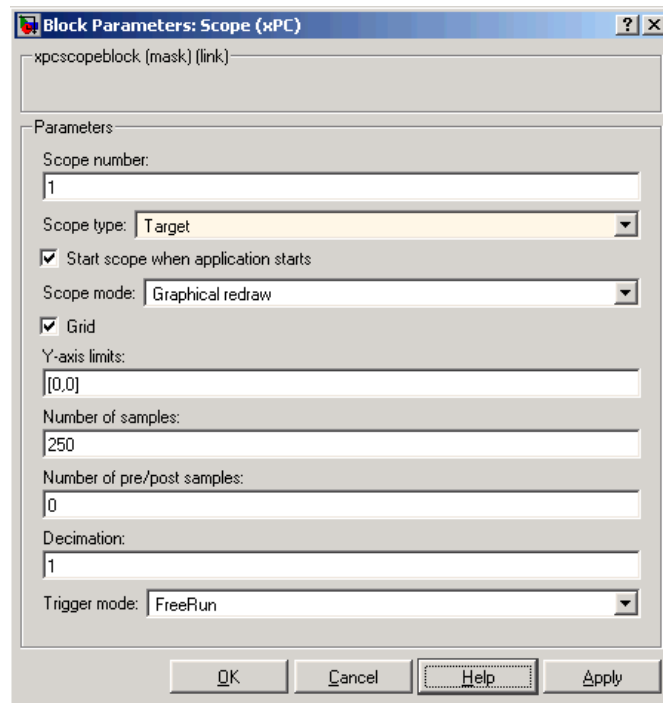
```
xpc_osc2
```

The Simulink block diagram opens for the model `xpc_osc2.mdl`.



- 2 Double-click the block labeled Scope (xPC).

The **Block Parameters: Scope (xPC)** dialog box opens.



By default, the scope of type Target dialog is displayed.

- 3 In the **Scope number** box, a unique number to identify the scope is displayed. This number is incremented each time you add a new xPC Target Scope block. Normally, you do not want to edit this value.

This number identifies the xPC Target Scope block and the scope screen on the host or target computers.

- 4 From the **Scope type** list, select Target if it is not already selected.

The updated dialog box is displayed.

- 5 Select the **Start scope when application starts** check box to start a scope when the target application is downloaded and started. The scope window opens automatically.

- 6 From the **Scope mode** list, select Numerical, Graphical redraw, Graphical sliding, or Graphical rolling.

If you have a scope type of Target and a scope mode of Numerical, the scope block dialog adds a **Numerical format** box to the dialog. You can define the display format for the data. See step 7 for a description of how to complete the **Numerical format** box. If you choose not to complete the **Numerical format** box, xPC Target displays the signal using the default format of %15.6f, which is a floating-point format, with no label.

- 7 In the **Numerical format** box, enter a label and associated numeric format type in which to display signals. By default, the entry format is the floating-point, %15.6f. The **Numerical format** box takes entries of the format

```
'[LabelN] [%width.precision] [LabelX]'
```

where

LabelN is the label for the signal. You can use a different label for each signal or the same label for each signal. This argument is optional.

width is the minimum number of characters to offset from the left of the screen or label. This argument is optional.

precision is the maximum number of decimal places for the signal value. This argument is optional.

type is the data type for the signal format. You can use one or more of the following types:

Type	Description
%e or %E	Exponential format using e or E
%f	Floating point
%g	Signed value printed in f or e format depending on which is smaller
%G	Signed value printed in f or E format depending on which is smaller

LabelX is a second label for the signal. You can use a different label for each signal or the same label for each signal. This argument is optional.

Enclose the contents of the **Numerical format** field in quotation marks.

For example,

```
'Foo %15.2f end'
```

For a whole integer signal value, enter 0 for the precision value. For example,

```
'Foo1 %15.0f end'
```

For a line with multiple entries, delimit each entry with a command and enclose the entire string in quotation marks. For example,

```
'Foo2 %15.6f end,Foo3 %15.6f end2'
```

You can have multiple **Numerical format** entries, separated by a comma. If you enter one entry, that entry applies to each signal (scalar expansion). If you enter fewer label entries than signals, the first entry applies to the first signal, the second entry applies to the second signal, and so forth, and the last entry is scalar expanded for the remaining signals. If you have two entries and one signal, xPC Target ignores the second label entry and applies the first entry. You can enter as many format entries as you have signals for the scope.

- 8 Select the **Grid** check box to display grid lines on the scope. Note that this parameter is only applicable for scopes of type Target and scope modes of type Graphical redraw, Graphical sliding, or Graphical rolling.
- 9 In the **Y-Axis limits** box, enter a row vector with two elements where the first element is the lower limit of the y-axis and the second element is the upper limit. If you enter 0 for both elements, then scaling is set to auto. Note that this parameter is only applicable for scopes of type Target and scope modes of type Graphical redraw, Graphical sliding, or Graphical rolling.
- 10 In the **Number of samples** box, enter the number of values to be acquired in a data package.

If you select a **Scope mode** of Graphical redraw, this parameter specifies the number of values to be acquired before the graph is redrawn.

If you select a **Trigger mode** other than FreeRun, this parameter can specify the number of samples to be acquired before the next trigger event.

- 11 In the **Number of pre/post samples** box, enter the number of samples to save or skip. Specify a value less than 0 to save this number of samples before a trigger event. Specify a value greater than 0 to skip this number of samples after the trigger event before data acquisition begins.
- 12 In the **Decimation** box, enter a value to collect data at each sample time (1) or to collect data at less than every sample time (2 or greater).
- 13 From the **Trigger mode** list, select FreeRun.

If you select FreeRun or Software Triggering, the trigger event is an automatic one. No external trigger specification is required.

If you select Signal Triggering, then, in the **Trigger signal** box, enter the index of a signal. In the **Trigger level** box, enter a value for the signal to cross before triggering. From the **Trigger slope** list, select either, rising, or falling. You do not need to specify scope triggering.

If you select Scope Triggering, then in the **Trigger scope number** box, enter the scope number of a Scope block. If you use this trigger mode, you

---

must also add a second Scope block to your Simulink model. You do not need to specify signal triggering.

If you select Scope Triggering and want the scope to trigger on a specific sample of the other scope, enter a value in the **Sample to trigger on** box. The default value is 0 and indicates that the triggering scope and the triggered (current) scope start simultaneously. For more information on this field, see “Triggering One Scope with Another Scope to Acquire Data” in Chapter 2, in the xPC Target User’s Guide documentation.

**14** Click **OK**.

**15** From the **File** menu, click **Save As**. The model is saved as `xpc_osc2.mdl`.

Your next task is to simulate the model. See “Simulating the Model” on page 3-34.

---

**Note** As soon as the target application is built and downloaded, the xPC Target kernel creates a scope. If you want to change xPC Target Scope parameters after building the target application or while it is running, you need to assign the scope to a MATLAB variable. To assign the scope object, use the target object method `getscope`.

If you use the target object method `getscope` to remove a scope created during the build and download process, and then you restart the target application, the xPC Target kernel recreates the scope.

---

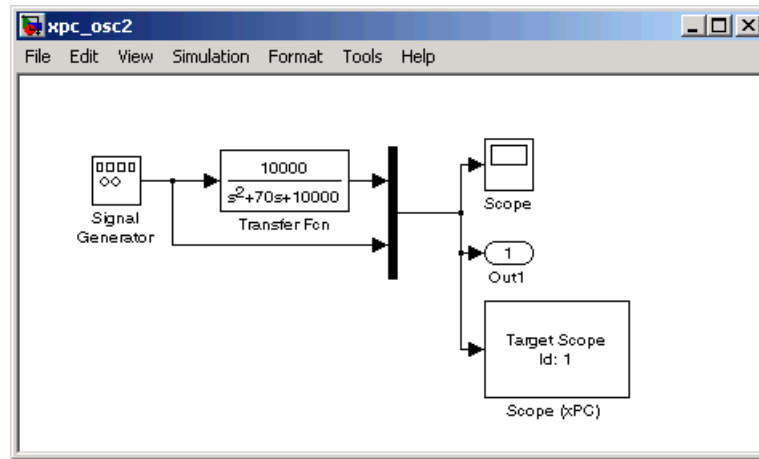
## Entering Parameters for an xPC Target Scope of Type Host

This procedure uses the model `xpc_osc2.mdl` as an example.

- 1 In the MATLAB window, type

```
xpc_osc2
```

The Simulink block diagram opens for the model `xpc_osc2.mdl`.



- 2 Double-click the block labeled **Scope (xPC)**.

The **Block Parameters: Scope (xPC)** dialog box opens.

By default, the scope of type target dialog is displayed.

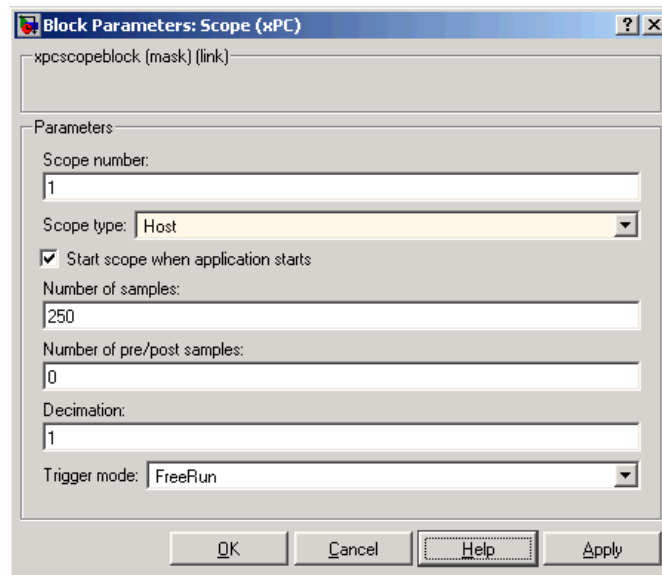
- 3 In the **Scope number** box, a unique number to identify the scope is displayed. This number is incremented each time you add a new xPC Target scope. Normally, you do not want to edit this value.

This number identifies the xPC Target Scope block and the scope screen on the host or target computers.

- 4 From the **Scope type** list, select Host.

The updated dialog box is displayed.





- 5 Select the **Start scope when application starts** check box to start a scope when the target application is downloaded and started. With a scope of type target, the scope window opens automatically. With a scope of type host, you need to open the window by typing xpcscope.
- 6 In the **Number of samples** box, enter the number of values to be acquired in a data package.
- 7 In the **Number of pre/post samples** box, enter the number of samples to save or skip. Specify a value less than 0 to save this number of samples before a trigger event. Specify a value greater than 0 to skip this number of samples after the trigger event before data acquisition begins.
- 8 In the **Decimation** box, enter a value to collect data at each sample time (1) or to collect data at less than every sample time (2 or greater).

- 9** From the **Trigger mode** list, select FreeRun.

If you select FreeRun or Software Triggering, the trigger event is an automatic one. No external trigger specification is required.

If you select Signal Triggering, then in the **Trigger signal** box, enter the index of a signal. In the **Trigger level** box, enter a value for the signal to cross before triggering. From the **Trigger slope** list, select either, rising, or falling. You do not need to specify scope triggering.

If you select Scope Triggering, then in the **Trigger scope number** box, enter the scope number of a Scope block. If you use this trigger mode, you must also add a second Scope block to your Simulink model. You do not need to specify signal triggering.

If you select Scope Triggering and want the scope to trigger on a specific sample of the other scope, enter a value in the **Sample to trigger on** box. The default value is 0 and indicates that the triggering scope and the triggered (current) scope start simultaneously. For more information on this field, see “Triggering One Scope with Another Scope to Acquire Data” in Chapter 2, in the xPC Target User’s Guide documentation.

- 10** Click **OK**.

- 11** From the **File** menu, click **Save As**. The model is saved as xpc\_osc2.mdl.

Your next task is to simulate the model. See “Simulating the Model” on page 3-34.

---

**Note** As soon as the target application is built and downloaded, the xPC Target kernel creates a scope. If you want to change xPC Target Scope parameters after building the target application or while it is running, you need to assign the scope to a MATLAB variable. To assign the scope object, use the target object method `getscope`.

If you use the target object method `remscope` to remove a scope created during the build and download process, and then you restart the target application, the xPC Target kernel recreates the scope.

---

### Entering Parameters for an xPC Target Scope of Type File

In addition to logging signal data via a scope of type `host`, you can also have xPC Target save signal data to a file on the target PC C:\ hard drive or 3.5 inch disk drive.

After you add an xPC Target Scope block to your Simulink model, you can configure this block to save a file on the target PC.

---

**Note** The signal data file can quickly increase in size. You should examine the file size between runs to gauge the growth rate for the file. If the signal data file grows beyond the available space on the disk, the signal data might be corrupted.

---

Saving signal data to files is most useful when you are using target PCs as stand-alone xPC Target systems. To access the contents of the signal data file that a xPC Target scope of type `file` creates, use the xPC Target file system object (`xpctarget.fs`) from a host PC MATLAB window. To view or examine the signal data, you can use the `readxpcfile` utility in conjunction with the `plot` function. For further details on the `xpctarget.fs` file system object and the `readxpcfile` utility, see Chapter 8, “Working with Target PC Files and File Systems.” Saving signal data to files lets you recover signal data from a previous run in the event of system failure (such as a system crash).

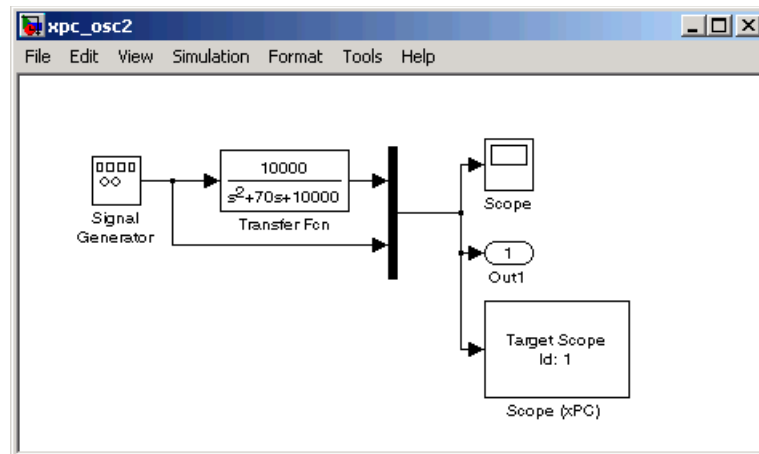
To add an xPC Target Scope block, see “Adding an xPC Target Scope Block” on page 3-15.

This procedure uses the model `xpc_osc2.mdl` as an example.

- 1 In the MATLAB window, type

```
xpc_osc2
```

The Simulink block diagram opens for the model `xpc_osc2.mdl`.



- 2 Double-click the block labeled **Scope (xPC)**.

The **Block Parameters: Scope (xPC)** dialog box opens.

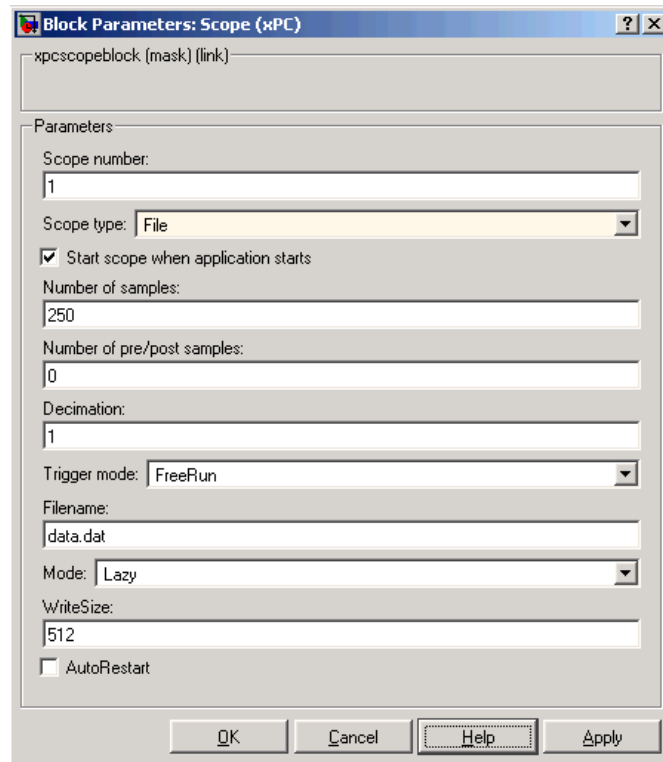
By default, the scope of type Target dialog is displayed.

- 3 In the **Scope number** box, a unique number to identify the scope that is displayed. This number is incremented each time you add a new xPC Target scope. Normally, you do not want to edit this value.

This number identifies the xPC Target Scope block and the scope screen on the host or target computer.

- 4 From the **Scope type** list, select File.

The updated dialog box is displayed.



- 5 Select the **Start scope when application starts** check box to start a scope when the target application is downloaded and started. The scope window opens automatically.
- 6 In the **Number of samples** box, enter the number of values to be acquired in a data package. This parameter works in conjunction with the **AutoRestart** check box. If the **AutoRestart** box is selected, the scope of type file collects data up to **Number of samples**, then starts over again, overwriting the buffer. If the **AutoRestart** box is not selected, the scope of type file collects data only up to **Number of samples**, then stops.
- 7 In the **Number of pre/post samples** box, enter the number of samples to save or skip. Specify a value less than 0 to save this number of samples before a trigger event. Specify a value greater than 0 to skip this number of samples after the trigger event before data acquisition begins.

- 8** In the **Decimation** box, enter a value to collect data at each sample time (1) or to collect data at less than every sample time (2 or greater).

---

**Note** This value is the same as **Decimation** in the MATLAB interface.

---

- 9** From the **Trigger mode** list, select FreeRun, Software Triggering, Signal Triggering, or Scope Triggering.

If you select FreeRun or Software Triggering, the trigger event is an automatic one. No external trigger specification is required.

If you select Signal Triggering, then in the **Trigger signal** box, enter the index of a signal. In the **Trigger level** box, enter a value for the signal to cross before triggering. From the **Trigger slope** list, select either, rising, or falling. You do not need to specify scope triggering.

If you select Scope Triggering, then in the **Trigger scope number** box, enter the scope number of a Scope block. If you use this trigger mode, you must also add a second Scope block to your Simulink model. You do not need to specify signal triggering.

If you want the scope to trigger on a specific sample of the other scope, enter a value in the **Sample to trigger on** box. The default value is 0 and indicates that the triggering scope and the triggered (current) scope start simultaneously. For more information on this field, see “Triggering One Scope with Another Scope to Acquire Data” in Chapter 2, in the xPC Target User’s Guide documentation.

- 10** In the **Filename** box, enter a name for the file to contain the signal data. By default, the target PC writes the signal data to a file named C:\data.dat.

- 11** From the **Mode** list, select either **Lazy** or **Commit**. Both modes open a file, write signal data to the file, then close that file at the end of the session. With the **Commit** mode, each file write operation simultaneously updates the FAT entry for the file. This mode is slower, but the file system always knows the actual file size. With the **Lazy** mode, the FAT entry is updated only when the file is closed and not during each file write operation. This mode is faster, but if the system crashes before the file is closed, the file system might not know the actual file size (the file contents, however, will be intact). If you experience a system crash, you can expect to lose a **WriteSize** amount of data.
- 12** In the **WriteSize** box, enter the block size, in bytes, of the data chunks. This parameter specifies that a memory buffer of length **Number of samples** write data to the file in **WriteSize** chunks. By default, this parameter is 512 bytes, which is the typical disk sector size. Using a block size that is the same as the disk sector size provides optimal performance.

If you experience a system crash, you can expect to lose a **WriteSize** amount of data.

- 13** In the **Number of samples** box, enter the number of values to be acquired in a data package.
- 14** Select the **AutoRestart** check box to enable the scope of type file to collect data up to **Number of samples**, then start over again, appending the new data to the end of the signal data file. Clear the **AutoRestart** check box to have the scope of type file collect data up to **Number of samples**, then stop.

If the named signal data file already exists, xPC Target overwrites the old data with the new signal data.

Your next task is to simulate the model. See “Simulating the Model” on page 3-34.

The following sections describe how to simulate your model and run the target application. With scopes of type file, xPC Target generates a signal data file on the target PC after you run the target application. For further details on working with these files, see Chapter 8, “Working with Target PC Files and File Systems,” in the xPC Target User’s Guide documentation.

## Simulating the Model

You use Simulink in normal mode to observe the behavior of your model in nonreal time. This section includes the following topics:

- “Simulating the Model with Simulink” on page 3-34 — Use the Simulink window interface to run a simulation.
- “Simulating the Model from MATLAB” on page 3-36 — Use Simulink functions in the MATLAB Command Window to run a simulation.

For procedures to run your target application in real time, see “Running the Target Application” on page 3-51.

### Simulating the Model with Simulink

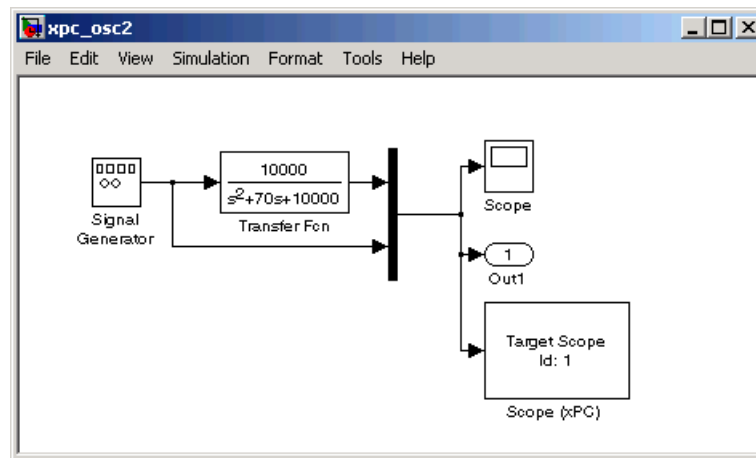
After you load your Simulink model, you can run a simulation. This procedure uses the Simulink model `xpc_osc2.mdl` as an example and assumes you have already loaded that model. To create this model, see “Creating a Simple Simulink Model” on page 3-2.

- 1 In the MATLAB window, type

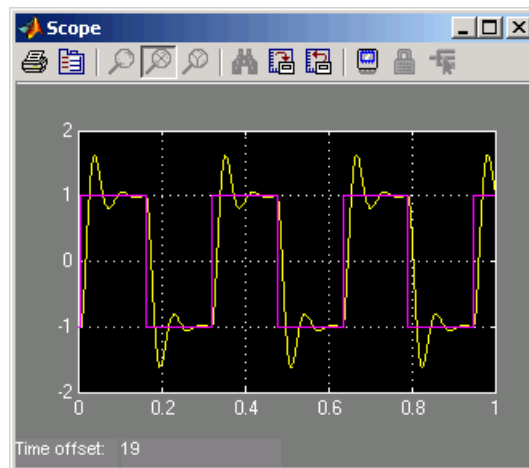
```
xpc_osc2
```

MATLAB loads the oscillator model and displays the Simulink block diagram, as shown below.





- 2 In the Simulink window, double-click the block Scope.  
Simulink opens a scope window.
- 3 From the **Simulation** menu, click **Normal**, and then click **Start**.  
The **Scope1** window displays a trace of the signal data.



- 4** You can either let the simulation run to its stop time, or stop the simulation manually. To stop the simulation manually, from the **Simulation** menu, click **Stop**.

Your next task is to create an xPC Target application. See “xPC Target Application” on page 3-38.

## Simulating the Model from MATLAB

You run a simulation of your Simulink model to observe the behavior of the model in nonreal time.

After you load your Simulink model into the MATLAB workspace, you can run a simulation. This procedure uses the Simulink model `xpc_osc2.mdl` as an example and assumes you have already loaded that model. To create this model, see “Creating a Simple Simulink Model” on page 3-2.

- 1** In the MATLAB window, type

```
sim('xpc_osc2')
```

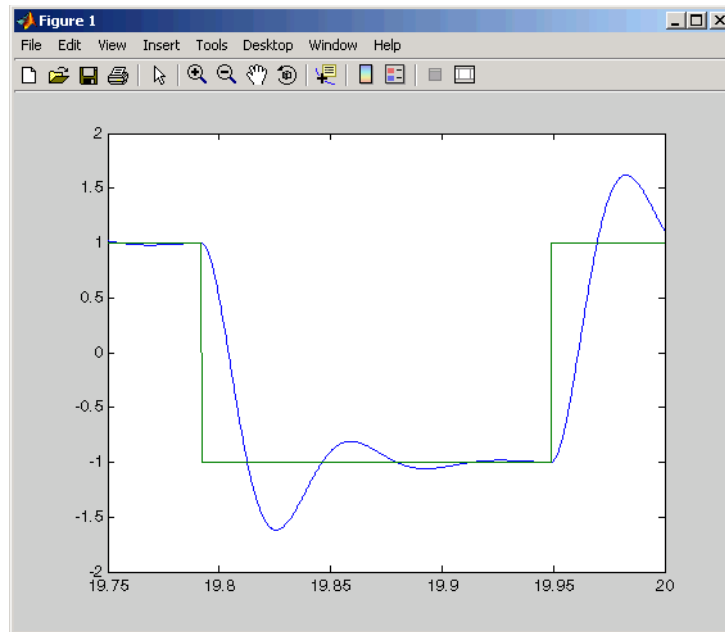
Simulink runs a simulation in normal mode through to completion. You cannot manually stop the simulation. See the Simulink documentation for further information on using the `sim` command.

- 2** After Simulink finishes the simulation, type

```
plot(tout,yout)
```

You entered the MATLAB variables `tout` and `yout` in the **Data I/O** pane on the **Configuration Parameters** dialog box. The signals are logged to memory through Output blocks. To add an Output block, see “Adding a Simulink Output Block” on page 3-8 and “Entering Parameters for the Output Blocks” on page 3-10.

MATLAB opens a plot window and displays the output response. The signal from the signal generator is added to the output block and shown in the figure below.



---

**Note** When your target application is running in real time, data is not saved to the variables `tout` and `yout`. Instead, data is saved in the target PC memory and can be retrieved through the target object properties `tg.TimeLog`, `tg.StateLog`, and `tg.OutLog`. However, in the **Configuration Parameters** dialog box, you must still select the **Time**, **States**, and **Output** check boxes for data to be logged to the target object properties.

---

Your next task is to create a target application. See “xPC Target Application” on page 3-38.

## xPC Target Application

You run the target application to observe the behavior of your model in real time. This section includes the following topics:

- “Booting the Target PC” on page 3-38 — Start the xPC Target kernel running on the target PC.
- “Troubleshooting the Boot Process” on page 3-39 — Solve problems when booting the target PC.
- “Entering the Real-Time Workshop Parameters” on page 3-40 — Enter parameters specific for building target applications.
- “Building and Downloading the Target Application” on page 3-44 — Use Real-Time Workshop and a third-party C compiler to create the target application.
- “Troubleshooting the Build Process” on page 3-46 — Solve problems when building your target application.
- “Increasing the Timeout Value” on page 3-47 — Increase the time the download process waits for a target application to load onto the target PC.
- “xPC Target Options” on page 3-48 — Reference for all of the fields in the dialog box.

For procedures to simulate your model in nonreal time, see “Simulating the Model” on page 3-34.

### Booting the Target PC

Booting the target computer loads and starts the xPC Target kernel on the target PC. The loader then waits for xPC Target to download your target application from the host PC.

After you have configured xPC Target using the xPC Target Explorer, and created a target boot disk for that setup, you can boot the target PC. You need to boot the target computer before building your target application because the build process automatically downloads your target application to the target PC.

- 1** Insert the target boot disk into the target PC disk drive.
- 2** Turn on the target PC or press the reset button.

The target PC displays the following screen.

Loaded App: <b>1MB free</b>	
Memory: <b>124MB</b>	
Mode: <b>loader</b>	
Logging: -	
StopTime: -	
SampleTime: -	
AverageTET: -	
Execution: -	
	-----
	* xPC Target 2.6, (c)1996-2004 The MathWorks, Inc. *
	-----
	System: Host-Target Interface is RS232 (COM1/2)
	System: COM2 detected, BaudRate: 115200

In the example above, the status window shows that the kernel is in loader mode and waiting to load a target application. 1 MB of memory is reserved for the application, 3 MB is used by the kernel, and 28 MB is available from a total of 32 MB. The xPC Target kernel uses the 28 MB for the heap, running scopes, and acquiring data.

Your next task is to enter the simulation and real-time run parameters for Real-Time Workshop. See “Entering the Real-Time Workshop Parameters” on page 3-40.

## Troubleshooting the Boot Process

### Possible Problem

When booting the target PC, it might display the message

```
xPC Target 2.6 loading kernel..@@@@@@@@@@@@@@@@@@@@
```

The target PC displays this message when it cannot read and load the kernel from the target boot disk. The probable cause is a bad disk.

**Solution.** Reformat the disk or use a new formatted floppy disk and create a new target boot disk.

### Possible Problem

When booting the target PC, you get a message similar to the following:

```
Not a bootable medium or NTLDR is missing
```

Selecting either DOSLoader or StandAlone mode instead of BootFloppy mode can cause this message.

**Solution.** If the xPC Target Explorer window is not already open, open it. In the MATLAB Command Window, type `xpcexplr`. In the xPC Target Explorer **xPC**

**Target Hierarchy** pane, select a target PC Configuration node. For example, select the Configuration node for Target PC1. From the **Target boot mode** list, select Bootfloppy. Create a new boot floppy disk.

## Entering the Real-Time Workshop Parameters

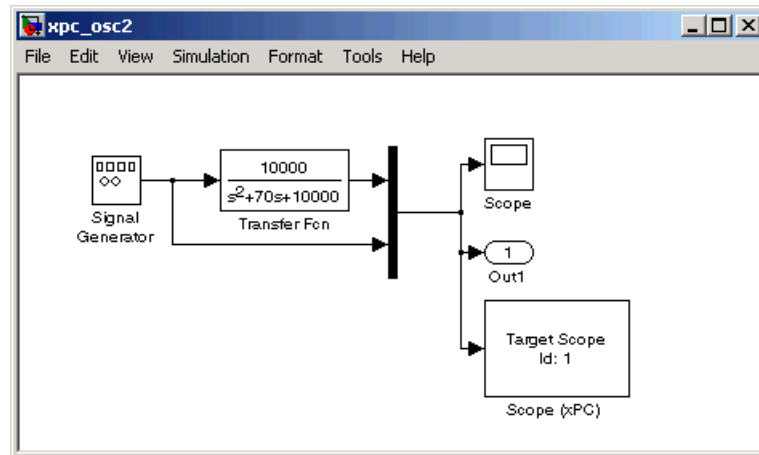
You enter the simulation and real-time run parameters in the **Configuration Parameters** dialog box. These parameters give information to Real-Time Workshop on how to build the target application from your Simulink model.

After you load a Simulink model and boot the target PC, you can enter the simulation parameters. This procedure uses the Simulink model `xpc_osc2.mdl` as an example and assumes you have already loaded that model (see “Simulink Model” on page 3-2).

- 1 In the MATLAB window, type

```
xpc_osc2
```

MATLAB loads the oscillator model and displays the Simulink block diagram, as shown below.



- 2 In the Simulink window, and from the **Simulation** menu, click **Configuration Parameters**.

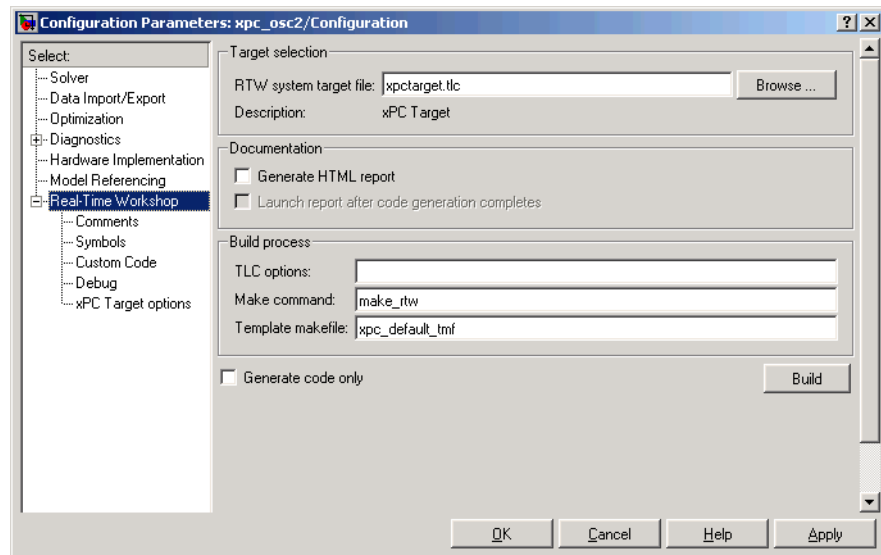
The **Configuration Parameters** dialog box is displayed for the model.

**3** Click the **Real-Time Workshop** node.

The **Real-Time Workshop** pane opens.

**4** To build a basic target application, in the **Target selection** section, click the **Browse** button at the **RTW system target file** list. Click `xpctarget.tlc`, and then click **OK**.

The system target file `xpctarget.tlc`, the template makefile `xpc_default_tmf`, and the make command `make_rtw` are automatically entered into the page. The **xPC Target options** node appears in the left pane. The **Real-Time Workshop** pane should now look like the figure shown.



If you have the Real-Time Workshop Embedded Coder, you can build an ERT target application. To build an ERT target application, in the **Target selection** section, click the **Browse** button at the **RTW system target file** list. Click `xpctargetert.tlc`, and then click **OK**.

Note that if the Real-Time Workshop Embedded Coder is not installed and you select the `xpctargetert.tlc`, the build fails.

- 5 In the left pane, click the **xPC Target options** node.

The associated pane is displayed.

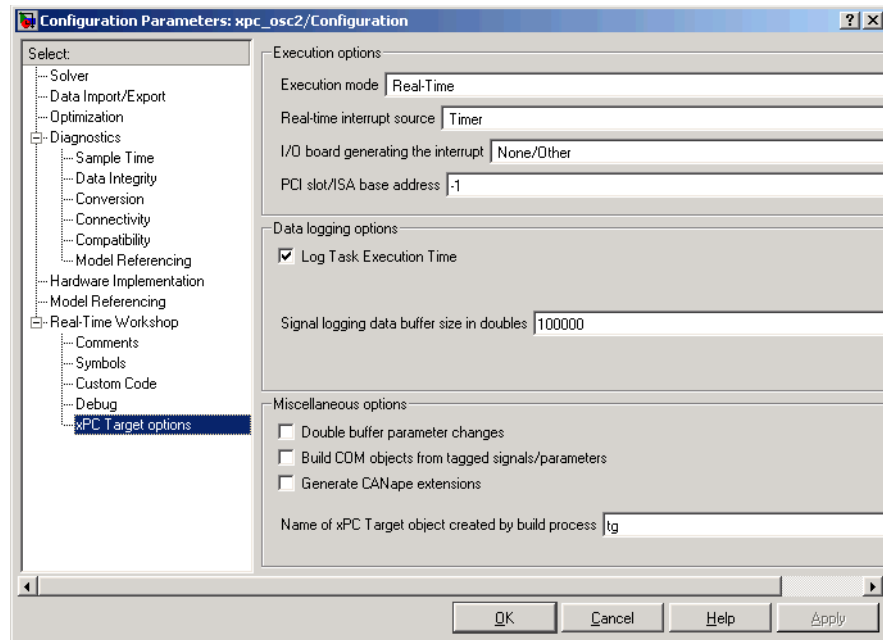
- 6 From the **Execution mode** list, select either Real-Time or Freerun. The option Freerun is similar to a simulation, but with the generated code. It runs the target application as fast as it can. However, unlike a simulation, the Freerun mode of xPC Target does not support variable-step solvers.
- 7 From the **Real-time interrupt source** list, select a source. The default value is Timer.
- 8 Select the **Log Task Execution Time** check box to log task execution times to the target object property `tg.TETlog`.

The task execution time is the time in seconds to complete calculations for the model equations and post outputs during each sample interval.

- 9 In the **Signal logging buffer size in doubles** box, enter the maximum number of sample points to save before wrapping, for example, 100000. This buffer includes the time, states, outputs, and task execution time logs.
- 10 In the **Name of xPC Target object created by build process** box, enter the name of the target object created by the build process. The default target object name is `tg`.

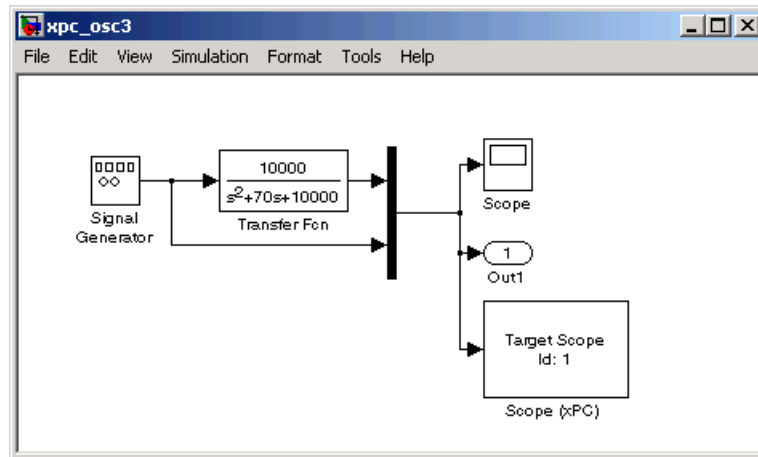
The **Real-Time Workshop** pane should now look like the figure shown.





**11** Click **OK**.

**12** From the **File** menu, click **Save as**. Enter a filename. For example, enter `xpc_osc3` and then click **Save**.



Your next task is to create (build) the target application. See “Building and Downloading the Target Application” on page 3-44.

## Building and Downloading the Target Application

You use the xPC Target build process to generate C code, compile, link, and download your target application to the target PC.

After you enter your changes in the **Configuration Parameters** dialog box, you can build your target application. This procedure uses the Simulink model `xpc_osc3.mdl` as an example. To create this model, see “xPC Target Application” on page 3-38:

- 1 In the MATLAB window, type

```
xpc_osc3
```

MATLAB loads the oscillator model and displays the Simulink block diagram.

- 2 In the Simulink window and from the **Tools** menu, select **Real-Time Workshop**. From the **Real-Time Workshop** submenu, click **Build Model**.

After the compiling, linking, and downloading process, a target object is created in your MATLAB workspace. The default name of the target object is `tg`. For more information about the target object, see Chapter 2, “Targets

and Scopes in the MATLAB Interface,” in the xPC Target User’s Guide documentation.

On the host computer, MATLAB displays the following lines after a successful build process:

```
### Starting Real-Time Workshop build procedure for model:
xpc_osc3
. . .
### Successful completion of xPC Target build procedure for
model: xpc_osc3
```

The target PC displays the following information.

Loaded App: <b>xpc_osc3</b>	Scope: 1, created, type is target
Memory: <b>123MB</b>	Scope: 1, signal 0 added
Mode: <b>RT, single</b>	Scope: 1, signal 1 added
Logging: <b>t x y tet</b>	Scope: 1, NumSamples set to 500
StopTime: <b>20 d</b>	Scope: 1, trigger level set to 0.000000
SampleTime: <b>0.00025</b>	Scope: 1, TriggerScope set to 1
AverageTET: <b>-</b>	Scope: 1, lower y-axis limit set to 0.000000
Execution: <b>stopped</b>	Scope: 1, upper y-axis limit set to 0.000000
	System: <b>initializing application finished</b>

**3** In the MATLAB window, type

```
tg
```

MATLAB displays a list of properties for the target object tg.

If you do not have a successful build, see “Troubleshooting the Build Process” on page 3-46.

Your next task is to run the target application in real time on the target PC. See “Running the Target Application” on page 3-51.

## Troubleshooting the Build Process

If the host PC and target PC are not properly connected, or you have not correctly entered the environment properties, the download process is terminated after about 5 seconds with a timeout error.

To correct the problem, use the following procedure:

- 1 If the xPC Target Explorer is not already up, in the MATLAB window, type

```
xpcexplr
```

The **xPC Target Explorer** window opens.

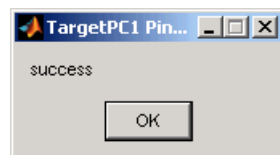
- 2 For the target PC in question, check the RS-232 or TCP/IP parameters. If necessary, make changes to the communication properties and recreate the target boot disk.

In some cases, the download might have completed successfully even though you get a timeout error. To detect this, wait until the target screen displays

```
System:initializing application finished.
```

- 3 In the xPC Target Explorer window
  - a Select the target PC in question
  - b From the menu bar, select **Tools -> Ping Target**.

For a working connection between the host PC and target PC, xPC Target Explorer displays a popup dialog box.



- 4 Right-click the target PC in question and select Connect.

If the connection is resumed, the connection is all right. If the connection is timing out consistently for a particular model, the timeout needs to be increased. See “Increasing the Timeout Value” on page 3-47.

For information on setting up the xPC Target software environment, see either “Environment Properties for Serial Communication” on page 2-21 or “Environment Properties for Network Communication” on page 2-33, and then see “Target Boot Disk” on page 2-40.

## Increasing the Timeout Value

By default, if the host PC does not get a response from the target PC after downloading a target application and waiting about 5 seconds, the host PC software times out. On the other hand, the target PC responds only after downloading and initializing the target application.

Usually 5 seconds is enough time to download a target application, but in some cases it may not be sufficient. The time to download a target application mostly depends on your I/O hardware. For example, thermocouple hardware takes longer to initialize. In this case, even though the target PC is fine, a false timeout is reported.

To increase the timeout value, use the following procedure:

- 1 In your MATLAB working directory, create a file called `xpcd1timeout.dat`.
- 2 In this file, put a single integer. For example, enter  
20

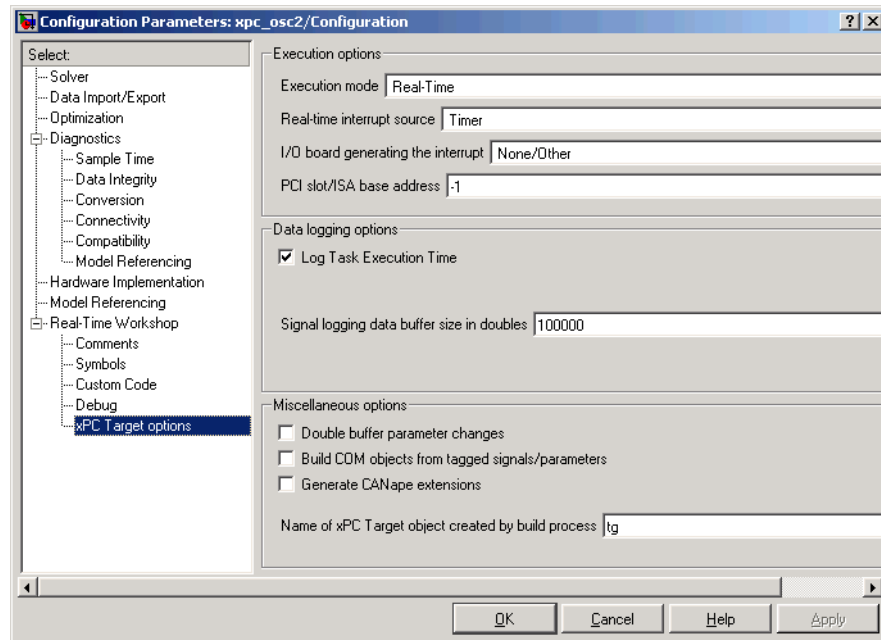
In this case, the host PC waits for about 20 seconds before declaring that a timeout has occurred. Note that it does not take 20 seconds for every download. The host PC polls the target PC about once every second, and if a response is returned, declares success. Only in the case where a download really fails it does take the full 20 seconds.

If the file `xpcd1timeout.dat` exists, it is read once before every download. To change the timeout value, change the number in this file. Setting the timeout to 5 is the same as the default. Note also that simply removing the file does not change the timeout to the default value. xPC Target uses the last value you entered until you restart MATLAB.

## xPC Target Options

Following is a description of the fields in the **xPC Target options** node. To access this node, from the model, select **Simulation -> Configuration Parameters**. In the left pane, click the **xPC Target options** node.

You might need to enter and select these options before you create (build) a target application. However, this is not normally necessary because the parameters have reasonable defaults.



**Execution mode** — From the list select either Real-Time or Freerun.

**Real-time interrupt source** — From the list select Timer or a number from 5 to 15.

**I/O board generating the interrupt** — From the list, select the board interrupt source.

**PCI slot/ISA base address** — Enter the slot number or base address for the I/O board generating the interrupt. The PCI slot can be either -1 (let xPC Target determine the slot number) or of the form [bus, slot]. The base address is a hexadecimal number of the form 0x300.

To determine the bus and PCI slot number of the boards in the target PC, in the MATLAB window, type `getxpcpci`.

**Log Task Execution Time** — Select this check box to log task execution times to the target object property `tg.TETlog`.

**Signal logging buffer size in doubles** — Enter the maximum number of sample points to save before wrapping. Your target application uses this buffer to store the time, states, outputs, and task execution time logs as defined in your Simulink model.

For example, the model `xpc_osc2.mdl` has six data items (one time, two states, two outputs, and one task execution time (TET)). If you enter a buffer size of 100000, then the target object property `tg.MaxLogSamples` is calculated as  $\text{floor}(100000 / 6) = 16666$ . After saving 16666 sample points, the buffer wraps and further samples overwrite the older ones.

If you select a logging buffer size larger than the available RAM on the target PC, after downloading and initializing the target application, the target PC displays a message, `ERROR: allocation of logging memory failed`. In this case you need to install more RAM or reduce the buffer size for logging. In any case you must reboot the target PC.

**Double buffer parameter changes** — Selecting this option changes parameter tuning so that the process of changing parameters in the target application uses a double buffer:

- When a parameter change request is received, the new value is compared to the old one. If the new value is identical to the old one, it is discarded, and if different, queued.
- At the start of execution of the next sample of the real-time task, all queued parameters are updated. This means that parameter tuning affects the task execution time (TET), and the very act of parameter tuning can cause a CPU overload error.

Double buffering leads to a more robust parameter tuning interface, at the cost of increased TET and a higher probability of overloads. You should normally clear this check box. It is cleared by default.

**Build COM objects from tagged signals/parameters** — If you select this check box, the build process creates a model-specific COM library file:

```
<model_name>COMiface.dll
```

Use this file to create custom GUI interfaces with Visual Basic or other tools that can use COM objects.

**Name of xPC Target object created by build process** — Enter the name of the target object created by the build process. The default target object name is tg.



## Running the Target Application

During the build process, xPC Target creates a target object that represents the target application running on the target PC. The target object is defined by a set of properties and associated methods. You control the target application and computer by setting the target object properties. This section includes the following topics:

- “Control with xPC Target Explorer” on page 3-51— Use xPC Target Explorer to change target application parameters, add xPC Target scopes, and select and log signals from your target application.
- “Control with MATLAB Commands” on page 3-55 — Start and stop the target application, view the status, change the stop time and sample time, and download a new target application.
- “Control with Simulink External Mode” on page 3-56 — Connect a Simulink model to an xPC Target application for parameter tuning.

### Control with xPC Target Explorer

This procedure assumes you have created an xPC Target boot disk and you have booted the target PC. See “Target Boot Disk” on page 2-40. While the xPC Target Explorer gives you access to build and download a target application, this procedure begins with a target application already downloaded to the target PC (see “xPC Target Application” on page 3-38).

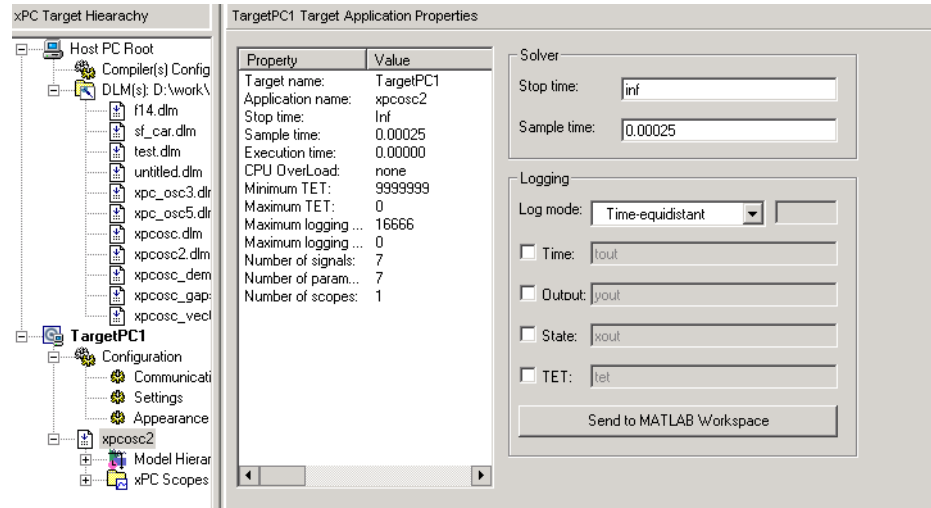
- 1 In the MATLAB window, type

```
xpcexplr
```

The **xPC Target Explorer** window opens.

- 2 To connect to the target PC, right-click the target PC icon for which you have downloaded the application and select Connect.

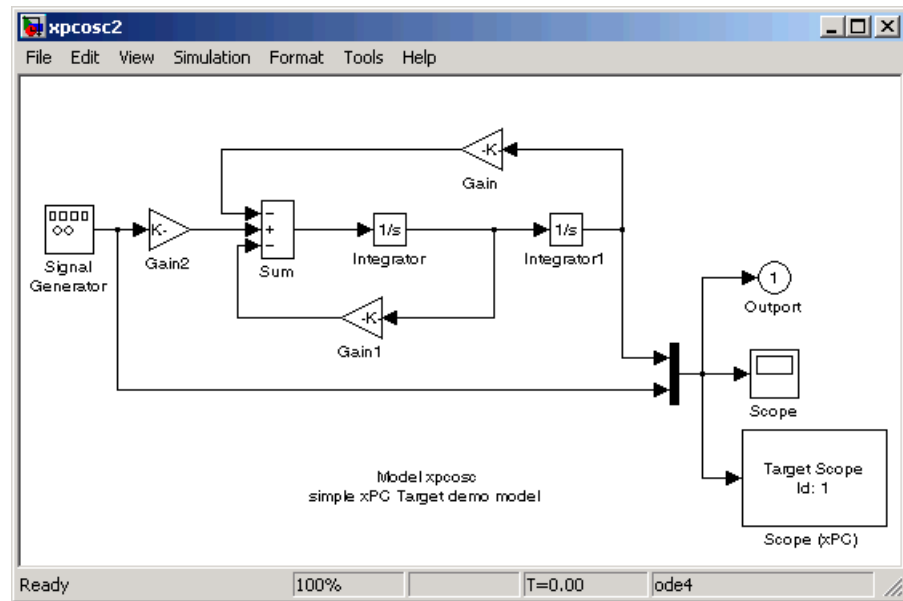
A node for the target application appears in the **xPC Target Hierarchy** under the target PC node and displays information about the previously loaded target application.



Note, if, in your current directory, you have a prebuilt target application that you want to download to the target PC, left-click and drag the desired target application to the target PC to which you want to download the target application.


- 3 If you want to rebuild the current target application, in the xPC Target Explorer window, right-click the target application node and select **Go To Simulink Model**.

The Simulink window opens for that model.

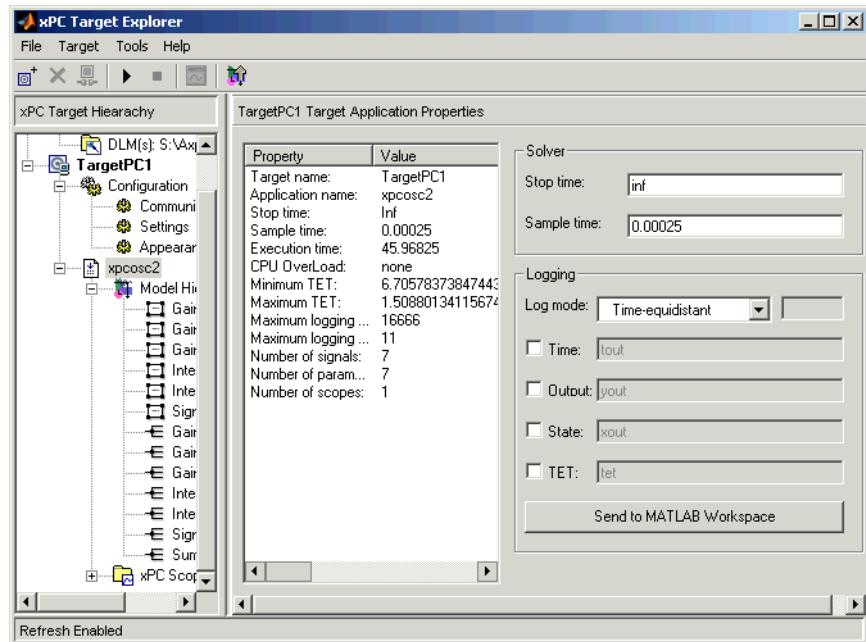


- 4 To rebuild the target application, in the Simulink window and from the **Tools** menu, select **Real-Time Workshop**. From the **Real-Time Workshop** submenu, click **Build Model**.

xPC Target recompiles, links, and downloads the target application to the target PC.

- 5 Start the target application. For example, in the xPC Target Explorer window, select the downloaded target application.
- 6 From the toolbar, click the **Start application** button . The target application begins running on the target PC, and stops when it reaches the stop time.
- 7 With the target application still selected in the Target Hierarchy pane of xPC Target Explorer, enter a new value for the **Stop time** value for the application and press **Enter**. For example

inf



**8** Again, click the **Start application** button. The target application now runs until you stop it.

**9** From the toolbar, click the **Stop application** button .

See also “Signal Tracing with xPC Target Explorer,” “Signal Logging with xPC Target Explorer,” and “Signal Logging with xPC Target Explorer” in Signals and Parameters of the xPC Target User’s Guide documentation.

## Control with MATLAB Commands

You run your target application in real time to observe the behavior of your model with generated code.

After xPC Target downloads your target application to the target PC, you can run the target application. This procedure uses the Simulink model `xpc_osc3.mdl` as an example, and assumes you have created and downloaded the target application for that model. The default name of the target object is `tg`.

- 1 In the MATLAB window, type any of  
`+tg` or `tg.start` or `start(tg)`

The target application starts running on the target PC. In the MATLAB window, the status of the target object changes from stopped to running.

```
xPC Object
  Connected    = Yes
  Application  = xpc_osc3
  Mode        = Real-Time Single-Tasking
  Status      = running
```

On the target PC screen, the **Execution** line changes from stopped to running and the **AverageTET** line is periodically updated with a new value.

Loaded App: <code>xpc_osc3</code>	Scope: 1, lower y-axis limit set to 0.000000
Memory: 123MB	Scope: 1, upper y-axis limit set to 0.000000
Mode: RT, single	System: initializing application finished
Logging: t x y tet	System: execution started (sample time: 0.000250)
StopTime: 10000 d	System: execution stopped at 10.191750
SampleTime: 0.00025	Scope: 1, set to state 'Interrupted'
AverageTET: 6.859e-006	minimal TET: 0.000006 at time 0.006250
Execution: 10.00 s	maximal TET: 0.000017 at time 0.097750
	System: execution started (sample time: 0.000250)

- 2 In the MATLAB window, type  
`-tg` or `tg.stop` or `stop(tg)`

The target application stops running.

xPC Target allows you to change many properties and parameters without rebuilding your target application. Two of these properties are `StopTime` and `SampleTime`.

- 3** Change the stop time. For example, to change the stop time to 1000 seconds, type either

```
tg.StopTime = 1000 or set(tg, 'StopTime', 1000)
```

- 4** Change the sample time. For example, to change the sample time to 0.01 seconds, type either

```
tg.SampleTime = 0.01 or set(tg, 'SampleTime', 0.01)
```

Although you can change the sample time in between different runs, you can only change the sample time without rebuilding the target application under certain circumstances.

If you choose a sample time that is too small, a CPU overload can occur. If a CPU overload occurs, the target object property `CPUOverload` changes to detected. In that case, change the **Fixed step size** in the **Solver** node to a larger value and rebuild the model.

## Control with Simulink External Mode

Control of your xPC Target application with Simulink is limited to connecting a Simulink model to a target application through external mode, and starting the target application. Using Simulink external mode is one method to tune parameters.

After you create and download a target application to the target PC, you can run the target application. This procedure uses the Simulink model `xpc_osc2.mdl` as an example (see “Building and Downloading the Target Application” on page 3-44).

- 1** In the Simulink window, and from the **Simulation** menu, click **External**.

A check mark appears next to the menu item **External**, and Simulink external mode is activated. Simulink external mode connects your Simulink model to your target application as a simple graphical user interface.

- 2** In the Simulink window, and from the **Simulation** menu, click **Connect to target**.

All the current Simulink model parameters are downloaded to your target application. This downloading guarantees the consistency of the parameters between the host model and the target application.

The target PC displays the following message, where # is the actual number of tunable parameters in your model:

```
ExtM: Updating # parameters
```

- 3** From the **Simulation** menu, click **Start real-time code**.

The **StopTime** is changed to 99999999 seconds, the target application begins running, and the target PC displays the following message:

```
System: execution started (sample time: 0.000250)
```

- 4** In the MATLAB window, type

```
tg.stop or -tg
```

---

**Note** You cannot stop the target application from the Simulink window by clicking **Stop real-time code** from the **Simulation** menu.

---





<b>application</b>	See target application.
<b>build process</b>	Process of generating a target application from your Simulink model, compiling, linking, and downloading the generated code to create a <i>target application</i> .
<b>execution</b>	Running the <i>target application</i> on the target PC in real time.
<b>executable code</b>	See target application.
<b>kernel</b>	Real-time software component running on the target PC that manages the downloaded <i>target application</i> .
<b>model</b>	Simulink/Stateflow model.
<b>parameter tuning</b>	Process of changing block parameters and downloading the new values to a <i>target application</i> while it is running or not running.
<b>sample rate</b>	Rate the <i>target application</i> is stepped in samples/second. Reciprocal of the <i>sample time</i> .
<b>sample time</b>	Interval, in seconds, between the execution of <i>target application</i> steps.
<b>signal logging</b>	Acquiring and saving signal data created during a real-time execution.
<b>signal monitoring</b>	Getting the values of one or more signals without time information.
<b>signal tracing</b>	Acquiring and displaying packages of signal data during real-time execution.
<b>simulation</b>	Running a simulation of the Simulink and Stateflow model on the host PC in nonreal time.
<b>target application</b>	Executable code generated from a Simulink and Stateflow model, which can be executed by the xPC Target kernel on the target PC.



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