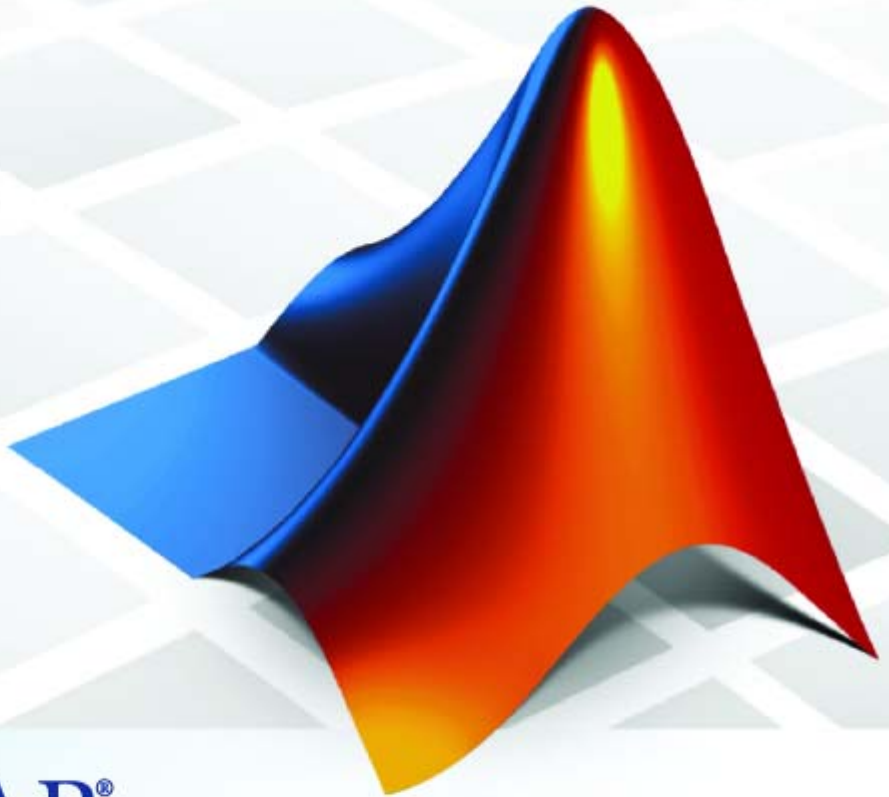


Real-Time Workshop[®] 7

User's Guide



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Real-Time Workshop® User's Guide

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Understanding Real-Time Workshop®

1

Product Overview	1-2
About Real-Time Workshop	1-2
Some Real-Time Workshop Capabilities	1-3
Software Design with Real-Time Workshop	1-4
Rapid Prototyping Process	1-6
About Rapid Prototyping	1-6
Key Aspects of Rapid Prototyping	1-6
Rapid Prototyping for Digital Signal Processing	1-10
Rapid Prototyping for Control Systems	1-11
Open Architecture of Real-Time Workshop	1-13
About Real-Time Workshop Architecture	1-13
Support for C and C++ Code Generation	1-16
Support for International (Non-US-ASCII) Characters ...	1-18
Where to Find Help	1-21
Introduction	1-21
Getting Started	1-21
How Do I...	1-21
Summary of Real-Time Workshop Limitations	1-27

Code Generation and the Build Process

2

Choosing and Configuring Your Target	2-3
Introduction	2-3
Selecting a System Target File	2-4
Selecting a System Target File Programmatically	2-5
Available Targets	2-6

Creating Custom Targets	2-10
Template Makefiles and Make Options	2-10
Choosing and Configuring a Compiler	2-19
Introduction	2-19
Real-Time Workshop and ANSI C/C++ Compliance	2-19
C++ Target Language Considerations	2-20
Choosing and Configuring Your Compiler on Windows ...	2-20
Choosing and Configuring Your Compiler on UNIX	2-21
Including S-Function Source Code	2-21
Adjusting Simulation Configuration Parameters for	
Code Generation	2-23
Introduction	2-23
Configuring the Solver	2-23
Configuring a Model for Data Logging	2-25
Configuring Optimizations	2-28
Configuring Diagnostics	2-28
Configuring Hardware Properties and Constraints	2-30
Configuring Referenced Models	2-39
Simulink and Real-Time Workshop Interactions to	
Consider	2-40
Configuring Real-Time Workshop Code Generation	
Parameters	2-49
Introduction	2-49
Opening the Real-Time Workshop Pane	2-50
Selecting a Target Configuration	2-51
Configuring the Target Language for Generated Code ...	2-52
Configuring Report Generation	2-52
Configuring the Build Process	2-53
Configuring Code Comments	2-56
Configuring Generated Identifiers	2-57
Configuring Custom Code	2-60
Troubleshooting the Build Process	2-61
Configuring Model Interfaces	2-63
Selecting and Viewing Target Function Libraries	2-68
Configuring Generated Code with TLC	2-77
Introduction	2-77
Assigning Target Language Compiler Variables	2-77
Setting Target Language Compiler Options	2-79

Interacting with the Build Process	2-81
Introduction	2-81
Initiating the Build Process	2-81
Construction of Symbols	2-82
Generated Source Files and File Dependencies	2-84
Reloading Code from the Model Explorer	2-104
Rebuilding Generated Code	2-104
Profiling Generated Code	2-105
Customizing the Build Process	2-108
Controlling the Compiling and Linking Phases of the Build Process	2-108
Cross-Compiling Code Generated on Windows	2-109
Controlling the Location and Naming of Libraries During the Build Process	2-112
Recompiling Precompiled Libraries	2-117
Customizing Post Code Generation Build Processing	2-117
Validating Generated Code	2-123
Viewing Generated Code	2-123
Tracing Generated Code Back to Your Simulink Model ...	2-125
Getting Model Optimization Advice	2-127
Integrating Legacy and Custom Code	2-129
Introduction	2-129
Block-Based Integration	2-129
Model or Target-Based Integration	2-131
Relocating Code to Another Development Environment	2-134
Introduction	2-134
Deciding on a Structure for the Zip File	2-134
Deciding on a Name for the Zip File	2-135
Packaging Model Code Files in a Zip File	2-136
Inspecting the Generated Zip File	2-137
Relocating and Unpacking the Zip File	2-137
Code Packaging Example	2-137
packNGo Function Limitations	2-138

Generated Code Formats

3

Introduction	3-2
Targets and Code Formats	3-3
Introduction	3-3
Backwards Compatibility of Code Formats	3-4
How Symbols Are Formatted in Generated Code	3-7
Choosing a Code Format for Your Application	3-10
Real-Time Code Format	3-14
Introduction	3-14
Unsupported Blocks	3-14
System Target Files	3-15
Template Makefiles	3-15
Real-Time malloc Code Format	3-16
Introduction	3-16
Unsupported Blocks	3-16
System Target Files	3-17
Template Makefiles	3-17
S-Function Code Format	3-18
Embedded Code Format	3-18
Introduction	3-18
Using the Real-Time Model Data Structure	3-19
Making GRT-Based Targets ERT-Compatible	3-21

Building Subsystems and Working with Referenced Models

4

Nonvirtual Subsystem Code Generation	4-2
Introduction	4-2

Nonvirtual Subsystem Code Generation Options	4-3
Modularity of Subsystem Code	4-14
Code Reuse Limitations	4-15
Determining Why Subsystem Code Is Not Reused	4-15
Generating Code and Executables from Subsystems ..	4-23
Generating Code for Model Referencing	4-26
Introduction	4-26
Overview of Referenced Model Code Generation	4-26
Project Directory Structure for Model Reference Targets ..	4-28
Building Model Reference Targets	4-28
Real-Time Workshop Model Referencing Requirements ..	4-29
Storage Classes for Signals Used with Model Blocks	4-36
Inherited Sample Time for Referenced Models	4-40
Reusable Code and Referenced Models	4-41
Customizing the Library File Suffix, Including the File Type Extension	4-45
Real-Time Workshop Model Referencing Limitations	4-45
Sharing Utility Functions	4-49
Introduction	4-49
Controlling Shared Utility Generation	4-49
rtwtypes.h and Shared Utilities	4-50
Incremental Shared Utility Generation and Compilation ..	4-51
Shared Utility Checksum	4-51
Shared Fixed-Point Utilities	4-53
Supporting Shared Utility Directories in the Build	
Process	4-55
Modifying Template Makefiles to Support Shared Utilities	4-56

Working with Data Structures

5

Parameter Storage, Interfacing, and Tuning	5-2
Introduction	5-2
Nontunable Parameter Storage	5-3

Tunable Parameter Storage	5-5
Tunable Parameter Storage Classes	5-7
Using the Model Parameter Configuration Dialog Box ...	5-10
Tunable Expressions	5-14
Linear Block Parameter Tunability	5-18
Parameter Configuration Quick Reference Diagram	5-19
Generated Code for Parameter Data Types	5-20
Tunable Workspace Parameter Data Type Considerations	5-26
Parameter Tuning by Using MATLAB Commands	5-28
Signal Storage, Optimization, and Interfacing	5-31
Introduction	5-31
Signal Storage Concepts	5-32
Signals with Auto Storage Class	5-34
Declaring Test Points	5-39
Interfacing Signals to External Code	5-40
Symbolic Naming Conventions for Signals in Generated Code	5-42
Summary of Signal Storage Class Options	5-43
Parameter Tuning and Signal Monitoring	5-45
Introduction	5-45
Using the C-API to Tune Parameters and Monitor Signals	5-45
Using the Target Language Compiler API to Tune Parameters and Monitor Signals	5-45
Simulink Data Objects and Code Generation	5-46
Introduction	5-46
Parameter Objects	5-47
Parameter Object Configuration Quick Reference Diagram	5-54
Signal Objects	5-55
Using Signal Objects to Initialize Signals and Discrete States	5-60
Resolving Conflicts in Configuration of Parameter and Signal Objects	5-69
Customizing Code for Parameter and Signal Objects	5-71
Using Objects to Export ASAP2 Files	5-71
Block State Storage and Interfacing	5-72

Introduction	5-72
Block State Storage	5-72
Block State Storage Classes	5-73
Using the State Properties Dialog Box to Interface States to External Code	5-74
Symbolic Names for Block States	5-76
Block States and Simulink Signal Objects	5-79
Summary of State Storage Class Options	5-80
Storage Classes for Data Store Memory Blocks	5-82
Data Store Memory and Simulink Signal Objects	5-84

External Mode

6

Introduction	6-2
Using the External Mode User Interface	6-3
External Mode Interface Options	6-3
External Mode Related Menu and Toolbar Items	6-6
External Mode Control Panel	6-11
Target Interfacing	6-13
External Signal Uploading and Triggering	6-15
Data Archiving	6-20
Parameter Downloading	6-22
External Mode Compatible Blocks and Subsystems ...	6-25
Compatible Blocks	6-25
Signal Viewing Subsystems	6-25
External Mode Communications Overview	6-28
Introduction	6-28
The Download Mechanism	6-28
Inlined and Tunable Parameters	6-30
Client/Server Implementations	6-32
Introduction	6-32
Using the TCP/IP Implementation	6-32
Using the Serial Implementation	6-35

Running the External Program	6-37
Implementing an External Mode Protocol Layer	6-39
Using External Mode Programmatically	6-40
External Mode Limitations	6-46
Limitations on Changing Parameters	6-46
Limitation on Mixing 32-bit and 64-bit Architectures	6-47

Program Architecture

7

Introduction	7-2
Model Execution	7-4
Introduction	7-4
Models for Non-Real-Time Single-Tasking Systems	7-6
Models for Non-Real-Time Multitasking Systems	7-7
Models for Real-Time Single-Tasking Systems	7-8
Models for Real-Time Multitasking Systems	7-9
Models for Multitasking Systems that Use Real-Time Tasking Primitives	7-12
Program Timing	7-13
Program Execution	7-14
External Mode Communication	7-15
Data Logging in Single-Tasking and Multitasking Model Execution	7-15
Rapid Prototyping and Embedded Model Execution Differences	7-16
Rapid Prototyping Model Functions	7-17
Embedded Model Functions	7-23
Rapid Prototyping Program Framework	7-24
Introduction	7-24
Rapid Prototyping Program Architecture	7-24
Rapid Prototyping System-Dependent Components	7-25
Rapid Prototyping System-Independent Components	7-27
Rapid Prototyping Application Components	7-30

Models with Multiple Sample Rates

8

Introduction	8-2
Single-Tasking and Multitasking Execution Modes ...	8-4
Introduction	8-4
Executing Multitasking Models	8-6
Multitasking and Pseudomultitasking Modes	8-7
Building a Program for Multitasking Execution	8-10
Single-Tasking Mode	8-10
Building a Program for Single-Tasking Execution	8-11
Model Execution and Rate Transitions	8-11
Simulating Models with Simulink	8-12
Executing Models in Real Time	8-12
Single-Tasking Versus Multitasking Operation	8-13
Sample Rate Transitions	8-14
Introduction	8-14
Data Transfer Problems	8-16
Data Transfer Assumptions	8-17
Rate Transition Block Options	8-17
Faster to Slower Transitions in Simulink	8-21
Faster to Slower Transitions in Real Time	8-22
Slower to Faster Transitions in Simulink	8-24
Slower to Faster Transitions in Real Time	8-25
Single-Tasking and Multitasking Execution of a Model: an Example	8-28
Introduction	8-28
Single-Tasking Execution	8-29
Multitasking Execution	8-31

Optimization Parameters Overview	9-3
Optimizing Models	9-5
Using the Model Advisor	9-5
Demos Illustrating Optimizations	9-5
Other Optimization Tools and Techniques	9-5
Minimizing Computations and Storage for Intermediate Results	9-9
Introduction	9-9
Expression Folding Example	9-10
Using and Configuring Expression Folding	9-11
Block Diagram Performance Tuning	9-16
Introduction	9-16
Lookup Tables and Polynomials	9-16
Reducing the Number of Blocks in a Model	9-29
Optimizing Code for Switch Blocks	9-33
Optimizing Data Type Usage	9-34
Additional Integer and Fixed-Point Optimizations	9-38
Optimizing Signals	9-40
Implementing Logic Signals as Boolean Data	9-40
Reducing Memory Requirements for Signals	9-40
Declaring Signals as Local Function Data	9-41
Reusing Memory Allocated for Signals	9-41
Inlining Invariant Signals	9-41
Inlining Parameters	9-43
Referenced Models	9-44
Configuring a Loop Unrolling Threshold	9-45
Controlling Memory Allocation for Time Counters	9-47

Optimizing Code Resulting from Floating-Point to Integer Conversions	9-48
Optimization Dependencies	9-50

Writing S-Functions for Real-Time Workshop Code Generation

10

Introduction	10-3
About S-Functions	10-3
Additional Information	10-4
Classes of Problems Solved by S-Functions	10-4
Types of S-Functions	10-5
Basic Files Required for Implementation	10-7
Writing Noninlined S-Functions	10-9
About Noninlined S-Functions	10-9
Noninlined S-Function Parameter Type Limitations	10-9
Writing Wrapper S-Functions	10-11
About Wrapper S-Functions	10-11
MEX S-Function Wrapper	10-11
TLC S-Function Wrapper	10-16
The Inlined Code	10-21
Writing Fully Inlined S-Functions	10-22
Multiport S-Function Example	10-22
Using the Legacy Code Tool to Automate the Generation of Files for Fully Inlined S-Functions	10-24
Legacy Code Tool and Code Generation	10-24
Generating File for Code Generation Support	10-25
Addressing Dependencies on Files in Different Locations	10-25
Deploying Generated S-Functions for Simulation and Code Generation	10-26

Writing Fully Inlined S-Functions with the mdlRTW	
Routine	10-27
About S-Functions and mdlRTW	10-27
S-Function RTWdata	10-28
The Direct-Index Lookup Table Algorithm	10-29
The Direct-Index Lookup Table Example	10-30
Writing S-Functions That Support Expression	
Folding	10-53
Introduction	10-53
Categories of Output Expressions	10-54
Acceptance or Denial of Requests for Input Expressions ..	10-59
Utilizing Expression Folding in Your TLC Block	
Implementation	10-63
Writing S-Functions That Specify Sample Time	
Inheritance Rules	10-69
Writing S-Functions That Support Code Reuse	10-71
Writing S-Functions for Multirate Multitasking	
Environments	10-72
Introduction	10-72
Rate Grouping Support in S-Functions	10-72
Creating Multitasking-Safe, Multirate, Port-Based Sample	
Time S-Functions	10-73
Integrating C and C++ Code	10-80
Build Support for S-Functions	10-81
Introduction	10-81
Implicit Build Support	10-82
Specifying Additional Source Files for an S-Function	10-82
Using TLC Library Functions	10-84
Using the rtwmakecfg.m API	10-84

Introduction	11-3
S-Function Target Overview	11-3
Intellectual Property Protection for S-Function in Simulation	11-4
Required Files for S-Function Deployment	11-4
Sample Time Propagation in Generated S-Functions	11-5
Choice of Solver Type	11-5
Creating an S-Function Block from a Subsystem	11-6
Tunable Parameters in Generated S-Functions	11-12
Automated S-Function Generation	11-15
System Target File and Template Makefiles	11-20
Introduction	11-20
System Target File	11-20
Template Makefiles	11-20
Checksums and the S-Function Target	11-21
S-Function Target Limitations	11-22
Run-Time Parameters and S-Function Compatibility Diagnostics	11-22
Goto and From Block Limitations	11-22
Building and Updating Limitations	11-24
Unsupported Blocks	11-24

Introduction	12-2
About Rapid Simulation	12-2

Licensing Protocols for Simulink Solvers in RSim	
Executables	12-3
Rapid Simulation Performance	12-4
General Rapid Simulation Workflow	12-5
Identifying Your Rapid Simulation Requirements	12-7
Configuring Inport Blocks to Provide Rapid Simulation	
Source Data	12-9
Configuring and Building a Model for Rapid	
Simulation	12-10
Setting Up Rapid Simulation Input Data	12-14
Introduction	12-14
Creating a MAT-File That Includes a Model's Parameter	
Structure	12-15
Creating a MAT-File for a From File Block	12-19
Creating a MAT-File for an Inport Block	12-19
Programming Scripts for Batch and Monte Carlo	
Simulations	12-25
Running Rapid Simulations	12-26
Introduction	12-26
Requirements for Running Rapid Simulations	12-28
Setting a Clock Time Limit for a Rapid Simulation	12-29
Overriding a Model's Simulation Stop Time	12-29
Reading the Parameter Vector into a Rapid Simulation ...	12-30
Specifying New Signal Data File for a From File Block ...	12-31
Specifying Signal Data File for an Inport Block	12-33
Changing Block Parameters for an RSim Simulation	12-37
Specifying a New Output Filename for a Simulation	12-38
Specifying New Output Filenames for To File Blocks	12-39
Rapid Simulation Target Limitations	12-40

Resources for Tornado Applications	13-2
Introduction	13-2
Tornado Environment	13-2
Tornado Target	13-3
VxWorks Block Library	13-3
Tornado Application Architecture	13-4
Hardware Architecture	13-4
Software Architecture	13-5
Module Architecture	13-6
Host Processes	13-6
VxWorks Tasks	13-7
Installing the Tornado Software	13-10
Introduction	13-10
Installing and Configuring Tornado	13-10
Connecting to the VxWorks Target	13-10
Verifying the Tornado Installation	13-11
Implementing a Tornado Application	13-12
Designing the Simulink Model	13-12
Adding Device Driver Blocks	13-12
Specifying Code Generation Options	13-13
Configuring the Template Makefile	13-19
Building the Application	13-21
Automatic Download and Execution	13-21
Manual Download and Execution	13-22
Introduction	13-22
Resetting VxWorks	13-22
Downloading Files	13-22
Starting the Program	13-23

Inserting Custom Code Into Generated Code

14

Custom Code Library	14-2
Example: Using a Custom Code Block	14-6
Custom Code in Subsystems	14-9
Preventing User Source Code from Being Deleted from Build Directories	14-10

Timing Services

15

Absolute and Elapsed Time Computation	15-2
Introduction	15-2
Timers for Periodic and Asynchronous Tasks	15-3
Allocation of Timers	15-3
Integer Timers in Generated Code	15-3
Elapsed Time Counters in Triggered Subsystems	15-4
APIs for Accessing Timers	15-5
Introduction	15-5
C-API for S-Functions	15-5
TLC API for Code Generation	15-8
Elapsed Timer Code Generation Example	15-10

Asynchronous Support

16

Introduction	16-2
About Asynchronous Support	16-2

VxWorks Library Overview	16-2
Accessing the VxWorks Library	16-4
Generating Code with the VxWorks Library Blocks	16-4
Demos and Additional Information	16-4
Handling Interrupts	16-5
Generating Interrupt Service Routines	16-5
Spawning a VxWorks Task	16-13
Rate Transitions and Asynchronous Blocks	16-21
Introduction	16-21
Handling Rate Transitions for Asynchronous Tasks	16-23
Handling Multiple Asynchronous Interrupts	16-23
Using Timers in Asynchronous Tasks	16-27
Creating a Customized Asynchronous Library	16-30
Introduction	16-30
Async Interrupt Block Implementation	16-31
Task Sync Block Implementation	16-35
asynclib.tlc Support Library	16-36
Asynchronous Support Limitations	16-39

Data Exchange APIs

17

C-API for Interfacing with Signals and Parameters ...	17-2
Introduction	17-2
Generating C-API Files	17-3
Description of C-API Files	17-5
Using the C-API in an Application	17-16
C-API Limitations	17-20
Generating C-API and ASAP2 Files	17-21
Target Language Compiler API for Signals and Parameters	17-21

Creating an External Mode Communication	
Channel	17-23
Introduction	17-23
The Design of External Mode	17-23
External Mode Communications Overview	17-26
External Mode Source Files	17-28
Guidelines for Implementing the Transport Layer	17-31
Combining Multiple Models	17-35
Using GRT Malloc to Combine Models	17-36

Working with Embedded MATLAB Coder

18

About Embedded MATLAB Coder	18-3
Converts M-Code to C Code	18-3
Running a Demo of Embedded MATLAB Coder	18-4
How Embedded MATLAB Coder Resolves Function Calls	18-4
Workflows for Converting M-Code to C Code	18-5
Workflow for Converting M-Code to Embeddable C Code ..	18-5
Workflow for Converting M-Code to a C-MEX Function ..	18-6
Installing Prerequisite Products for Embedded MATLAB Coder	18-8
Setting Up the C Compiler	18-9
File Paths and Naming Conventions	18-10
Compile Path Search Order	18-10
Can I Add Files to the Embedded MATLAB Path?	18-10
When to Use the Embedded MATLAB Path	18-10
Adding Directories to Search Paths	18-11
Naming Conventions	18-11
Making M-Code Compliant with Embedded MATLAB	18-13

Debugging Strategies	18-13
Detecting Embedded MATLAB Syntax Violations at Compile Time	18-15
Configuring Your Environment for Code Generation ..	18-16
Types of Configuration Objects	18-16
Working with Configuration Objects	18-17
Creating Configuration Objects	18-18
Modifying Configuration Objects	18-19
Saving Configuration Objects	18-20
Specifying Properties of Primary Function Inputs	18-22
Why You Must Specify Input Properties	18-22
Properties to Specify	18-22
Rules for Specifying Properties of Primary Inputs	18-24
Methods for Defining Properties of Primary Inputs	18-24
Defining Input Properties by Example at the Command Line	18-25
Defining Input Properties Programmatically in the M-File	18-28
Choosing Your Target	18-37
Types of Targets	18-37
Specifying the Target to the Compiler	18-38
Relationship of Targets and Configuration Objects	18-38
Location of Generated Files	18-39
Specifying main Functions for C Executables	18-39
Compiling Your M-File	18-41
Before Compiling Your M-Code	18-41
Running Embedded MATLAB Coder	18-41
Generated Files and Locations	18-42
Specifying Custom Files to Build	18-42
Working with Compilation Reports	18-44
About Compilation Reports	18-44
Generating Compilation Reports	18-44
Names and Locations of Compilation Reports	18-44
Description of Compilation Reports	18-45
Examples of Reports	18-47

Calling Generated C Functions	18-51
Calling C Functions from the Embedded MATLAB	
Subset	18-51
Calling Initialize and Terminate Functions	18-52
Calling C Functions with Multiple Outputs	18-56
Calling C Functions that Return Arrays	18-56
Integrating Custom C Code with Generated Code	18-57
About Custom C Code Integration in Embedded	
MATLAB	18-57
Specifying Custom C Files on the Command Line	18-57
Specifying Custom C Files with Configuration Objects ...	18-57

Blocks That Depend on Absolute Time

A

Generating ASAP2 Files

B

Overview	B-3
Targets Supporting ASAP2	B-4
Defining ASAP2 Information	B-5
Memory Address Attribute	B-6
Generating an ASAP2 File	B-8
Introduction	B-8
Using Generic Real-Time Target or Embedded Coder	
Target	B-8
Using the ASAM-ASAP2 Data Definition Target	B-10
Customizing an ASAP2 File	B-12
Introduction	B-12
ASAP2 File Structure on the MATLAB Path	B-12

Customizing the Contents of the ASAP2 File	B-13
ASAP2 Templates	B-14
Structure of the ASAP2 File	B-19
Generating ASAP2 and C-API Files	B-21

Examples

C

Models	C-2
Model Code Packaging	C-2
Model Reference	C-2
Data Management	C-2
Optimizations	C-3
S-Functions	C-3
Custom Code	C-3
Timing Services	C-3
Interfaces	C-3

Index

Understanding Real-Time Workshop[®]

The following sections describe the architecture and application of Real-Time Workshop[®], and summarize the contents and organization of its documentation, giving an overview of its contents and some entry points into it for a number of topics of interest.

Product Overview (p. 1-2)

Highlights key Real-Time Workshop capabilities and explains how to apply Real-Time Workshop to Model-Based Design and deployment

Rapid Prototyping Process (p. 1-6)

Lists advantages of rapid prototyping and describes its application in two domains — digital signal processing and control systems

Open Architecture of Real-Time Workshop (p. 1-13)

Discusses ways of extending Real-Time Workshop capabilities, support for C and C++ code generation, and support for international characters

Where to Find Help (p. 1-21)

Identifies resources for basic descriptions and advanced information on specific topics

Summary of Real-Time Workshop Limitations (p. 1-27)

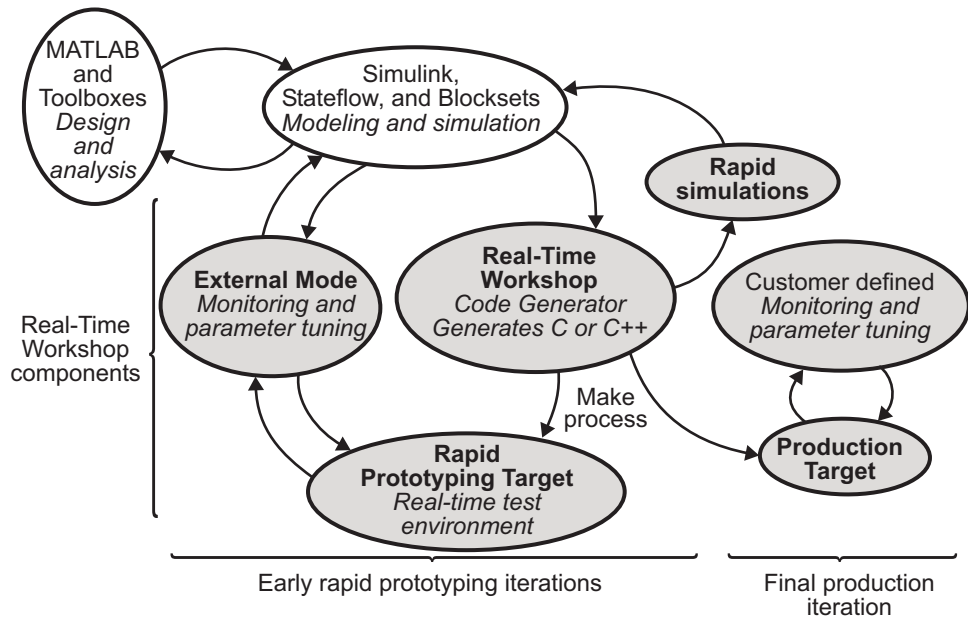
Lists product features that have documented limitations and provides cross references to details

Product Overview

In this section...
“About Real-Time Workshop” on page 1-2
“Some Real-Time Workshop Capabilities” on page 1-3
“Software Design with Real-Time Workshop” on page 1-4

About Real-Time Workshop

Real-Time Workshop generates optimized, portable, and customizable ANSI C or C++ code from Simulink® models to create standalone implementations of models that operate in real-time and non-real-time in a variety of target environments. Generated code can run on PC hardware, DSPs, microcontrollers on bare-board environments, and with commercial or proprietary real-time operating systems (RTOS). Real-Time Workshop lets you speed up simulations, build in intellectual property protection, and operate across a wide variety of real-time rapid prototyping targets. The next figure shows the role of Real-Time Workshop (shaded elements) in the software design process.



Software Design and Deployment Using MATLAB and Real-Time Workshop

Some Real-Time Workshop Capabilities

With Real-Time Workshop, you can quickly generate code for discrete-time, continuous-time (fixed-step), and hybrid systems, as well as for finite state machines modeled in Stateflow® using the optional Stateflow Coder. The optional Real-Time Workshop Embedded Coder works with Real-Time Workshop to generate efficient, embeddable source code. These core products support a growing set of embedded targets, such as Target for Freescale™ MPC5xx, Target for TI C6000™, and Target for Infineon C166®.

Real-Time Workshop is a key link in the set of system design tools provided by The MathWorks, providing a real-time development environment — a direct path from system design to hardware implementation. You can streamline application development and reduce costs with Real-Time Workshop by testing design iterations with real-time hardware. Real-Time Workshop supports the execution of dynamic system models on hardware by automatically converting models to code and providing model debugging

support. It is well suited for accelerating simulations, rapid prototyping, turnkey solutions, and production of embedded real-time applications.

Using integrated makefile-based targeting support, Real-Time Workshop builds programs that can help speed up your simulations, provide intellectual property protection, and run on a wide variety of real-time rapid prototyping or production targets. Simulink's external mode run-time monitor works seamlessly with real-time targets, providing an elegant signal monitoring and parameter tuning interface.

Software Design with Real-Time Workshop

A typical product cycle using MathWorks tools starts with modeling in Simulink, followed by an analysis of the simulations in MATLAB®. During the simulation process, you use the rapid simulation features of Real-Time Workshop to speed up your simulations.

After you are satisfied with the simulation results, you use Real-Time Workshop in conjunction with a rapid prototyping target, such as xPC Target. The rapid prototyping target is connected to your physical system. You test and observe your system, using your Simulink model as the interface to your physical target. Once you have verified that your simulation is functioning properly, you use Real-Time Workshop to transform your model to C or C++ code. An extensible make process and download procedure creates an executable for your model and places it on the target system. Finally, using external mode, you can monitor and tune parameters in real-time as your model executes on the target environment.

There are two broad classes of targets: rapid prototyping targets and embedded targets. Code generated for the rapid prototyping targets supports increased monitoring and tuning capabilities. Code generated for embedded targets is highly optimized and suitable for deployment in production systems, and can include application-specific entry points to monitor signals and tune parameters.

To support embedded targets, The MathWorks distributes Real-Time Workshop Embedded Coder as a separate product. Embedded Coder is an extension of Real-Time Workshop, designed to generate C or C++ code for embedded discrete-time systems, where efficiency, configurability, readability, and traceability of the generated code are extremely important. Real-Time

Workshop Embedded Coder enhances Real-Time Workshop code generation technology to generate embeddable ANSI or ISO C or C++ code that compares favorably with hand-optimized code in terms of performance, ROM code size, RAM requirements, and readability. See the Real-Time Workshop Embedded Coder documentation for information about optimization, specifically for embedded code.

Rapid Prototyping Process

In this section...
“About Rapid Prototyping” on page 1-6
“Key Aspects of Rapid Prototyping” on page 1-6
“Rapid Prototyping for Digital Signal Processing” on page 1-10
“Rapid Prototyping for Control Systems” on page 1-11

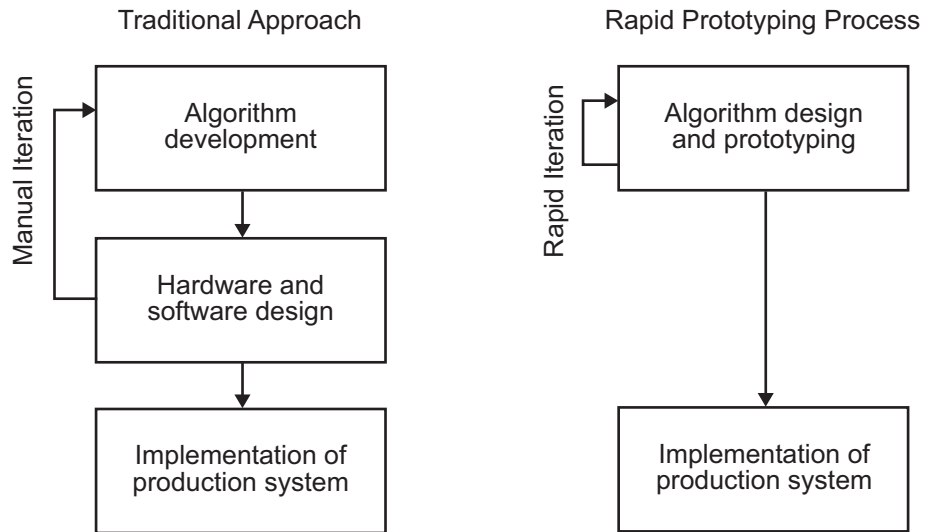
About Rapid Prototyping

Real-Time Workshop supports *rapid prototyping*, an application development process that allows you to

- Conceptualize solutions graphically in a block diagram modeling environment
- Evaluate system performance early on — before laying out hardware, coding production software, or committing to a fixed design
- Refine your design by rapid iteration between algorithm design and prototyping
- Monitor signals and tune parameters while your real-time model runs, using Simulink in external mode as a graphical front end

Key Aspects of Rapid Prototyping

The next figure contrasts the rapid prototyping development process with the traditional development process.



Traditional Versus Rapid Prototyping Development Processes

The traditional approach to real-time design and implementation typically involves multiple teams of engineers, including an algorithm design team, software design team, hardware design team, and an implementation team. When the algorithm design team has completed its specifications, the software design team implements the algorithm in a simulation environment and then specifies the hardware requirements. The hardware design team then creates the production hardware. Finally, the implementation team integrates the hardware into the larger overall system.

This traditional development process is time-consuming because algorithm designers often do not have access to the hardware that is actually deployed. The rapid prototyping process combines the algorithm, software, and hardware design phases, eliminating potential bottlenecks by allowing engineers to see results and rapidly iterate solutions before building expensive hardware.

Automating Programming

Automatic program building allows you to make design changes directly to the block diagram, putting algorithm development (including coding, compiling, linking, and downloading to target hardware) under control of a single process:

- Design a Model in Simulink

You begin the rapid prototyping process with the development of a model in Simulink. Using principles of control engineering, you model plant dynamics and other dynamic components that constitute a controller and/or an observer.

- Simulate your Model in Simulink

You use MATLAB, Simulink, and toolboxes to aid in the development of algorithms and analysis of the results. If the results are not satisfactory, you can iterate the modeling and analysis process until results are acceptable.

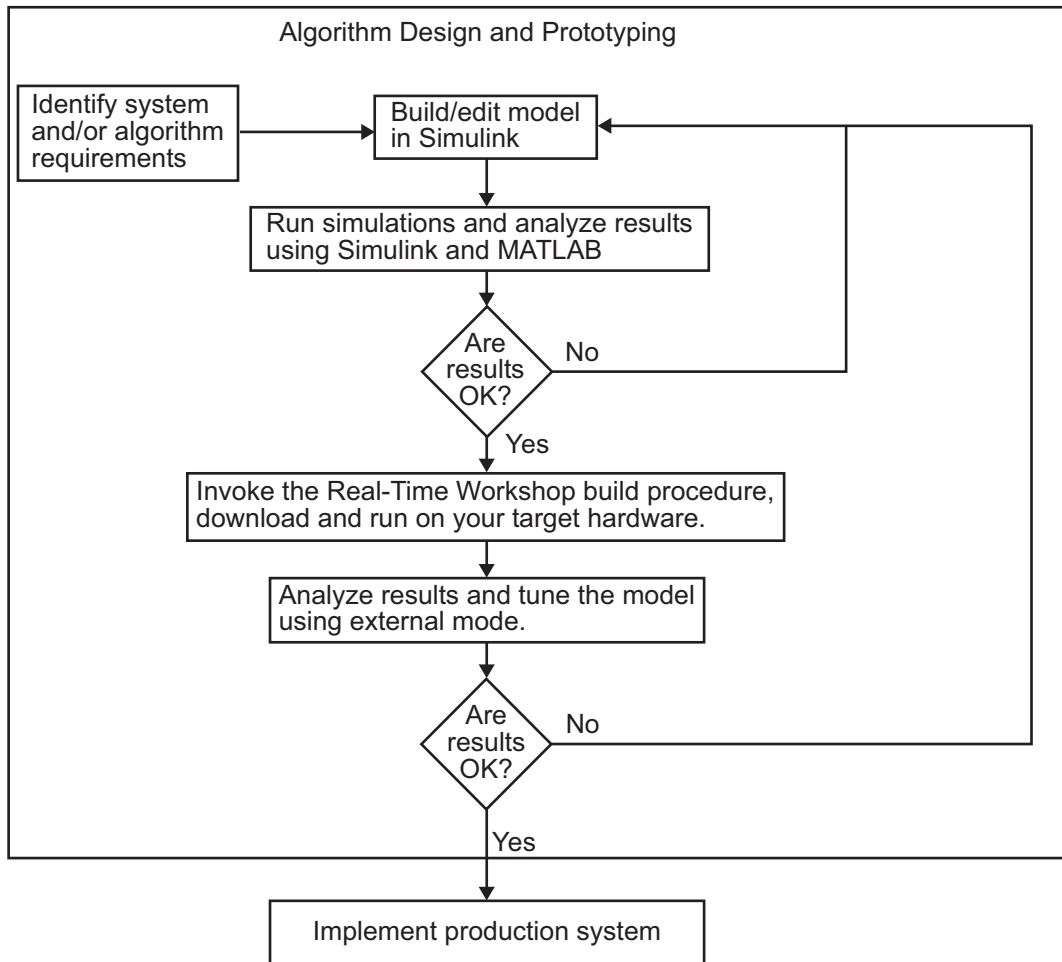
- Generate Source Code with Real-Time Workshop

Once simulation results are acceptable, you generate downloadable C or C++ code that implements the appropriate portions of the model. You can use Simulink in external mode to monitor signals, tune parameters, and further validate and refine your model, quickly iterating through solutions.

- Implement a Production Prototype

At this stage, the rapid prototyping process is complete. You can begin the final implementation for production with confidence that the underlying algorithms work properly in your real-time production system.

The next figure shows the flow of this process.



The Rapid Prototyping Development Process

Highly productive development cycles are possible due to the integration between MATLAB, Simulink, and Real-Time Workshop. Each component adds value to your application design process:

- MATLAB: Provides design, analysis, and data visualization tools.

- Simulink: Provides system modeling, simulation, and validation.
- Real-Time Workshop: Generates C or C++ code from Simulink model; provides framework for running generated code in real-time, tuning parameters, and monitoring real-time data.

Rapid Prototyping for Digital Signal Processing

The first step in the rapid prototyping process for digital signal processing is to consider the kind and quality of the data to be worked on, and to relate it to the system requirements. Typically this includes examining the signal-to-noise ratio, distortion, and other characteristics of the incoming signal, and relating them to algorithm and design choices.

System Simulation and Algorithm Design

In the rapid prototyping process, the block diagram plays two roles in algorithm development. The block diagram helps to identify processing bottlenecks, and to optimize the algorithm or system architecture. The block diagram also functions as a high-level system description. That is, the diagram provides a hierarchical framework for evaluating the behavior and accuracy of alternative algorithms under a range of operating conditions.

Analyzing Results, Tuning Parameters, and Monitoring Signals

After you create an algorithm (or a set of candidate algorithms), the next stage is to consider architectural and implementation issues. These include complexity, speed, and accuracy. In a conventional development environment, this would mean running the algorithm and recoding it in C or C++ or in a hardware design and simulation package.

Using Simulink external mode you can change parameters while your processing algorithms execute in real time on the target hardware. After building and downloading the executable to your hardware, you tune (modify) block parameters in Simulink, which downloads the new values to the hardware. You can monitor the effects of your parameter changes by connecting Scope blocks to signals that you want to observe.

Note Opening a dialog box for a source block causes Simulink to pause. While Simulink is paused, you can edit the parameter values. You must close the dialog box to have the changes take effect and allow Simulink to continue.

Rapid Prototyping for Control Systems

Rapid prototyping for control systems is similar to digital signal processing, with one major difference. In control systems design, you must model your plant prior to developing algorithms to simulate closed-loop performance. The process continues with the specification of a controller connected to the plant model. Once your plant model is sufficiently accurate, the rapid prototyping process for control system design continues in much the same manner as digital signal processing design.

Rapid prototyping begins with developing block diagram plant models of sufficient fidelity for preliminary system design and simulation. Once simulations indicate acceptable system performance levels, the controller block diagram is separated from the plant model and I/O device driver blocks are attached to it. Automatic code generation immediately converts the controller to real-time executable code, which can be automatically loaded onto target hardware.

Modeling Plants in Simulink

The first step in the design process is development of a plant model. Next, you specify a controller model to be connected to the plant model. The Simulink libraries of linear and nonlinear blocks help you construct models involving plant, sensor, and actuator dynamics. Because Simulink is customizable, you can further simplify modeling by creating custom blocks and block libraries from continuous- and discrete-time components.

Using System Identification Toolbox, you can analyze test data to develop an empirical plant model; or you can use Symbolic Math Toolbox to translate the equations of the plant dynamics into state-variable form.

Analyzing Simulation Results

You can use MATLAB and Simulink to analyze the results produced from a model developed in the first step of the rapid prototyping process. At this stage, you can design and add a controller to your plant.

Deriving and Analyzing Controller Algorithms

From the block diagrams developed during the modeling stage, you can extract state-space models through linearization techniques. These matrices can be used in control system design. You can use the following tools to facilitate control system design, and work with the matrices that you derived:

- Control System Toolbox
- Model Predictive Control Toolbox
- Robust Control Toolbox
- System Identification Toolbox
- SimMechanics

Once you have your controller designed, you can create a closed-loop system by connecting it to the Simulink plant model. Closed-loop simulations allow you to determine how well the initial design meets performance requirements.

Once you have a satisfactory model, it is a simple matter to generate C or C++ code directly from the controller block diagram, compile it for the target processor, and link it with supplied or user-written application modules. The plant model runs on the host platform, controlled by generated code on the target processor.

Analyzing Results, Tuning Parameters, and Monitoring Signals

You can load output data from your program into MATLAB for analysis, or display the data with third-party monitoring tools. You can easily make design changes to the Simulink model and then regenerate the C or C++ code.

Open Architecture of Real-Time Workshop

In this section...

“About Real-Time Workshop Architecture” on page 1-13

“Support for C and C++ Code Generation” on page 1-16

“Support for International (Non-US-ASCII) Characters” on page 1-18

About Real-Time Workshop Architecture

Real-Time Workshop is an open system designed for use with a wide variety of operating environments and hardware types. The figure Real-Time Workshop Architecture on page 1-15 shows how you can extend key elements of Real-Time Workshop.

You can configure the Real-Time Workshop program generation process to your own needs by modifying the following components:

- Simulink and the model file (*model.mdl*)

Simulink provides a very high-level language (VHLL) development environment. The language elements are blocks and subsystems that visually embody your algorithms. You can think of Real-Time Workshop as a compiler that processes a VHLL source program (*model.mdl*), and emits code suitable for a traditional high-level language (HLL) compiler.

S-functions written in C or C++ let you extend the Simulink VHLL by adding new general-purpose blocks, or incorporating legacy code into a block.

- The intermediate model description (*model.rtw*)

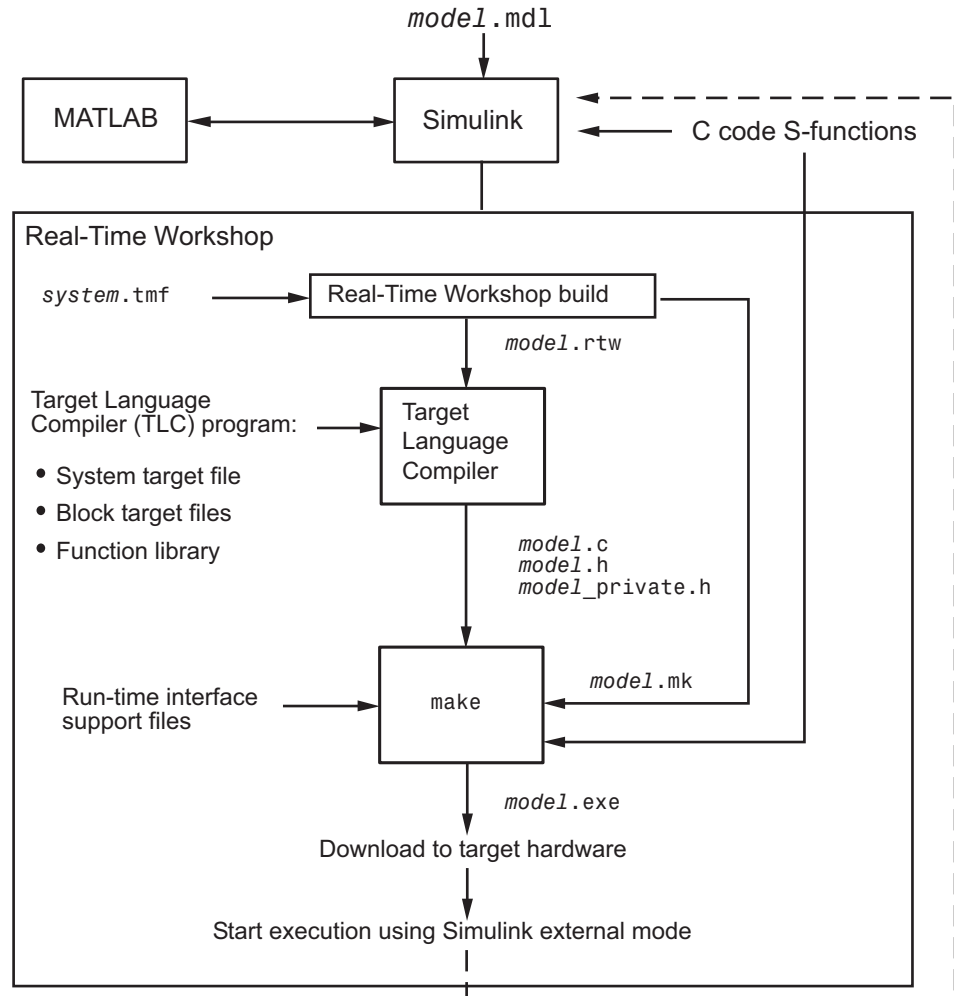
The initial stage of the code generation process is to analyze the source model. The resultant description file contains a hierarchical structure of records describing systems and blocks and their connections.

The S-function API includes a special function, `mdlRTW`, that lets you customize the code generation process by inserting parameter data from your own blocks into the *model.rtw* file.

- The Target Language Compiler (TLC) program

The Target Language Compiler interprets a program that reads the intermediate model description and generates code that implements the model as a program.

You can customize the elements of the TLC program in two ways. First, you can implement your own system target file, which controls overall code generation parameters. Second, you can implement block target files, which control how code is generated from individual blocks such as your own S-Function blocks.



Real-Time Workshop Architecture

- Source code generated from the model; for descriptions of these files, see Getting Started.

There are several ways to customize generated code, or interface it to custom code:

- Exported entry points let you interface your hand-written code to the generated code. This makes it possible to develop your own timing and

execution engine, or to combine code generated from several models into a single executable.

- You can automatically make signals, parameters, and other data structures within generated code visible to your own code, facilitating parameter tuning and signal monitoring.
 - Prepare or modify Target Language Compiler script files to customize the transformation of Simulink blocks into source code. See the Target Language Compiler documentation for more details.
- Run-time interface support files

The run-time interface consists of code interfacing to the generated model code. You can create a custom set of run-time interface files, including

- A harness (main) program
 - Code to implement a custom external mode communication protocol
 - Code that interfaces to parameters and signals defined in the generated code
 - Timer and other interrupt service routines
 - Hardware I/O drivers
- The template makefile and *model.mk*

A makefile, *model.mk*, controls the compilation and linking of generated code. Real-Time Workshop generates *model.mk* from a template makefile during the code generation and build process. You can create a custom template makefile to control compiler options and other variables of the make process.

All of these components contribute to the process of transforming a Simulink model into an executable program. The topics in the next section point you to documentation describing each of them.

Support for C and C++ Code Generation

Real-Time Workshop supports C and C++ code generation. The primary motivation for C++ support is to facilitate integration of generated code with legacy or custom user code written in C++. Consider the following as you choose a language for your generated code:

- Whether you need to configure Real-Time Workshop to use a specific compiler. This is required to generate C++ code on Windows. See “Choosing and Configuring a Compiler” on page 2-19.
- The language configuration setting for the model. See “Configuring the Target Language for Generated Code” on page 2-52.
- Whether you need to integrate legacy or custom code with generated code. For a summary of integration options, see “Integrating Legacy and Custom Code” on page 2-129.
- Whether you need to integrate C and C++ code. If so, see “Integrating C and C++ Code” on page 10-80.
- “C++ Target Language Limitations” on page 1-17.

For a demo, enter `sfcndemo_cppcount` in the MATLAB Command Window. For a Stateflow example, enter `sf_cpp`.

C++ Target Language Limitations

- Microsoft Visual C/C++, GNU C/C++, Watcom C/C++ and Borland® C/C++ compilers have been fully tested with V6.4 (R2006a) Real-Time Workshop and are fully supported on 32-bit Windows and 32/64-bit Linux platforms. However, V6.4 (R2006a) provides Beta C++ support only for the Intel® C/C++ compiler, which has not yet been fully evaluated for C++ compatibility with MathWorks products.
- Real-Time Workshop provides Beta support for C++ code generation for all blockset products. C++ code generation for other blockset products has not yet been fully evaluated.
- Real-Time Workshop does not support C++ code generation for the following:

- SimDriveline
- SimMechanics
- SimPowerSystems
- Target for Freescale™ MPC5xx
- Target for Infineon C166®
- Target for TI C2000™
- Target for TI C6000™

xPC Target

- When using the model reference feature, the language of the code generated for the top model and any referenced models must match. For example, if you generate C++ code for the top model, the generated code for all referenced models must also be C++ code.
 - The following Real-Time Workshop Embedded Coder dialog box fields currently do not accept the .cpp extension. However, a .cpp file will be generated if you specify a filename without an extension in these fields, with C++ selected as the target language for your generated code.
 - **Data definition filename** field on the **Data Placement** pane of the Configuration Parameters dialog box
 - **Definition file** field for an **mpt data object** in the Model Explorer
- These restrictions on specifying .cpp will be removed in a future release.

Support for International (Non-US-ASCII) Characters

Real-Time Workshop does not include non-US-ASCII characters in compilable portions of source code. However, Simulink, Stateflow, Real-Time Workshop, and Real-Time Workshop Embedded Coder do support non-US-ASCII characters in certain ways. When non-US-ASCII characters are encountered during code generation, they either become comments in the generated code or do not propagate into the generated source files. Sources of non-US-ASCII characters are described below:

- **Simulink Block Names:** The name of Simulink blocks are permitted to use non-US-ASCII character sets. The block name can be output in a comment above the generated code for that block when the **Simulink block comments** check box is selected. If Real-Time Workshop also uses the block name in the generated code as an identifier, the identifier's name will be changed to ensure only US-ASCII characters are present.

One exception to using non-US-ASCII characters in block names is for nonvirtual subsystems configured to use the subsystem name as either the function name or the filename. In this case, only US-ASCII characters can be used to name the subsystem.
- **User comments on Stateflow diagrams:** These comments can contain non-US-ASCII characters. They are written to the generated code when the **Include comments** check box is selected.

- Custom TLC files (.t1c): User-created Target Language Compiler files can have non-US-ASCII characters inside both TLC comments and in any code comments which are output. The Target Language Compiler does not support non-US-ASCII characters in TLC variable or function names.

Additional Support with Real-Time Workshop Embedded Coder

Users of Real-Time Workshop Embedded Coder have additional international character support:

- Simulink Block Description: Real-Time Workshop Embedded Coder propagates block descriptions entered from Simulink Block Parameter dialog boxes into the generated code as comments when the **Simulink block descriptions** check box on the **Real-Time Workshop/Comments** pane of the Configuration Parameters dialog box is selected. Non-US-ASCII characters are supported for these descriptions.
- Real-Time Workshop Embedded Coder code template file: Code Generation Template (.cgt) files provide customization capability for the generated code. Any output lines in the .cgt file which are C or C++ comments can contain non-US-ASCII characters, for example the file banner and file trailer sections; these comments are propagated to the generated code. However, although TLC comments in .cgt files can contain non-US-ASCII characters, these TLC comments are not propagated to the generated code.
- Stateflow object descriptions: Stateflow object descriptions can contain non-US-ASCII characters. The description will appear as a comment above the generated code for that chart when the **Stateflow object descriptions** check box is selected.
- Simulink Parameter Object Description: Simulink Parameter Object descriptions can contain non-US-ASCII characters. The description will appear as a comment above the generated code when the Simulink data object descriptions check box is selected.
- MPT Signal Object Description: MPT object descriptions can contain non-US-ASCII characters. The description will appear as a comment above the generated code when the Simulink data object descriptions check box is selected.

Character Set Limitation

You can encounter problems with models containing characters of a specific character set, such as Shift JIS, on a host system for which that character set is not configured as the default.

When models containing characters of a given character set are used on a host system that is not configured with that character set as the default, Simulink can incorrectly interpret characters during model loading and saving. This can lead to corrupted characters being displayed in the model and possibly the model failing to load. It can also lead to corrupted characters in the model file (.mdl) if you save it.

This limitation does not exist when the characters used in the model are in the default character set for the host system. For example, you can use Shift JIS characters with no issues if the host system is configured to use Japanese Windows.

Additionally, during code generation, the Target Language Compiler can have similar problems reading characters from either the *model.rtw* or user written *.tlc* files. This can result in corrupt characters in generated source file comments or a Target Language Compiler error.

For an example of international character set support for code generation, run the demo model *rtwdemo_international*. This demo model is set up to work around the character limitations described above. If you run this demo from a non-Japanese MATLAB host machine, you must set up an international character set for Simulink. For example, type

```
bdclose all; set_param(0, 'CharacterEncoding', 'Shift_JIS')
rtwdemo_international
```

Other uses of non-US-ASCII characters in models or in files used during the build process are not supported; you should not depend on any incidental functionality that may exist.

For additional information, see the description of `s1CharacterEncoding` in “Model Construction” in the Simulink documentation.

Where to Find Help

In this section...
“Introduction” on page 1-21
“Getting Started” on page 1-21
“How Do I...” on page 1-21

Introduction

Documentation for Real-Time Workshop and related products from The MathWorks covers many topics — some in considerable depth — and includes many examples of use. Some of the major topics covered are summarized below, enabling you to locate directly what you need to proceed.

Getting Started

If you are a less experienced user, see *Getting Started*, which introduces the product and describes its capabilities, applications, benefits, and general usage. Inside that guide are tutorials that provide immediate hands-on experience to get you familiar with the look, feel, and capabilities of Real-Time Workshop.

How Do I...

If you need specific details about how to use Real-Time Workshop, scan the topics and descriptions below to locate documentation relevant to your development tasks and interests. You can also search the index to find information not included in this list.

Operate the Real-Time Workshop User Interface

You control most aspects of code generation through the Real-Time Workshop tab of the Configuration Parameters dialog box, and the dialog boxes descending from it. See “Configuring Real-Time Workshop Code Generation Parameters” on page 2-49 for full descriptions of the options at your disposal.

Select Targets and Customize Compilation

Setting up targets for code generation is simple with the System Target File Browser, described in “Choosing and Configuring Your Target” on page 2-3. Look there also for information on configuring compilers (“Choosing and Configuring a Compiler” on page 2-19) and modifying makefiles (“Template Makefiles and Make Options” on page 2-10). For details on working with specific targets, see Chapter 11, “S-Function Target”, Chapter 12, “Running Rapid Simulations”, Chapter 13, “Targeting Tornado for Real-Time Applications”, Appendix B, “Generating ASAP2 Files”, and the Real-Time Workshop Embedded Coder documentation.

Generate Single-Tasking and Multitasking Code

Real-Time Workshop fully supports single-tasking and multitasking code generation. See Chapter 7, “Program Architecture”, Chapter 8, “Models with Multiple Sample Rates”, Chapter 15, “Timing Services”, and Chapter 16, “Asynchronous Support” for a more details.

Customize Generated Code

Real-Time Workshop supports customization of the generated code.

You can include Custom Code blocks in any system of any model to insert comments, include directives and code in specific functions. See Chapter 14, “Inserting Custom Code Into Generated Code”, for more information. You can also insert C or C++ code by using the Custom Code configuration set dialog box.

The most flexible approach to customizing generated code is to modify Target Language Compiler (TLC) files. The Target Language Compiler is an interpreted language that translates Simulink models into C or C++ code. Using the Target Language Compiler, you can direct the code generation process.

You can customize Real-Time Workshop generated code to include custom header files. See “Code Configuration Functions” in the Target Language Compiler documentation for details.

Optimize Generated Code

The default code generation settings are generic for flexible rapid prototyping systems. The penalty for this flexibility is code that is less than optimal. There are several optimization techniques that you can use to minimize the source code size and memory usage once you have a model that meets your requirements.

See Chapter 2, “Code Generation and the Build Process”, and Chapter 6, “External Mode”, to learn techniques for code optimization techniques available for all target configurations. Start by running Model Advisor to evaluate and enhance the quality of code that Real-Time Workshop can generate for a model. See the Real-Time Workshop Embedded Coder documentation for information on optimizing embedded code.

Make Subsystem and Referenced Model Code Reusable

If your models contain multiple references to the same atomic subsystem, you can ask Real-Time Workshop to generate a single reentrant function to represent the subsystem, rather than inlining it or generating multiple functions that all do the same thing. Chapter 4, “Building Subsystems and Working with Referenced Models”, tells how to do this, and describes model characteristics that can limit or prevent subsystem reuse. It also tells you how to integrate code from referenced models into your applications and how project (slprj) directories are organized.

Verify Generated Code

Using Real-Time Workshop data logging features, you can create an executable that runs on your workstation and creates a data file. You can then compare the results of your program with the results of running an equivalent Simulink simulation.

For more information on how to verify Real-Time Workshop generated code, see “Configuring a Model for Data Logging” on page 2-25. See also “Data Logging” and “Code Verification” in Getting Started.

Incorporate Generated Code into Larger Systems

If your Real-Time Workshop generated code is intended to function within an existing code base (for example, if you want to use the generated code as a

plug-in function), you should use Real-Time Workshop Embedded Coder. See the Real-Time Workshop Embedded Coder documentation for information on entry points and header files you need to interface code to code generated by Real-Time Workshop Embedded Coder.

Incorporate Existing Code into Generated Code

To interface your hand-written code with Real-Time Workshop generated code, you can use an S-function wrapper. See Chapter 10, “Writing S-Functions for Real-Time Workshop Code Generation”, for specific instructions. For additional details, see *Writing S-Functions* in the Simulink documentation and the Target Language Compiler documentation.

Integrate Generated Code with Legacy and Custom Code

A variety of mechanisms are available for integrating code generated by Real-Time Workshop into legacy or custom code and vice versa. See “Integrating Legacy and Custom Code” on page 2-129 and “Build Support for S-Functions” on page 10-81 for details.

Trace Code Back to Blocks

Real-Time Workshop inserts comments throughout the generated code that make it easy to trace generated code back to your Simulink model. See “Tracing Generated Code Back to Your Simulink Model” on page 2-125 for more information about this feature. HTML code generation reports and the Code Viewer in Model Explorer include hyperlinks that link symbols in the generated code to blocks that generated them for Real-Time Workshop Embedded Coder users. See “Generating Code for a Referenced Model” in Getting Started for an example of viewing generated code in Model Explorer.

Automate Builds

Using Real-Time Workshop, you can generate code with the push of a button. The automatic build procedure, initiated by a single mouse click and driven by a model and a system target file, generates code, a makefile, and optionally compiles (or cross-compiles) and downloads a program. See “Automatic Program Building” in Getting Started for an overview, and Chapter 2, “Code Generation and the Build Process” for complete details.

You can create your own system target files to create custom targets that interface with external code or operating environments. If you have in the past created system target files, note that the form of callbacks has changed between Versions 5 and 6 of Real-Time Workshop. See the Real-Time Workshop Embedded Coder documentation for full details.

Tune Parameters During Execution

Parameter tuning enables you to change block parameters while a generated program runs, thus avoiding recompiling the generated code. Real-Time Workshop supports parameter tuning in four different environments:

- **External mode:** You can tune parameters from Simulink while running the generated code on a target processor. See Chapter 6, “External Mode”, for information on this mode.
- **External C application program interface (API):** You can write your own C-API interface for parameter tuning using support files provided by The MathWorks. See Chapter 17, “Data Exchange APIs”, for more information.
- **Rapid simulation:** You can use the Rapid Simulation Target (`rsim`) in batch mode to provide fast simulations for performing parametric studies. Although this is not an on-the-fly application of parameter tuning, it is nevertheless a useful way to evaluate a model. This mode is also useful for Monte Carlo simulation. See Chapter 12, “Running Rapid Simulations”, for more information.
- **Simulink:** Prior to generating real-time code, you can tune parameters on the fly in your Simulink model.

See also “Interface with Signals and Parameters” on page 1-26.

Monitor Signals and Log Data

There are several ways to monitor signals and data in Real-Time Workshop:

- **External mode:** You can monitor and log signals from an externally executing program by using Scope blocks and several other types of external mode compatible blocks. See “Using the External Mode User Interface” on page 6-3 for a discussion of what external mode can do, and “Creating an External Mode Communication Channel” on page 17-23 for advanced details on customizing external mode communication.

- External C application program interface (API): You can write your own C-API for signal monitoring using support files provided by The MathWorks. See Chapter 17, “Data Exchange APIs”, for more information.
- MAT-file logging: You can use a MAT-file to log data from the generated executable. See “Configuring a Model for Data Logging” on page 2-25 for more information.
- Simulink: You can use any of the Simulink data logging capabilities.

Interface with Signals and Parameters

You can interface signals and parameters in your model to hand-written code by specifying the storage declarations of signals and parameters. For more information, see

- “Parameter Storage, Interfacing, and Tuning” on page 5-2
- “Signal Storage, Optimization, and Interfacing” on page 5-31
- “Interfacing Signals to External Code” on page 5-40
- “C-API for Interfacing with Signals and Parameters” on page 17-2

Learn from Sample Implementations

Real-Time Workshop provides sample implementations that illustrate the development of real-time programs under Tornado, as well as generic real-time programs under Windows and UNIX.

These sample implementations are located in the following directories:

- `matlabroot/rtw/c/grt`: Generic real-time examples
- `matlabroot/rtw/c/tornado`: Tornado examples

Summary of Real-Time Workshop Limitations

The following sections identify Real-Time Workshop feature limitations:

- “C++ Target Language Limitations” on page 1-17
- “Tunable Expression Limitations” on page 5-16
- “Limitations on Specifying Data Types in the Workspace Explicitly” on page 5-28
- “Code Reuse Limitations” on page 4-15
- “Real-Time Workshop Model Referencing Limitations” on page 4-45
- “External Mode Limitations” on page 6-46
- “Noninlined S-Function Parameter Type Limitations” on page 10-9
- “S-Function Target Limitations” on page 11-22
- “Rapid Simulation Target Limitations” on page 12-40
- “C-API Limitations” on page 17-20
- “Simulink Block Support”

Code Generation and the Build Process

This chapter provides an overview of the Real-Time Workshop features that you can control with the Configuration Parameters dialog box and Model Explorer. The following sections step you through the Configuration Parameters dialog panes and discuss more options for controlling code generation and compiling it for specific environments.

Choosing and Configuring Your Target (p. 2-3)

Explains how to select a system target file and discusses template makefiles and the make command

Choosing and Configuring a Compiler (p. 2-19)

Provides guidance for choosing and configuring a compiler and choosing appropriate template makefiles

Adjusting Simulation Configuration Parameters for Code Generation (p. 2-23)

Explains how to adjust solver, data import and export, optimization, diagnostic, hardware implementation, and model referencing parameters for code generation

Configuring Real-Time Workshop Code Generation Parameters (p. 2-49)

Explains how to use the Real-Time Workshop pane of the Configuration Parameters dialog box to configure code generation options

Configuring Generated Code with TLC (p. 2-77)

Explains how to use the Target Language Compiler to generate source code in specific ways or to give the code specific characteristics

Interacting with the Build Process (p. 2-81)	Discusses details about the build process and how to interact with it
Customizing the Build Process (p. 2-108)	Explains how to customize the build process for cross-compilation, library usage, and postprocessing of generated code
Validating Generated Code (p. 2-123)	Discusses tools and techniques available for validating generated code
Integrating Legacy and Custom Code (p. 2-129)	Summarizes the different ways of integrating legacy and custom code with code generated by Real-Time Workshop
Relocating Code to Another Development Environment (p. 2-134)	Explains how to package code for relocation to another development environment

Choosing and Configuring Your Target

In this section...

“Introduction” on page 2-3

“Selecting a System Target File” on page 2-4

“Selecting a System Target File Programmatically” on page 2-5

“Available Targets” on page 2-6

“Creating Custom Targets” on page 2-10

“Template Makefiles and Make Options” on page 2-10

Introduction

The first step to setting up a file for code generation is to choose and configure a system target. The process of generating target-specific code is controlled by the following:

- A system target file
- A template makefile
- A make command

You can specify this configuration information for a specific type of target in one step by using the System Target File Browser. The browser lists a variety of ready-to-run configurations.

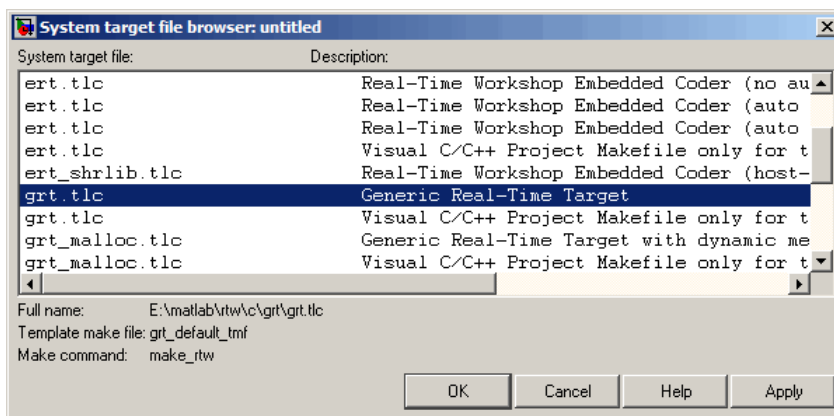
When you select a target, Real-Time Workshop changes settings in the current configuration set to be compatible with the corresponding system target file. For example, many hardware emulation target settings, such as word size and byte ordering, are set automatically according to device type requirements. After selecting a system target, you can modify other model configuration settings to meet model or system requirements.

If you want to apply different system target files to a given model, you can do so by creating multiple configuration sets for that model. At any given time, you choose one configuration set to be the active configuration set. This is the preferred practice over simply changing the model’s system target file.

Selecting a System Target File

To select a target configuration using the System Target File Browser,

- 1 Click **Real-Time Workshop** on the Configuration Parameters dialog box. The **Real-Time Workshop** pane appears.
 - 2 Click the **Browse** button next to the **System target file** field. This opens the System Target File Browser. The browser displays a list of all currently available target configurations, including customizations. When you select a target configuration, Real-Time Workshop automatically chooses the appropriate system target file, template makefile, and make command.
- “Selecting a System Target File” on page 2-4 shows the System Target File Browser with the generic real-time target selected.
- 3 Click the desired entry in the list of available configurations. The background of the list box turns yellow to indicate an unapplied choice has been made. To apply it, click **Apply** or **OK**.



System Target File Browser

When you choose a target configuration, Real-Time Workshop automatically chooses the appropriate system target file, template makefile, and make command for the selected target, and displays them in the **System target file** field. The description of the target file from the browser is placed below its name in the general **Real-Time Workshop** pane.

Selecting a System Target File Programmatically

Simulink models store model-wide parameters and target-specific data in *configuration sets*. Every configuration set contains a component that defines the structure of a particular target and the current values of target options. Some of this information is loaded from a system target file when you select a target using the System Target File Browser. You can configure models to generate alternative target code by copying and modifying old or adding new configuration sets and browsing to select a new target. Subsequently, you can interactively select an active configuration from among these sets (only one configuration set can be active at a given time).

Scripts that automate target selection need to emulate this process.

To program target selection

- 1** Obtain a handle to the active configuration set with a call to the `getActiveConfigSet` function.
- 2** Define string variables that correspond to the required Real-Time Workshop system target file, template makefile, and make command settings. For example, for the ERT target, you would define variables for the strings `'ert.tlc'`, `'ert_default_tmf'`, and `'make_rtw'`.
- 3** Select the system target file with a call to the `switchTarget` function. In the function call, specify the handle for the active configuration set and the system target file.
- 4** Set the `TemplateMakefile` and `MakeCommand` configuration parameters to the corresponding variables created in step 2.

For example:

```
cs = getActiveConfigSet(model);
stf = 'ert.tlc';
tmf = 'ert_default_tmf';
mc = 'make_rtw';
switchTarget(cs,stf,[]);
set_param(cs,'TemplateMakefile',tmf);
set_param(cs,'MakeCommand',mc);
```

Available Targets

The following table lists supported system target files and their associated code formats. The table also gives references to relevant manuals or chapters in this book. All of these targets are built using the `make_rtw` make command.

Note You can select any target of interest using the System Target File Browser. This allows you to experiment with configuration options and save your model with different configurations. However, you cannot build or generate code for non-GRT targets unless you have the appropriate license on your system (Real-Time Workshop Embedded Coder for ERT, Real-Time Windows Target for RTWIN, and so on).

Each system target file invokes one or more template makefiles. The template makefile that is invoked activates a particular compiler (for example, `Lcc`, `gcc`, `Watcom`, or `Borland`). This is specified for you by `MEXOPTS`, which is determined when you run `mex -setup` to select a compiler for `mex`. One exception is the Visual C/C++ project target, which has separate System Target File Browser entries.

Targets Available from the System Target File Browser

Target/Code Format	System Target File	Template Makefile and Comments	Reference
Real-Time Workshop Embedded Coder (PC or UNIX)	<code>ert.tlc</code> <code>ert_shrplib.tlc</code>	<code>ert_default_tmf</code> Use <code>mex -setup</code> to configure for <code>Lcc</code> , <code>Watcom</code> , <code>Borland</code> , <code>vc</code> , <code>gcc</code> , <code>Intel</code> , and so on	Real-Time Workshop Embedded Coder documentation
Real-Time Workshop Embedded Coder for Visual C/C++ Project Makefile	<code>ert.tlc</code>	<code>ert_msvc.tmf</code> Creates a makefile which can be loaded into the MSVC IDE	Real-Time Workshop Embedded Coder documentation

Targets Available from the System Target File Browser (Continued)

Target/Code Format	System Target File	Template Makefile and Comments	Reference
Real-Time Workshop Embedded Coder for Tornado (VxWorks)	ert.tlc	ert_tornado.tmf	Real-Time Workshop Embedded Coder documentation
Generic Real-Time for PC/UNIX	grt.tlc	grt_default_tmf Use mex -setup to configure for Lcc, Watcom, Borland, vc, gcc, Intel, and so on	Chapter 3, “Generated Code Formats”
Generic Real-Time for Visual C/C++ Project Makefile	grt.tlc	grt_msvc.tmf	Chapter 3, “Generated Code Formats”
Generic Real-Time (dynamic) for PC/UNIX	grt_malloc.tlc	grt_malloc_default_tmf Use mex -setup to configure for Lcc, Watcom, Borland, vc, gcc, and so on Does not support SimStruct.	Chapter 3, “Generated Code Formats”
Generic Real-Time (dynamic) for Visual C/C++ Project Makefile	grt_malloc.tlc	grt_malloc_msvc.tmf Does not support SimStruct.	Chapter 3, “Generated Code Formats”
Rapid Simulation Target (default for PC or UNIX)	rsim.tlc	rsim_default_tmf Use mex -setup to configure	Chapter 12, “Running Rapid Simulations”
Rapid Simulation Target for Watcom	rsim.tlc	rsim_watc.tmf	Chapter 12, “Running Rapid Simulations”

Targets Available from the System Target File Browser (Continued)

Target/Code Format	System Target File	Template Makefile and Comments	Reference
Rapid Simulation Target for Visual C/C++	rsim.tlc	rsim_vc.tmf	Chapter 12, "Running Rapid Simulations"
Rapid Simulation Target for Intel	rsim.tlc	rsim_intel.tmf	Chapter 12, "Running Rapid Simulations"
Rapid Simulation Target for Borland	rsim.tlc	rsim_bc.tmf	Chapter 12, "Running Rapid Simulations"
Rapid Simulation Target for LCC	rsim.tlc	rsim_lcc.tmf	Chapter 12, "Running Rapid Simulations"
Rapid Simulation Target for UNIX	rsim.tlc	rsim_unix.tmf	Chapter 12, "Running Rapid Simulations"
S-Function Target for PC or UNIX	rtwsfcn.tlc	rtwsfcn_default.tmf Use mex -setup to configure	Chapter 11, "S-Function Target"
S-Function Target for Watcom	rtwsfcn.tlc	rtwsfcn_watc.tmf	Chapter 11, "S-Function Target"
S-Function Target for Visual C/C++	rtwsfcn.tlc	rtwsfcn_vc.tmf	Chapter 11, "S-Function Target"
S-Function Target for Borland	rtwsfcn.tlc	rtwsfcn_bc.tmf	Chapter 11, "S-Function Target"
S-Function Target for LCC	rtwsfcn.tlc	rtwsfcn_lcc.tmf	Chapter 11, "S-Function Target"
S-Function Target for Intel	rtwsfcn.tlc	rtwsfcn_intel.tmf	Chapter 11, "S-Function Target"
S-Function Target for UNIX	rtwsfcn.tlc	rtwsfcn_unix.tmf	Chapter 11, "S-Function Target"
Tornado (VxWorks) Real-Time Target	tornado.tlc	tornado.tmf	Chapter 13, "Targeting Tornado for Real-Time Applications"

Targets Available from the System Target File Browser (Continued)

Target/Code Format	System Target File	Template Makefile and Comments	Reference
ASAM-ASAP2 Data Definition Target	asap2.tlc	asap2_default_tmf	Appendix A, “Blocks That Depend on Absolute Time”
Real-Time Windows Target for Open Watcom	rtwin.tlc	rtwin.tmf	Real-Time Windows Target documentation
xPC Target for Intel, Visual C/C++, or Watcom C/C++	xpctarget.tlc xpctargetert.tlc	xpc_default_tmf xpc_intel.tmf xpc_vc.tmf xpc_watc.tmf	xPC Target documentation
Target for Freescale™ MPC5xx	mpc555exp.tlc mpc555pil.tlc mpc555rt.tlc mpc555rt_grt.tlc	mpc555exp.tmf mpc555exp_diab.tmf mpc555pil.tmf mpc555pil_diab.tmf mpc555rt.tmf mpc555rt_grt.tmf	Target for Freescale MPC5xx documentation
Target for Infineon C166®	c166.tlc c166_grt.tlc	c166.tmf c166_grt.tmf	Target for Infineon C166 documentation
Target for TI C2000™	ti_c2000_grt.tlc ti_c2000_ert.tlc	tii_c2000_grt.tmf ti_c2000_ert.tmf	Target for TI C2000 documentation
Target for TI C6000™	ti_c6000.tlc (GRT) ti_c6000_ert.tlc	ti_c6000.tmf ti_c6000_ert.tmf	Target for TI C6000 documentation

Targets Supporting Nonzero Start Time

When you try to build models with a nonzero start time, if the selected target does not support a nonzero start time, Real-Time Workshop does not generate code and displays an error message. The Rapid Simulation (RSim) target supports a nonzero start time when the **Configuration Parameters > RSim Target > Solver selection** parameter is set to Use Simulink solver module. All other targets do not support a nonzero start time.

Creating Custom Targets

You can create your own system target files to build custom targets that interface with external code or operating environments. If you have in the past created system target files, note that the form of callbacks has changed between Versions 5 and 6 of Real-Time Workshop. See the Real-Time Workshop Embedded Coder documentation for details, including how to make your custom targets appear in the System Target File Browser and display appropriate controls in panes of the Configuration Parameters dialog box.

Template Makefiles and Make Options

Real-Time Workshop includes a set of built-in template makefiles that are designed to build programs for specific targets.

There are two types of template makefiles:

- *Compiler-specific* template makefiles are designed for use with a particular compiler or development system.

By convention, compiler-specific template makefiles are named according to the target and compiler (or development system). For example, `grt_vc.tmf` is the template makefile for building a generic real-time program under Visual C/C++; `ert_1cc.tmf` is the template makefile for building a Real-Time Workshop Embedded Coder program under the Lcc compiler.

- *Default* template makefiles make your model designs more portable, by choosing the correct compiler-specific makefile and compiler for your installation. “Choosing and Configuring a Compiler” on page 2-19 describes the operation of default template makefiles in detail.

Default template makefiles are named *target_default_tmf*. They are M-files that, when run, select the appropriate TMF. For example, `grt_default_tmf` is the default template makefile for building a generic real-time program; `ert_default_tmf` is the default template makefile for building a Real-Time Workshop Embedded Coder program.

You can supply options to makefiles by using arguments to the **Make command** field in the general **Real-Time Workshop** pane of the Configuration Parameters dialog box. Append the arguments after `make_rtw` (or `make_xpc` or other make command), as in the following example:


```
make_rtw OPTS=" -DMYDEFINE=1 "
```

The syntax for make command options differs slightly for different compilers.

Complete details on the structure of template makefiles are provided in the Real-Time Workshop Embedded Coder documentation. This information is provided for those who want to customize template makefiles. This section describes compiler-specific template makefiles and common options you can use with each.

Note To control compiler optimizations for your Real-Time Workshop makefile build at Simulink GUI level, use the **Compiler optimization level** option on the **Real-Time Workshop** pane of the Simulink Configuration Parameters dialog box. The **Compiler optimization level** option provides

- Target-independent values `Optimizations on` (faster runs) and `Optimizations off` (faster builds), which allow you to easily toggle compiler optimizations on and off during code development
- The value `Custom` for entering custom compiler optimization flags at Simulink GUI level (rather than at other levels of the build process)

If you specify compiler options for your Real-Time Workshop makefile build using `OPT_OPTS`, `MEX_OPTS` (except `MEX_OPTS=" -v "`), or `MEX_OPT_FILE`, the value of **Compiler optimization level** is ignored and a warning is issued about the ignored parameter.

Template Makefiles for UNIX

The template makefiles for UNIX platforms are designed to be used with GNU Make. These makefile are set up to conform to the guidelines specified in the IEEE Std 1003.2-1992 (POSIX) standard.

- `ert_unix.tmf`
- `grt_malloc_unix.tmf`
- `grt_unix.tmf`
- `rsim_unix.tmf`

- `rtwsfcn_unix.tmf`

You can supply options by using arguments to the `make` command.

- `OPTS` — User-specific options, for example,

```
make_rtw OPTS=" -DMYDEFINE=1 "
```

- `OPT_OPTS`— Optimization options. Default is `-O`. To enable debugging specify as `OPT_OPTS=-g`. Because of optimization problems in `IBM_RS`, the default is no optimization.
- `CPP_OPTS` — C++ compiler options.
- `USER_SRCS` — Additional user sources, such as files needed by S-functions.
- `USER_INCLUDES` — Additional include paths, for example,

```
USER_INCLUDES=" -Iwhere-ever -Iwhere-ever2 "
```

These options are also documented in the comments at the head of the respective template makefiles.

Template Makefiles for Visual C/C++

Real-Time Workshop offers two sets of template makefiles designed for use with Visual C/C++.

To build an executable within the Real-Time Workshop build process, use one of the `target_vc.tmf` template makefiles:

- `ert_vc.tmf`
- `grt_malloc_vc.tmf`
- `grt_vc.tmf`
- `rsim_vc.tmf`
- `rtwsfcn_vc.tmf`

You can supply options by using arguments to the `make` command.

- `OPT_OPTS` — Optimization option. Default is `-O2`. To enable debugging specify as `OPT_OPTS=-Zd`.
- `OPTS` — User-specific options.
- `CPP_OPTS` — C++ compiler options.
- `USER_SRCS` — Additional user sources, such as files needed by S-functions.
- `USER_INCLUDES` — Additional include paths, for example,

```
USER_INCLUDES=" -Iwhere-ever -Iwhere-ever2"
```

These options are also documented in the comments at the head of the respective template makefiles.

Visual C/C++ Code Generation Only. To create a Visual C/C++ project makefile (`model.mak`) without building an executable, use one of the `target_msvc.tmf` template makefiles:

- `ert_msvc.tmf`
- `grt_malloc_msvc.tmf`
- `grt_msvc.tmf`

These template makefiles are designed to be used with `nmake`, which is bundled with Visual C/C++.

You can supply the following options by using arguments to the `nmake` command:

- `OPTS` — User-specific options, for example,

```
make_rtw OPTS="/D MYDEFINE=1"
```

- `USER_SRCS` — Additional user sources, such as files needed by S-functions.
- `USER_INCLUDES` — Additional include paths, for example,

```
USER_INCLUDES=" -Iwhere-ever -Iwhere-ever2"
```

These options are also documented in the comments at the head of the respective template makefiles.

Template Makefiles for Watcom C/C++

Real-Time Workshop provides template makefiles to create an executable for Windows using Watcom C/C++. These template makefiles are designed to be used with `wmake`, which is bundled with Watcom C/C++.

Note The Watcom C compiler is no longer available from the manufacturer. However, Real-Time Workshop continues to ship with Watcom-related template makefiles.

- `ert_watc.tmf`
- `grt_malloc_watc.tmf`
- `grt_watc.tmf`
- `rsim_watc.tmf`
- `rtwsfcn_watc.tmf`

You can supply options by using arguments to the `make` command. Note that the location of the quotes is different from the other compilers and make utilities discussed in this chapter.

- `OPTS` — User-specific options, for example,

```
make_rtw "OPTS=-DMYDEFINE=1"
```

- `OPT_OPTS` — Optimization options. The default optimization option is `-oxat`. To turn off optimization and add debugging symbols, specify the `-d2` compiler switch in the `make` command, for example,

```
make_rtw "OPT_OPTS=-d2"
```

- `CPP_OPTS` — C++ compiler options.
- `USER_OBJS` — Additional user objects, such as files needed by S-functions.
- `USER_PATH` — The directory path to the source (`.c` or `.cpp`) files that are used to create any `.obj` files specified in `USER_OBJS`. Multiple paths must be separated with a semicolon. For example,

```
USER_PATH="path1;path2"
```

- `USER_INCLUDES` — Additional include paths, for example,

```
USER_INCLUDES=" -Iinclude-path1 -Iinclude-path2"
```

These options are also documented in the comments at the head of the respective template makefiles.

Template Makefiles for Borland C/C++

Real-Time Workshop provides template makefiles to create an executable for Windows using Borland C/C++.

- `ert_bc.tmf`
- `grt_bc.tmf`
- `grt_malloc_bc.tmf`
- `rsim_bc.tmf`
- `rtwsfcn_bc.tmf`

You can supply these options by using arguments to the make command:

- `OPTS` — User-specific options, for example,

```
make_rtw OPTS="-DMYDEFINE=1"
```

- `OPT_OPTS` — Optimization options. Default is none. To turn off optimization and add debugging symbols, specify the `-v` compiler switch in the make command.

```
make_rtw OPT_OPTS="-v"
```

- `CPP_OPTS` — C++ compiler options.
- `USER_OBJS` — Additional user objects, such as files needed by S-functions.
- `USER_PATH` — The directory path to the source (`.c` or `.cpp`) files that are used to create any `.obj` files specified in `USER_OBJS`. Multiple paths must be separated with a semicolon. For example,

```
USER_PATH="path1;path2"
```

- `USER_INCLUDES` — Additional include paths, for example,

```
USER_INCLUDES=" -Iinclude-path1 -Iinclude-path2"
```

These options are also documented in the comments at the head of the respective template makefiles.

Template Makefiles for LCC

Real-Time Workshop provides template makefiles to create an executable for Windows using Lcc compiler Version 2.4 and GNU Make (gmake).

- `ert_lcc.tmf`
- `grt_lcc.tmf`
- `grt_malloc_lcc.tmf`
- `rsim_lcc.tmf`
- `rtwsfcn_lcc.tmf`

You can supply options by using arguments to the `make` command:

- `OPTS` — User-specific options, for example,

```
make_rtw OPTS="-DMYDEFINE=1"
```

- `OPT_OPTS` — Optimization options. Default is none. To enable debugging, specify `-g4` in the `make` command:

```
make_rtw OPT_OPTS="-g4"
```

- `CPP_OPTS` — C++ compiler options.
- `USER_SRCS` — Additional user sources, such as files needed by S-functions.
- `USER_INCLUDES` — Additional include paths, for example,

```
USER_INCLUDES=" -Iwhere-ever -Iwhere-ever2"
```

For Lcc, have a `/` as file separator before the filename instead of a `\`, for example, `d:\work\proj1\myfile.c`.

These options are also documented in the comments at the head of the respective template makefiles.

Enabling Real-Time Workshop to Build When Pathnames Contain Spaces

Real-Time Workshop is able to handle pathnames that include spaces. Spaces might appear in the pathname from several sources:

- Your MATLAB installation directory
- The current MATLAB directory in which you initiate a build
- A compiler you are using for a Real-Time Workshop build

If your work environment includes one or more of the preceding scenarios, use the following support mechanisms, as necessary and appropriate:

- Add the following code to your template makefile (.tmf):

```
ALT_MATLAB_ROOT      = |>ALT_MATLAB_ROOT<|
ALT_MATLAB_BIN       = |>ALT_MATLAB_BIN<|
!if "$(MATLAB_ROOT)" != "$(ALT_MATLAB_ROOT)"
MATLAB_ROOT = $(ALT_MATLAB_ROOT)
!endif
!if "$(MATLAB_BIN)" != "$(ALT_MATLAB_BIN)"
MATLAB_BIN = $(ALT_MATLAB_BIN)
!endif
```

This code replaces `MATLAB_ROOT` with `ALT_MATLAB_ROOT` when the values of the two tokens are not equal, indicating the pathname for your MATLAB installation directory includes spaces. Likewise, `ALT_MATLAB_BIN` replaces `MATLAB_BIN`.

Note the preceding code is specific to `nmake`. See the supplied Real-Time Workshop template make files for platform-specific examples.

- Use the MATLAB command `rtw_alt_pathname` to translate fully qualified pathnames into standard DOS 8.3 style names. Specify the command with the pathname you want to translate.

For example, to translate the pathname `D:\Applications\Common Files`, specify the following:

```
rtw_alt_pathname('D:\Applications\Common Files')
ans =
    D:\APPLIC~1\COMMON~1
```

- When using operating system commands, such as `system` or `dos`, enclose pathnames that specify executables or command parameters in double quotes (" "). For example,

```
system('dir "D:\Applications\Common Files"')
```


Choosing and Configuring a Compiler

In this section...

- “Introduction” on page 2-19
- “Real-Time Workshop and ANSI C/C++ Compliance” on page 2-19
- “C++ Target Language Considerations” on page 2-20
- “Choosing and Configuring Your Compiler on Windows” on page 2-20
- “Choosing and Configuring Your Compiler on UNIX” on page 2-21
- “Including S-Function Source Code” on page 2-21

Introduction

The Real-Time Workshop build process depends upon the correct installation of one or more supported compilers. *Compiler*, in this context, refers to a development environment containing a linker and make utility, in addition to a high-level language compiler.

The build process also requires the selection of a template makefile. The template makefile determines which compiler runs, during the make phase of the build, to compile the generated code.

To determine which template makefiles are appropriate for your compiler and target, see Targets Available from the System Target File Browser on page 2-6.

Real-Time Workshop and ANSI C/C++ Compliance

Real-Time Workshop generates code that is compliant with the following standards:

Language	Supported Standard
C	ISO/IEC 9899:1990, also known as C89/C90
C++	ISO/IEC 14882:2003

Code generated by Real-Time Workshop from the following sources is ANSI C/C++ compliant:

- Simulink built-in block algorithmic code
- Real-Time Workshop and Real-Time Workshop Embedded Coder system level code (task ID [TID] checks, management, functions, and so on)
- Code from other blocksets (Simulink Fixed Point, Communications, and so on)
- Code from other code generators (Stateflow, Embedded MATLAB™ functions)

Additionally, Real-Time Workshop can incorporate code from

- Embedded targets (for example, startup code, device driver blocks)
- User-written S-functions or TLC files

Note Coding standards for these two sources are beyond the control of Real-Time Workshop, and can be a source for compliance problems, such as code that uses C99 features not supported in the ANSI C, C89/C90 subset.

C++ Target Language Considerations

To use the C++ target language support, you might need to configure Real-Time Workshop to use the appropriate compiler. For example, on Windows the default compiler is the Lcc C compiler shipped with MATLAB, which does not support C++. If you do not configure Real-Time Workshop to use a C++ compiler before you specify C++ for code generation, the following build error message appears:

```
The specified Real-Time Workshop target is configured to generate C++, but the C-only compiler, LCC, is the default compiler. To specify a C++ compiler, enter 'mex -setup' at the command prompt. To generate C code, click (Open) to open the Configuration Parameters dialog and set the target language to C.
```

Choosing and Configuring Your Compiler on Windows

On Windows platforms, you can use the Lcc C compiler shipped with MATLAB, or you can install and use one of the supported Windows compilers.

Real-Time Workshop will choose a compiler based on the template makefile (TMF) name specified on the **Real-Time Workshop** pane of the Configuration Parameters dialog box. The simplest approach is to let Real-Time Workshop pick a compiler based on your default compiler, as set up using the `mex -setup` function. When you use this approach, you do not need to define compiler-specific environment variables, and Real-Time Workshop determines the location of the compiler using information from the `mexopts.bat` file located in the preferences directory (use the `prefdir` command to verify this location).

To use this approach, the TMF filename specified must be an M-file that returns default compiler information by using the `mexopts.bat` file. Most targets provided by Real-Time Workshop use this approach, as when `grt_default_tmf` or `ert_default_tmf` is specified as the TMF name.

Alternatively, the name provided for the TMF can be a compiler-specific template makefile, for example `grt_vc.tmf`, which designates the Visual C/C++ compiler. When you provide a compiler-specific TMF filename, Real-Time Workshop uses the default `mexopts.bat` information to locate the compiler if `mex` has been set up for the same compiler as the specified TMF. If `mex` is not set up with a default compiler, or if it does not match the compiler specified by the TMF, then an environment variable must exist for the compiler specified by the TMF. The environment variable required depends on the compiler. See “Troubleshooting Third-Party Windows Compiler Configurations” in Getting Started for details.

Choosing and Configuring Your Compiler on UNIX

On UNIX, the Real-Time Workshop build process uses the default compiler. For all platforms except SunOS, `cc` is the default compiler. On SunOS, the default is `gcc`.

You should choose the UNIX template makefile that is appropriate to your target. For example, `grt_unix.tmf` is the correct template makefile to build a generic real-time program under UNIX.

Including S-Function Source Code

When Real-Time Workshop builds models with S-functions, source code for the S-functions can be either in the current directory or in the same directory

as their MEX-file. Real-Time Workshop adds an include path to the generated makefiles whenever it finds a file named *sfcnname.h* in the same directory that the S-function MEX-file is in. This directory must be on the MATLAB path.

Similarly, Real-Time Workshop adds a rule for the directory when it finds a file *sfcnname.c* (or *.cpp*) in the same directory as the S-function MEX-file is in.

Adjusting Simulation Configuration Parameters for Code Generation

In this section...

- “Introduction” on page 2-23
- “Configuring the Solver” on page 2-23
- “Configuring a Model for Data Logging” on page 2-25
- “Configuring Optimizations” on page 2-28
- “Configuring Diagnostics” on page 2-28
- “Configuring Hardware Properties and Constraints” on page 2-30
- “Configuring Referenced Models” on page 2-39
- “Simulink and Real-Time Workshop Interactions to Consider” on page 2-40

Introduction

When you are ready to generate code for a model, consider adjusting the model’s simulation configuration parameters. One way of adjusting the parameters is to modify option settings in the Configuration Parameters dialog box. Alternatively, you can use the `set_param` function. The user interface options and associated parameters related to Real-Time Workshop and Real-Time Workshop Embedded Coder are described in “Configuration Parameters” in the Real-Time Workshop Reference. This section describes simulation parameter adjustments to consider for code generation.

Note When you change a check box, menu selection, or edit field in any Configuration Parameters dialog box, the white background of the element you altered turns to light yellow to indicate that an unsaved change has been made. When you click **OK**, **Cancel**, or **Apply**, the background resets to white.

Configuring the Solver

- “Configuring Start and Stop Times” on page 2-24

- “Configuring the Solver Type” on page 2-25
- “Configuring the Tasking Mode” on page 2-25

For details about solver options, see “Solver Pane” in the Simulink reference documentation.

Configuring Start and Stop Times

The stop time must be greater than or equal to the start time. If the stop time is zero, or if the total simulation time (Stop minus Start) is less than zero, the generated program runs for one step. If the stop time is set to `inf`, the generated program runs indefinitely.

When using the GRT or Tornado targets, you can override the stop time when running a generated program from the Windows command prompt or UNIX command line. To override the stop time that was set during code generation, use the `-tf` switch.

```
model -tf n
```

The program runs for `n` seconds. If `n = inf`, the program runs indefinitely. See Getting Started in the Real-Time Workshop documentation for an example of the use of this option.

Certain blocks have a dependency on absolute time. If you are designing a program that is intended to run indefinitely (**Stop time = inf**), and your generated code does not use the `rtModel` data structure (that is, it uses `simstructs` instead), you must not use these blocks. See Appendix A, “Blocks That Depend on Absolute Time” for a list of blocks that can potentially overflow timers.

If you know how long an application that depends on absolute time needs to run, you can ensure that timers do not overflow and that they use optimal word sizes by specifying the **Application lifespan (days)** parameter on the **Optimization** pane. See “Controlling Memory Allocation for Time Counters” on page 9-47 for details.

Configuring the Solver Type

For code generation, you must configure a model to use a fixed-step solver for all targets except the S-function and RSim targets. You can configure the S-function and RSim targets with a fixed-step or variable-step solver.

Configuring the Tasking Mode

Real-Time Workshop supports both single-tasking and multitasking modes for periodic sample times. See Chapter 8, “Models with Multiple Sample Rates” for details.

Configuring a Model for Data Logging

This section describes techniques by which a Real-Time Workshop generated program can save data to a MAT-file for analysis. See also “Data Logging” in Getting Started for a tutorial on Real-Time Workshop data logging features.

Note Data logging is available only for targets that have access to a file system. In addition, only the RSim target executables are capable of accessing MATLAB workspace data.

- “Configuring a Model to Log States, Time, and Output” on page 2-25
- “Logging Data with Scope and To Workspace Blocks” on page 2-27
- “Logging Data with To File Blocks” on page 2-27
- “Data Logging Differences in Single- and Multitasking Models” on page 2-28

Configuring a Model to Log States, Time, and Output

The **Data Import/Export** pane enables a generated program to save system states, outputs, and simulation time at each model execution time step. The data is written to a MAT-file, named (by default) *model.mat*.

Before using this data logging feature, you should learn how to configure a Simulink model to return output to the MATLAB workspace. This is discussed in “Exporting Data to the MATLAB Workspace” in the Simulink documentation.

For each workspace return variable that you define and enable, Real-Time Workshop defines a MAT-file variable. For example, if your model saves simulation time to the workspace variable `tout`, your generated program logs the same data to a variable named (by default) `rt_tout`.

Real-Time Workshop logs the following data:

- All root Output blocks

The default MAT-file variable name for system outputs is `rt_yout`.

The sort order of the `rt_yout` array is based on the port number of the Output block, starting with 1.

- All continuous and discrete states in the model

The default MAT-file variable name for system states is `rt_xout`.

- Simulation time

The default MAT-file variable name for simulation time is `rt_tout`.

- “Overriding the Default MAT-File Name” on page 2-26
- “Overriding the Default MAT-File Variable Names” on page 2-26

Overriding the Default MAT-File Name. The MAT-file name defaults to `model.mat`. To specify a different filename,

- 1 Choose **Configuration Parameters** from the **Simulation** menu. The dialog box opens. Click **Real-Time Workshop**.
- 2 Append the following option to the existing text in the **Make command** field.

```
OPTS=" -DSAVEFILE=filename "
```

Overriding the Default MAT-File Variable Names. By default, Real-Time Workshop prefixes the string `rt_` to the variable names for system outputs, states, and simulation time to form MAT-file variable names. To change this prefix,

- 1 Choose **Configuration Parameters** from the **Simulation** menu. The dialog box opens. Click **Real-Time Workshop**.

- 2** In the **System target file** field, select `grt.tlc`.
- 3** Under **Real-Time Workshop**, select the **Interface** subpane.
- 4** Select a prefix (`rt_`) or suffix (`_rt`) from the **MAT-file variable name modifier** field, or choose none for no prefix (other targets may or may not have this option).

Logging Data with Scope and To Workspace Blocks

Real-Time Workshop also logs data from these sources:

- All Scope blocks that have the **Save data to workspace** option enabled
You must specify the variable name and data format in each Scope block's dialog box.
- All To Workspace blocks in the model
You must specify the variable name and data format in each To Workspace block's dialog box.

The variables are written to `model.mat`, along with any variables logged from the **Workspace I/O** pane.

Logging Data with To File Blocks

You can also log data to a To File block. The generated program creates a separate MAT-file (distinct from `model.mat`) for each To File block in the model. The file contains the block's time and input variable(s). You must specify the filename, variable names, decimation, and sample time in the To File block's dialog box.

Note Models referenced by Model blocks do not perform data logging in that context except for states, which you can include in the state logged for top models. Code generated by Real-Time Workshop for referenced models does not perform data logging to MAT-files.

Data Logging Differences in Single- and Multitasking Models

When logging data in single-tasking and multitasking systems, you will notice differences in the logging of

- Noncontinuous root Output blocks
- Discrete states

In multitasking mode, the logging of states and outputs is done after the first task execution (and not at the end of the first time step). In single-tasking mode, Real-Time Workshop logs states and outputs after the first time step.

See “Data Logging in Single-Tasking and Multitasking Model Execution” on page 7-15 for more details on the differences between single-tasking and multitasking data logging.

Note The rapid simulation target (RSim) provides enhanced logging options. See Chapter 12, “Running Rapid Simulations” for more information.

Configuring Optimizations

For information on configuring optimizations, see the following sections:

- Chapter 9, “Optimizing a Model for Code Generation”
- “Optimization Dependencies” on page 9-50

If you are licensed to use Real-Time Workshop Embedded Coder, see also “Configuring Optimizations” and “Tips for Optimizing the Generated Code” in the Real-Time Workshop Embedded Coder documentation.

Configuring Diagnostics

Diagnostic parameters that pertain to code generation include the following **Data Validity** parameters:

- **Detect loss of tunability** in the Parameters section
- **Model Verification block enabling** in the Debugging section

Detecting Loss of Tunability

If a tunable workspace variable is modified by Mask Initialization code, or is used in an arithmetic expression with unsupported operators or functions, the expression is reduced to a numeric expression and therefore cannot be tuned. You can use the **Detect loss of tunability** diagnostic to report such loss of tunability. The possible values are:

- none — Loss of tunability can occur without notification.
- warning — Loss of tunability generates a warning (default).
- error — Loss of tunability generates an error.

For a list of supported operators and functions, see “Tunable Expression Limitations” on page 5-16.

Enabling Model Verification Blocks

A specific use of the diagnostics options for code generation is to control the behavior of model verification (assertion) blocks. The **Model Verification block enabling** menu in the **Data Validity** subpane specifies whether model verification blocks such as Assert, Check Static Gap, and related range check blocks are included, excluded, or default to their local settings. The diagnostic has the same effect on code generated by Real-Time Workshop as it does on simulation behavior.

Settings are

- Use local settings
- Enable All
- Disable All

For Assertion blocks that are not disabled, the generated code for a model includes one of the following statements, at appropriate locations, depending on the block’s input signal type (Boolean, real, or integer, respectively).

```
utAssert(input_signal);  
utAssert(input_signal != 0.0);  
utAssert(input_signal != 0);
```

By default, `utAssert` has no effect in generated code. For assertions to abort execution, you must enable them by including a parameter in the `make_rtw` command. Specify the **Make command** field on the **Real-Time Workshop** pane as follows:

```
make_rtw OPTS=' -DDOASSERTS '
```

If you want triggered assertions not to abort execution and instead to print the assertion statement, use the following `make_rtw` variant:

```
make_rtw OPTS=' -DDOASSERTS -DPRINT_ASSERTS '
```

`utAssert` is defined as

```
#define utAssert(exp)  assert(exp)
```

You can provide your own definition of `utAssert` in a hand-coded header file if you want to customize assertion behavior in generated code. See *matlabroot/rtw/c/libsrc/rtlibsrc.h* for implementation details.

Finally, when running a model in accelerator mode, Simulink calls back to itself to execute assertion blocks instead of using generated code. Thus, user-defined callbacks are still called when assertions fail.

Configuring Hardware Properties and Constraints

The **Hardware Implementation** pane contains options that you can use to specify hardware properties and constraints, such as data size, byte ordering, and rounding behavior. Such information is necessary for code generation in two contexts:

- Generating production code for downloading and execution on the target hardware
- Generating test code that runs on the current hardware and emulates production code

The **Hardware Implementation** pane contains a subpane for each of these cases:

- **Embedded Hardware (simulation and code generation)** — Defines the target hardware that will run the production code. This information affects both simulation and code generation.
- **Emulation Hardware (code generation only)** — Defines the current hardware for which to generate code. This information affects only test code generation.

The two **Hardware Implementation** subpanes provide identical options and possible values. By default, the options and values initially look like this:

The screenshot shows a configuration pane with the following settings:

- Device vendor: Generic
- Device type: Unspecified (assume 32-bit Generic)
- Number of bits:
 - char: 8
 - short: 16
 - int: 32
 - long: 32
 - native word size: 32
- Byte ordering: Unspecified
- Signed integer division rounds to: Undefined
- Shift right on a signed integer as arithmetic shift

To see an example of **Hardware Implementation** pane capabilities, run the `rtwdemo_targetsettings` demo.

Specifying Hardware Implementation Options

This section describes considerations that apply and options that are available in both the **Embedded Hardware** and **Emulation Hardware** subpanes of the **Hardware Implementation** pane. The following sections describe considerations that apply only to one or the other subpane.

- “Specifying Embedded Hardware Characteristics” on page 2-35
- “Specifying Emulation Hardware Characteristics” on page 2-36

If you have specified a **System target file** (using the **Real-Time Workshop** pane **General** tab) and the target file specifies a default microprocessor and its hardware properties, the default and properties appear as initial values in the **Hardware Implementation** pane. Options with only one possible value cannot be changed. Any option that has more than one possible value provides a pulldown list of legal values.

Note If you specify any hardware properties manually, check carefully that their values are consistent with the system target file. Otherwise, the generated code may fail to compile or execute, or may execute but give incorrect results.

- “Configuring the Device Vendor” on page 2-32
- “Configuring the Device Type” on page 2-32
- “Configuring the Number of Bits” on page 2-33
- “Configuring the Byte Ordering” on page 2-34
- “Configuring How Compiler Rounds Results of Signed Integer Division” on page 2-34
- “Configuring Arithmetic Right Shifts on Signed Integers” on page 2-35

Configuring the Device Vendor. This option specifies the device vendor. To set the option, select a vendor name from the **Device vendor** menu. Your selection of vendor will determine the available device values in the **Device type** list. If the desired vendor name does not appear in the menu, select Generic and then use the **Device type** option to further specify the device.

Note For complete lists of **Device vendor** and **Device type** values, see “Device vendor” and “Device type” in the Simulink reference documentation.

Configuring the Device Type. This option specifies a hardware device among the supported devices listed for your **Device vendor** selection. To set the option, select a microprocessor name from the **Device type** menu. If the desired microprocessor does not appear in the menu, change the **Device vendor** to Generic.

If you specified the **Device vendor** as Generic, examine the listed device descriptions and select the device type that matches your hardware. If no available device type is appropriate, select Custom.

If you select a device type for which the target file specifies default hardware properties, the properties appear as initial values in the subpane. Options with only one possible value cannot be changed. Any option that has more than one possible value provides a pulldown list of legal values. Select values appropriate to your hardware. If the device type is Custom, all options can be set, and each option has a pulldown list of all possible values.

Configuring the Number of Bits. These options specify the **native word size** of the microprocessor, and the bit lengths of **char**, **short**, **int**, and **long** data. For code generation to succeed, all values must be multiples of 8, with a maximum of 32.

Real-Time Workshop integer type names are defined in the file `rtwtypes.h`. The values that you specify must be consistent with the word sizes as defined in the compiler's `limits.h` header file. The following table lists the standard Real-Time Workshop integer type names and maps them to the corresponding Simulink names.

Real-Time Workshop Integer Type	Simulink Integer Type
<code>boolean_T</code>	<code>boolean</code>
<code>int8_T</code>	<code>int8</code>
<code>uint8_T</code>	<code>uint8</code>
<code>int16_T</code>	<code>int16</code>
<code>uint16_T</code>	<code>uint16</code>
<code>int32_T</code>	<code>int32</code>
<code>uint32_T</code>	<code>uint32</code>

If no ANSI-C type with a matching word size is available, but a larger ANSI-C type not over 32 bits is available, Real-Time Workshop uses the larger type for `int8_T`, `uint8_T`, `int16_T`, and `uint16_T`. If no ANSI-C 32-bit type is available, Real-Time Workshop does not define `int32_T` and `uint32_T`.

An application can use integer data of any length from 1 (unsigned) or 2 (signed) bits up to the number of bits in a long, or 32 bits, whichever is less. If the integer length matches the length of an available type, Real-Time

Workshop uses that type. If no matching type is available, Real-Time Workshop uses the smallest available type that can hold the data, generating code that never uses the unnecessary higher-order bits. For example, on a target that provided 8-, 16-, and 32-bit integers, a signal specified as 24 bits would be implemented as an `int32_T` or `uint32_T`.

Code that uses emulated integer data is not maximally efficient, but can be useful during application development for emulating integer lengths that are available only on production hardware. The use of emulation does not affect the results of execution.

Configuring the Byte Ordering. Specifies whether the target hardware uses `Big Endian` (most significant byte first) or `Little Endian` (least significant byte first) byte ordering. If left as `Unspecified`, Real-Time Workshop generates code that determines the endianness of the target; this is the least efficient option.

Configuring How Compiler Rounds Results of Signed Integer Division. Specifies how an ANSI C conforming compiler used to compile code rounds the result of dividing one signed integer by another to produce a signed integer quotient. Real-Time Workshop uses this information to optimize the efficiency of code generated for signed division. The options are

- `Zero` — If the quotient is between two integers, the compiler chooses the integer that is closer to zero as the result.
- `Floor` — If the quotient is between two integers, the compiler chooses the integer that is closer to negative infinity.
- `Undefined` — The compiler's rounding behavior is undefined if either or both operands are negative.

The following table illustrates the compiler behavior specified by these options.

N	D	Ideal N/D	Zero	Floor	Undefined
33	4	8.25	8	8	8
-33	4	-8.25	-8	-9	-8 or -9
33	-4	-8.25	-8	-9	-8 or -9
-33	-4	8.25	8	8	-8 or -9

Configuring Arithmetic Right Shifts on Signed Integers. ANSI C does not define the behavior of right shifts on negative integers, so the behavior is implementation-dependent. Select this option if the C compiler implements a signed integer right shift as an arithmetic right shift, and clear it otherwise. An arithmetic right shift fills bits vacated by the right shift with the value of the most significant bit, which indicates the sign of the number in twos complement notation. The option is selected by default. If your compiler handles right shifts as arithmetic shifts, this is the preferred setting.

- When the option is selected, Real-Time Workshop generates simple efficient code whenever the Simulink model performs arithmetic shifts on signed integers.
- When the option is cleared, Real-Time Workshop generates fully portable but less efficient code to implement right arithmetic shifts.

Specifying Embedded Hardware Characteristics

The **Embedded Hardware (simulation and code generation)** subpane of the **Hardware Implementation** pane enables you to specify the characteristics of the deployment hardware that will be used to run the production code generated for the model by Real-Time Workshop. When you use this subpane, keep the following in mind:

- Code generation targets can have word sizes and other hardware characteristics that differ from the MATLAB host. Furthermore, code can be prototyped on hardware that is different from either the deployment target or the MATLAB host. Real-Time Workshop takes these differences into account when generating code.
- Simulink uses some of the information in the **Embedded Hardware** subpane to ensure that simulation without code generation gives the same

results as executing generated code, including detecting error conditions that could arise on the target hardware, such as hardware overflow.

- Real-Time Workshop generates code that gives bit-true agreement with Simulink's behavior for integer and fixed-point operations. Generated code that emulates unavailable data lengths runs less efficiently than it would without emulation, but bit-true agreement with Simulink is not affected.
- To ensure correctness and efficiency, if you change targets at any point during application development you must reconfigure the hardware implementation parameters for the new target before generating or regenerating code. Bit-true agreement with Simulink is not guaranteed when code executes on hardware for which it was not generated.
- Only Real-Time Workshop uses the **Signed integer division rounds to** parameter, which has no effect on Simulink. To achieve the analogous effect in Simulink, use the **Round integer calculations toward** block parameter to simulate the rounding behavior of the C compiler that you intend to use. This setting appears on the **Signal data type** pane of the parameter dialog boxes of blocks that can perform signed integer arithmetic, such as the Product and Sum blocks.
- When models contain Model blocks, all models that they reference must be configured to use identical hardware settings.

Specifying Emulation Hardware Characteristics

If the current hardware differs from the target hardware, you can generate code that runs on the current hardware but behaves as if it had been generated for and executed on the target hardware. Real-Time Workshop uses the information in both the **Embedded Hardware (simulation and code generation)** subpane and the **Emulation Hardware (code generation only)** subpane to generate such code. By default, the **Emulation Hardware** subpane initially contains only a button labeled **None**:

Hardware Implementation

Embedded hardware (simulation and code generation)

Device vendor: Generic

Device type: Unspecified (assume 32-bit Generic)

Number of bits: char: 8 short: 16 int: 32
long: 32 native word size: 32

Byte ordering: Unspecified

Signed integer division rounds to: Undefined

Shift right on a signed integer as arithmetic shift

Emulation hardware (code generation only)

None

(If the **Emulation Hardware** subpane contains a button labeled **Configure current execution hardware device**, see “Updating from Earlier Versions” on page 2-38, then continue from this point.)

To generate code that runs on current hardware and emulates target hardware, you must specify the properties of both types of hardware in the **Hardware Implementation** pane. The **Embedded Hardware** subpane specifies the target hardware properties, as described previously. To specify the current hardware properties,

- 1 Clear the **None** option in the **Emulation Hardware** subpane.

By default, the **Hardware Implementation** pane now looks like this:

Hardware Implementation

Embedded hardware (simulation and code generation)

Device vendor:

Device type:

Number of bits: char: short: int:
long: native word size:

Byte ordering:

Signed integer division rounds to:

Shift right on a signed integer as arithmetic shift

Emulation hardware (code generation only)

None

Device vendor:

Device type:

Number of bits: char: short: int:
long: native word size:

Byte ordering:

Signed integer division rounds to:

Shift right on a signed integer as arithmetic shift

2 In the **Emulation Hardware** subpane, specify the properties of the current hardware, using the instructions in “Specifying Hardware Implementation Options” on page 2-31

If you do not expose the **Emulation Hardware** subpane options and specify current hardware characteristics, Simulink and Real-Time Workshop default every **Emulation Hardware** option to have the same value as the corresponding **Embedded Hardware** option. This default is appropriate whenever the current hardware has the same characteristics as the target hardware.

Updating from Earlier Versions. If your model was created before MATLAB Release 14 and has not been updated, by default the **Hardware Implementation** pane initially looks like this:

Hardware Implementation

Embedded hardware (simulation and code generation)

Device vendor:

Device type:

Number of bits: char: short: int:
 long: native word size:

Byte ordering:

Signed integer division rounds to:

Shift right on a signed integer as arithmetic shift

Emulation hardware (code generation only)

Click **Configure current execution hardware device**. The **Configure current execution hardware device** button disappears. The subpane then appears as shown in the first figure in this section. Save your model at this point to avoid redoing **Configure current execution hardware device** next time you access the **Hardware Implementation** pane.

Configuring Referenced Models

- Minimize occurrences of algebraic loops by selecting the **Minimize algebraic loop occurrences** parameter on the Model Reference pane. The setting of this option affects only generation of code from the model. See “Configuring Hardware Properties and Constraints” on page 2-30 in the Real-Time Workshop documentation for information on how this option affects code generation. For more information, see “Model Blocks and Direct Feedthrough”.
- Use the **Round integer calculations toward** parameter settings on your model’s blocks to simulate the rounding behavior of the C compiler that you intend to use to compile code generated from the model. This setting appears on the **Signal data type** pane of the parameter dialog boxes of blocks that can perform signed integer arithmetic, such as the Product and Sum blocks.

For information on the **Model Referencing** pane options, see “Referencing a Model” in the Simulink documentation.

Simulink and Real-Time Workshop Interactions to Consider

The Simulink engine propagates data from one block to the next along signal lines. The data propagated consists of

- Data type
- Line widths
- Sample times

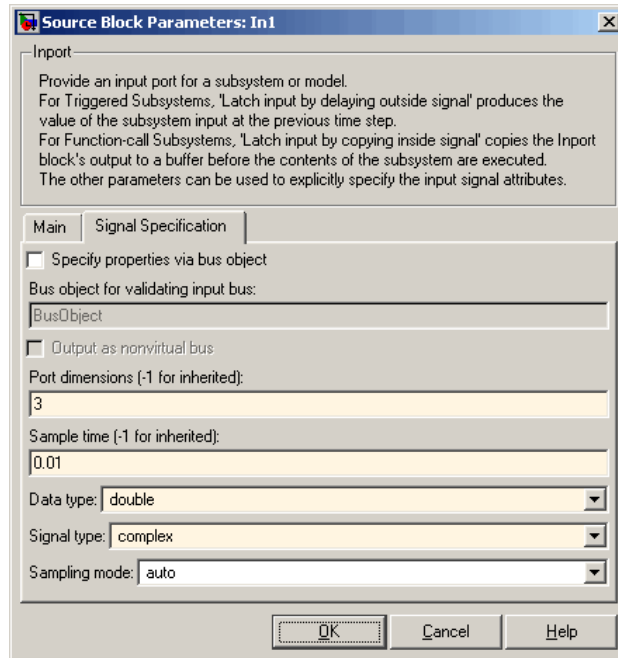
The first stage of code generation is compilation of the block diagram. This stage is analogous to that of a C or C++ program. The compiler carries out type checking and preprocessing. Similarly, Simulink verifies that input/output data types of block ports are consistent, line widths between blocks are of the correct thickness, and the sample times of connecting blocks are consistent.

You can verify what data types any given Simulink block supports by typing

```
showblockdatatypetable
```

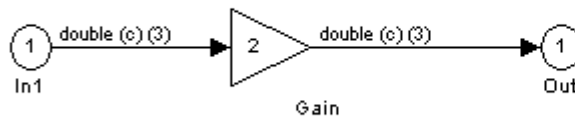
at the MATLAB prompt, or (from the Help browser) clicking the command above.

The Simulink engine typically derives signal attributes from a source block. For example, the Inport block's parameters dialog box specifies the signal attributes for the block.



In this example, the Inport block has a port width of 3, a sample time of .01 seconds, the data type is double, and the signal is complex.

This figure shows the propagation of the signal attributes associated with the Inport block through a simple block diagram.



In this example, the Gain and Outport blocks inherit the attributes specified for the Inport block.

- “Sample Time Propagation” on page 2-42
- “Latches for Subsystem Blocks” on page 2-43
- “Block Execution Order” on page 2-44
- “Algebraic Loops” on page 2-45

Sample Time Propagation

Inherited sample times in source blocks (for example, a root inport) can sometimes lead to unexpected and unintended sample time assignments. Since a block may specify an inherited sample time, information available at the outset is often insufficient to compile a block diagram completely.

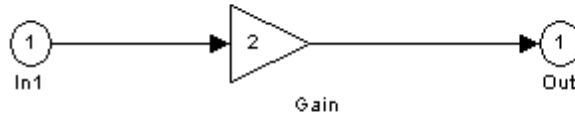
In such cases, the Simulink engine propagates the known or assigned sample times to those blocks that have inherited sample times but that have not yet been assigned a sample time. Thus, Simulink continues to fill in the blanks (the unknown sample times) until sample times have been assigned to as many blocks as possible.

Blocks that still do not have a sample time are assigned a default sample time according to the following rules:

- 1** If the current system has at least one rate in it, the block is assigned the fastest rate.
- 2** If no rate exists and the model is configured for a variable-step solver, the block is assigned a continuous sample time (but fixed in minor time steps). Real-Time Workshop (with the exception of the rapid simulation and S-function targets) does not currently support variable-step solvers.
- 3** If no rate exists and the model is configured for a fixed-step solver, the block is assigned a discrete sample time of $(T_f - T_i)/50$, where T_i is the simulation start time and T_f is the simulation stop time. If T_f is infinity, the default sample time is set to 0.2.

To ensure a completely deterministic model (one where no sample times are set using the above rules), you should explicitly specify the sample times of all your source blocks. Source blocks include root inport blocks and any blocks without input ports. You do not have to set subsystem input port sample times. You might want to do so, however, when creating modular systems.

An unconnected input implicitly connects to ground. For ground blocks and ground connections, the default sample time is derived from destination blocks or the default rule.



All blocks have an inherited sample time ($T_s = -1$). They are all assigned a sample time of $(T_f - T_i)/50$.

Constant Block Sample Times. You can specify a sample time for Constant blocks. This has certain implications for code generation.

When a sample time of `inf` is selected for a Constant block,

- If **Inline parameters** is on, the block takes on a constant sample time, and propagates a constant sample time downstream.
- If **Inline parameters** is off, the Constant block inherits its sample time – which is nonconstant – and propagates that sample time downstream.

Generated code for any block differs when it has a constant sample time; its outputs are represented in the constant block outputs structure instead of in the general block outputs structure. The generated code thus reflects that the Constant block propagates a constant sample time downstream if a sample time of `inf` is specified and **Inline parameters** is on.

Latches for Subsystem Blocks

When an Inport block is the signal source for a triggered or function-call subsystem, you can use latch options to preserve input values while the subsystem executes. The Inport block latch options include:

For...	You Can Use...
Triggered subsystems	Latch input by delaying outside signal
Function-call subsystems	Latch input by copying inside signal

When you use **Latch input by copying inside signal** for a function-call subsystem, Real-Time Workshop

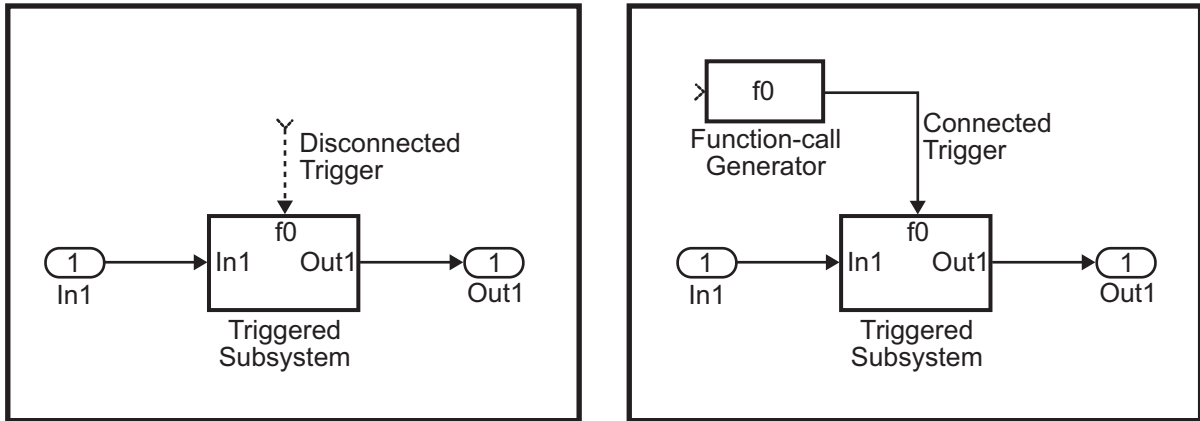
- Preserves latches in generated code regardless of any optimizations that might be set
- Places the code for latches at the start of a subsystem's output/update function

For more information on these options, see the description of the Inport block in the Simulink documentation.

Block Execution Order

Once Simulink compiles the block diagram, it creates a *model.rtw* file (analogous to an object file generated from a C or C++ file). The *model.rtw* file contains all the connection information of the model, as well as the necessary signal attributes. Thus, the timing engine in Real-Time Workshop can determine when blocks with different rates should be executed.

You cannot override this execution order by directly calling a block (in hand-written code) in a model. For example, in the next figure the *disconnected_trigger* model on the left has its trigger port connected to ground, which can lead to all blocks inheriting a constant sample time. Calling the trigger function, *f()*, directly from user code does not work correctly and should never be done. Instead, you should use a function-call generator to properly specify the rate at which *f()* should be executed, as shown in the *connected_trigger* model on the right.



Instead of the function-call generator, you could use any other block that can drive the trigger port. Then, you should call the model's main entry point to execute the trigger function.

For multirate models, a common use of Real-Time Workshop is to build individual models separately and then hand-code the I/O between the models. This approach places the burden of data consistency between models on the developer of the models. Another approach is to let Simulink and Real-Time Workshop ensure data consistency between rates and generate multirate code for use in a multitasking environment. The Simulink Rate Transition block is able to interface both periodic and asynchronous signals. For a description of the Real-Time Workshop libraries, see Chapter 16, “Asynchronous Support”. For more information on multirate code generation, see Chapter 8, “Models with Multiple Sample Rates”.

Algebraic Loops

Algebraic loops are circular dependencies between variables. This prevents the straightforward direct computation of their values. For example, in the case of a system of equations

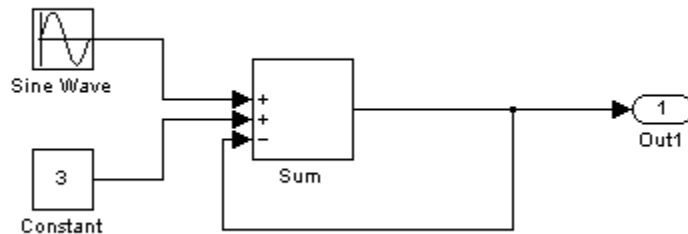
- $x = y + 2$
- $y = -x$

the values of x and y cannot be directly computed.

To solve this, either repeatedly try potential solutions for x and y (in an intelligent manner, for example, using gradient based search) or “solve” the system of equations. In the previous example, solving the system into an explicit form leads to

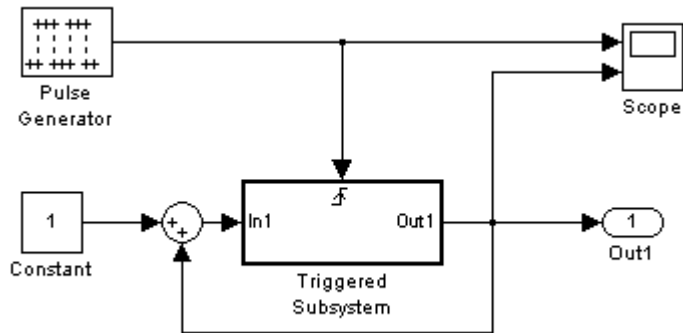
- $2x = 2$
- $y = -x$
- $x = 1$
- $y = -1$

An algebraic loop exists whenever the output of a block having direct feedthrough (such as Gain, Sum, Product, and Transfer Fcn) is fed back as an input to the same block. Simulink is often able to solve models that contain algebraic loops, such as the next diagram.



Real-Time Workshop does not produce code that solves algebraic loops. This restriction includes models that use Algebraic Constraint blocks in feedback paths. However, Simulink can often eliminate all or some algebraic loops that arise, by grouping equations in certain ways in models that contain them. It does this by separating the update and output functions to avoid circular dependencies. See “Algebraic Loops” in the Simulink documentation for details.

Algebraic Loops in Triggered Subsystems. While Simulink can minimize algebraic loops involving atomic and enabled subsystems, a special consideration applies to some triggered subsystems. An example for which code can be generated is shown in the following model and triggered subsystem.



The default behavior of Simulink is to combine output and update methods for the subsystem, which creates an apparent algebraic loop, even though the Unit Delay block in the subsystem has no direct feedthrough.

You can allow Simulink to solve the problem by splitting the output and update methods of triggered and enabled-triggered subsystems when necessary and feasible. If you want Real-Time Workshop to take advantage of this feature, select the **Minimize algebraic loop occurrences** check box in the Subsystem Parameters dialog box. Select this option to avoid algebraic loop warnings in triggered subsystems involved in loops.

Note If you always check this box, the generated code for the subsystem might contain split output and update methods, even if the subsystem is not actually involved in a loop. Also, if a direct feedthrough block (such as a Gain block) is connected to the inport in the above triggered subsystem, Simulink cannot solve the problem, and Real-Time Workshop is unable to generate code.

A similar **Minimize algebraic loop occurrences** option appears on the **Model Referencing** pane of the Configuration Parameters dialog box. Selecting it enables Real-Time Workshop to generate code for models containing Model blocks that are involved in algebraic loops.

Configuring Real-Time Workshop Code Generation Parameters

In this section...

- “Introduction” on page 2-49
- “Opening the Real-Time Workshop Pane” on page 2-50
- “Selecting a Target Configuration” on page 2-51
- “Configuring the Target Language for Generated Code” on page 2-52
- “Configuring Report Generation” on page 2-52
- “Configuring the Build Process” on page 2-53
- “Configuring Code Comments” on page 2-56
- “Configuring Generated Identifiers” on page 2-57
- “Configuring Custom Code” on page 2-60
- “Troubleshooting the Build Process” on page 2-61
- “Configuring Model Interfaces” on page 2-63
- “Selecting and Viewing Target Function Libraries” on page 2-68

Introduction

As discussed in “Adjusting Simulation Configuration Parameters for Code Generation” on page 2-23, many model configuration parameters affect the way that Real-Time Workshop generates code and builds an executable from your model.

However, you initiate and directly control the code generation and build process from the **Real-Time Workshop** pane and related tabs (also presented as subnodes).

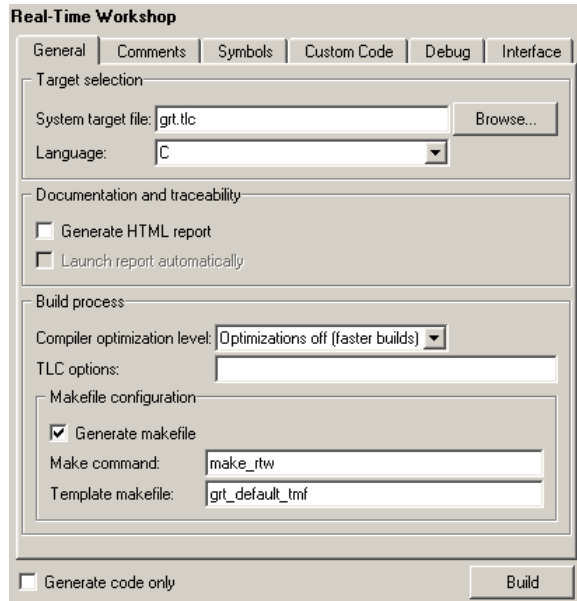
In addition to using the Configuration Parameters dialog box, you can use `get_param` and `set_param` to individually access most configuration parameters. The configuration parameters you can get and set are listed in “Parameter Command-Line Information Summary” in the Real-Time Workshop Reference.

Opening the Real-Time Workshop Pane

There are three ways to open the **Real-Time Workshop** pane of the Configuration Parameters dialog box:

- From the **Simulation** menu, choose Configuration Parameters (or type **Ctrl+E**). When the Configuration Parameters dialog box opens, click **Real-Time Workshop** in the **Select** (left) pane.
- Select **Model Explorer** from the **View** menu in the model window, or type `daexplr` on the MATLAB command line and press **Enter**. In Model Explorer, expand the node for the current model in the left pane and click **Configuration** (active). The configuration dialog elements are listed in the middle pane. Clicking any of these brings up that dialog in the right pane. Alternatively, right-clicking the Real-Time Workshop configuration element in the middle pane and choosing **Properties** from the context menu activates that dialog in a separate window.
- Select **Options** from the **Real-Time Workshop** submenu of the **Tools** menu in the model window.

The general **Real-Time Workshop** pane, as it appears in the Model Explorer, appears in the next figure.



Real-Time Workshop Pane

This pane allows you to specify most of the options for controlling the Real-Time Workshop code generation and build process. The content of the pane and its subpanes can change depending on the target you specify. Thus, a model that has multiple configuration sets can invoke parameters in one configuration that do not apply to another configuration. In addition, some configuration options are available only with Real-Time Workshop Embedded Coder.

For descriptions of Real-Time Workshop pane parameters, see “Real-Time Workshop Pane: General” in the Real-Time Workshop reference documentation.

Selecting a Target Configuration

Use the **Browse** button on the Real-Time Workshop pane to open the System Target File Browser (See “Selecting a System Target File” on page 2-4). The browser lets you select a preset target configuration consisting of a system target file, template makefile, and make command.

If you select a target configuration by using the System Target File Browser, your selection appears in the **System target file** field (*target.tlc*).

If you are using a target configuration that does not appear in the System Target File Browser, enter the name of your system target file in the **System target file** field. Click **Apply** or **OK** to configure for that target.

“Choosing and Configuring Your Target” on page 2-3 describes the use of the browser and includes a complete list of available target configurations.

Configuring the Target Language for Generated Code

Use the **Language** menu in the **Target selection** section of the Real-Time Workshop pane to select the target language for the code Real-Time Workshop generates. You can select C or C++. Real-Time Workshop generates .c or .cpp files, depending on your selection, and places the files in your build directory.

Note If you select C++, you might need to configure Real-Time Workshop to use the appropriate compiler before you build a system. For details, see “Choosing and Configuring a Compiler” on page 2-19.

Configuring Report Generation

To generate an navigable summary of source files when the model is built, select the **Generate HTML report** parameter. Selecting this parameter causes Real-Time Workshop to produce an HTML file for each generated source file, plus a summary and an index file, in a directory named `html` within the build directory. If you also select the **Launch report automatically** option (which is enabled by selecting **Generate HTML report**), the HTML summary and index are automatically displayed. If you do not want to see the report at that time, clear this second check box. In either case, you can refer to HTML reports at any time. To review an existing HTML report, use any HTML browser to open the file `html/model_codgen_rpt.html` within your build directory.

For more detail on report content, see “Viewing Generated Code in Generated HTML Reports” on page 2-123.

Configuring the Build Process

Controlling Compiler Optimization Level and Specifying Custom Optimization Settings

To control compiler optimizations for your Real-Time Workshop makefile build at Simulink GUI level, use the **Compiler optimization level** parameter. The **Compiler optimization level** parameter provides

- Target-independent values `Optimizations on (faster runs)` and `Optimizations off (faster builds)`, which allow you to easily toggle compiler optimizations on and off during code development
- The value `Custom` for entering custom compiler optimization flags at Simulink GUI level, rather than editing compiler flags into template makefiles (TMFs) or supplying compiler flags to Real-Time Workshop make commands

The default setting is `Optimizations off (faster builds)`. Selecting the value `Custom` enables the **Custom compiler optimization flags** field, in which you can enter custom compiler optimization flags (for example, `-O2`).

Note If you specify compiler options for your Real-Time Workshop makefile build using `OPT_OPTS`, `MEX_OPTS` (except `MEX_OPTS=" -v "`), or `MEX_OPT_FILE`, the value of **Compiler optimization level** is ignored and a warning is issued about the ignored parameter.

For more information about the **Compiler optimization level** parameter and its values, see “Compiler optimization level” and “Custom compiler optimization flags” in the Real-Time Workshop reference documentation.

Specifying TLC Options

You can enter Target Language Compiler (TLC) command line options in the **TLC options** edit field, for example

- `-aVarName=1` to declare a TLC variable and/or assign a value to it
- `-IC:\Work` to specify an include path

- `-v` to obtain verbose output from TLC processing (for example, when debugging)

Specifying TLC options does not add any flags to the **Make command** field, as do some of the targets available in the System Target File Browser.

For additional information, see “Setting Target Language Compiler Options” on page 2-79 for details, as well as the Target Language Compiler documentation.

Specifying Whether To Generate a Makefile

The **Generate makefile** option specifies whether Real-Time Workshop is to generate a makefile for a model during the build process. By default, Real-Time Workshop generates a makefile. You can suppress the generation of a makefile, for example in support of custom build processing that is not based on makefiles, by clearing **Generate makefile**. When you clear this option,

- The **Make command** and **Template makefile** options are unavailable.
- You must set up any post code generation build processing, using a user-defined command, as explained in “Customizing Post Code Generation Build Processing” on page 2-117.

Specifying a Make Command

A high-level M-file command, invoked when a build is initiated, controls the Real-Time Workshop build process. Each target has an associated make command. The **Make command** field displays this command.

Almost all targets use the default command, `make_rtw`. Third-party targets might supply another make command. See the vendor’s documentation.

In addition to the name of the make command, you can supply arguments in the **Make command** field. These arguments include compiler-specific options, include paths, and other parameters. When the build process invokes the make utility, these arguments are passed along in the make command line.

“Template Makefiles and Make Options” on page 2-10 lists the **Make command** arguments you can use with each supported compiler.

Specifying the Template Makefile

The **Template makefile** field has these functions:

- If you have selected a target configuration using the System Target File Browser, this field displays the name of an M-file that selects an appropriate template makefile for your development environment. For example, in “Real-Time Workshop Pane: General”, the **Template makefile** field displays `grt_default_tmf`, indicating that the build process invokes `grt_default_tmf.m`.
“Template Makefiles and Make Options” on page 2-10 gives a detailed description of the logic by which Real-Time Workshop selects a template makefile.
- Alternatively, you can explicitly enter the name of a specific template makefile (including the extension) or an M-file that returns a template make file in this field. You must do this if you are using a target configuration that does not appear in the System Target File Browser. For example, this is necessary if you have written your own template makefile for a custom target environment or you.

If you specify your own template makefile, be sure to include the filename extension. If you omit the extension, Real-Time Workshop attempts to find and execute a file with the extension `.m` (that is, an M-file). The template make file (or an M-file that returns a template make file) must be on the MATLAB path. To determine whether the file is on the MATLAB path, enter the following command in the MATLAB Command Window:

```
which tmf_filename
```

Generating Code Only

To configure the model for code generation only, rather than a complete build (make command does not execute), select the **Generate code only** parameter. The code is not compiled and an executable is not built.

When you select this option, the label of the **Build** button changes to **Generate code**.

Configuring Code Comments

Configure how Real-Time Workshop inserts comments into generated code, by modifying parameters on the Comments pane.

Note Comments can include international (non-US-ASCII) characters encountered during code generation when found in Simulink block names and block descriptions, user comments on Stateflow diagrams, Stateflow object descriptions, custom TLC files, and code generation template files.

To...	Select...
Include comments in generated code	Include comments. Selecting this parameter allows you to select one or more comment types to be placed in the code.
Automatically insert comments that describe a block's code before the code in the generated file	Simulink block comments.
Include comments for blocks that were eliminated as the result of optimizations (such as parameter inlining)	Show eliminated blocks.
Include comments for parameter variable names and names of source blocks in the model parameter structure declaration in <i>model_prm.h</i>	Verbose comments for SimulinkGlobal storage class. If you do not select this parameter, parameter comments are generated if less than 1000 parameters are declared. This reduces the size of the generated file for models with a large number of parameters. When you select the parameter, parameter comments are generated regardless of the number of parameters.

For descriptions of Comments pane parameters, see “Real-Time Workshop Pane: Comments” in the Real-Time Workshop reference documentation.

Configuring Generated Identifiers

Configure how Real-Time Workshop uses symbols to name identifiers and objects by setting parameters on the **Symbols** pane.

The only symbols option available for GRT targets is **Maximum identifier length**. This is the only symbols option for GRT targets. The **Maximum identifier length** field allows you to limit the number of characters in function, type definition, and variable names. The default is 31 characters. This is also the minimum length you can specify; the maximum is 256 characters. Consider increasing identifier length for models having a deep hierarchical structure, and when exercising some of the mnemonic identifier options described below.

Within a model containing Model blocks, no collisions of constituent model names can exist. When generating code from a model that uses model referencing, the **Maximum identifier length** must be large enough to accommodate the root model name and the name mangling string (if any). A code generation error occurs if **Maximum identifier length** is too small.

When a name conflict occurs between a symbol within the scope of a higher level model and a symbol within the scope of a referenced model, the symbol from the referenced model is preserved. Name mangling is performed on the symbol from the higher level model.

If Real-Time Workshop Embedded Coder is installed on your system, the **Symbols** pane expands to include options for controlling identifier formats, mangle length, scalar inlined parameters, and Simulink data object naming rules. For details, see “Customizing Generated Identifiers” in the Real-Time Workshop Embedded Coder documentation.

For descriptions of Symbols pane parameters, see “Real-Time Workshop Pane: Symbols” in the Real-Time Workshop reference documentation.

Reserved Keywords

Real-Time Workshop reserves certain words for its own use as keywords of the generated code language. Real-Time Workshop keywords are reserved for use internal to Real-Time Workshop or C programming, and should not be used in your model as identifiers or function names. If your model contains any reserved keywords, the Real-Time Workshop build does not complete

and an error message is displayed. To address this error, modify your model to use words that are not reserved. The following tables list Real-Time Workshop Language Keywords and Real-Time Workshop Target Function Library Keywords.

Real-Time Workshop Language Keywords

abs	continue	FALSE	NULL	time_T
asm	creal_T	float	pointer_T	true
auto	creal32_T	for	real_T	TRUE
bool	creal64_T	fortran	real32_T	typedef
boolean_T	cuint8_T	goto	real64_T	uint_T
break	cuint16_T	id_t	register	uint8_T
byte_T	cuint32_T	if	return	uint16_T
case	default	int	short	uint32_T
char	do	int_T	signed	uint64_T
char_T	double	int8_T	single	union
cint8_T	else	int16_T	sizeof	unsigned
cint16_T	enum	int32_T	static	void
cint32_T	extern	int64_T	struct	volatile
const	false	long	switch	while

Real-Time Workshop Target Function Library Keywords

acos	FLT_MIN	muDoubleScalarMax	rt_Lookup32
acosf	fmax	muDoubleScalarMin	rt_MAX
acosh	fmaxf	muDoubleScalarMod	rt_MIN
acoshf	fmin	muDoubleScalarPower	truncf
asin	fminf	muDoubleScalarRound	trunc
asinf	fmod	muDoubleScalarSign	RT_PI
asinh	fmodf	muDoubleScalarSin	rt_SATURATE

Real-Time Workshop Target Function Library Keywords (Continued)

asinhf	hypot	muDoubleScalarSinh	rt_SGN
atan	hypotf	muDoubleScalarSqrt	rt_UNSGN
atan2	ldexp	muDoubleScalarTan	tanhf
atan2f	log	muDoubleScalarTanh	rt_ZCFcn
atanf	log10	pow	rtInf
atanh	log10f	powf	rtInfF
atanhf	logf	roundf	rtIsInf
ceil	memcmp	rt_ABS	rtIsInfF
ceilf	memcpy	rt_atan2	rtIsNaN
cos	memset	rt_atan232	rtIsNaNF
cosf	muDoubleScalarAbs	utAssert	rtMinusInf
cosh	muDoubleScalarAcos	rt_DIVQUOT	rtMinusInfF
coshf	muDoubleScalarAcosh	rt_DIVREM	rtNaN
DBL_EPSILON	muDoubleScalarAsin	RT_E	rtNaNF
DBL_MAX	muDoubleScalarAsinh	rt_FSGN	sin
DBL_MIN	muDoubleScalarAtan	rt_hypot	sinf
exp	muDoubleScalarAtan2	rt_hypot32	sinh
exp10	muDoubleScalarAtanh	rt_I32ZCFcn	sinhf
exp10f	muDoubleScalarCeil	rt_InitInfAndNaN	SLibSfcnHelperFcns
expf	muDoubleScalarCos	RT_LN_10	sqrt
fabs	muDoubleScalarCosh	RT_LOG10E	sqrtf
fabsf	muDoubleScalarExp	rt_Lookup	tan
floor	muDoubleScalarFloor	rt_Lookup2D_General	tanf
floorf	muDoubleScalarHypot	rt_Lookup2D_Normal	tanh

Real-Time Workshop Target Function Library Keywords (Continued)

FLT_EPSILON	muDoubleScalarLog	rt_Lookup2D32_General	
FLT_MAX	muDoubleScalarLog10	rt_Lookup2D32_Normal	

Configuring Custom Code

Configure a model such that Real-Time Workshop includes external code—headers, files and functions—in generated code by using the Custom Code pane.

Use the Custom Code pane to insert code into the generated files and to include additional files and paths in the build process.

To...	Select...
Insert custom code near the top of the generated <i>model.c</i> or <i>model.cpp</i> file, outside of any function	Source file and enter the custom code to insert.
Insert custom code near the top of the generated <i>model.h</i> file	Header file and enter the custom code to insert.
Insert custom code inside the model's initialize function in the <i>model.c</i> or <i>model.cpp</i> file	Initialize function
Insert custom code inside the model's terminate function in the <i>model.c</i> or <i>model.cpp</i> file.	Terminate function and enter the custom code to insert. Also select the Terminate function required parameter on the Interface pane.

To...	Select...
Add include directories, which contain header files, to the build process	<p>Include directories and enter the absolute or relative paths to the directories. If you specify relative paths, the paths must be relative to the directory containing your model files, not relative to the build directory. The order in which you specify the directories is the order in which they are searched for source and include files.</p>
Add source files to be compiled and linked	<p>Source files and enter the full paths or just the filenames for the files. A filename is sufficient if the file is in the current MATLAB directory or in one of the include directories. For each additional source that you specify, Real-Time Workshop expands a generic rule in the template makefile for the directory in which the source file is found. For example, if a source file is found in directory <code>inc</code>, Real-Time Workshop adds a rule similar to the following:</p> <pre data-bbox="501 730 1095 788">%.obj: buildir\inc\%.c \$(CC) -c -Fo\$(@F) \$(CFLAGS) \$<</pre> <p>Real-Time Workshop adds the rules in the order you list the source files.</p>
Add libraries to be linked	<p>Libraries and enter the full paths or just the filenames for the libraries. A file name is sufficient if the library is located in the current MATLAB directory or is listed as one of the Include directories.</p>

Note Custom code that you include in a configuration set is ignored when building S-function targets, accelerated simulation targets, and model reference simulation targets.

For descriptions of Custom Code pane parameters, see “Real-Time Workshop Pane: Custom Code” in the Real-Time Workshop reference documentation.

Troubleshooting the Build Process

Use the Debug pane to configure a model such that generated code and the build process are optimized for troubleshooting. You can set parameters that apply to the model compilation phase, the target language code generation phase, or both.

The debug parameters will be helpful if you are writing TLC code for customizing targets, integrating legacy code, or developing new blocks. .

To...	Select...
Display progress information during code generation in the MATLAB Command Window c	Verbose build. Compiler output also displays.
Prevent the build process from deleting the <i>model.rtw</i> file from the build directory at the end of the build	Retain .rtw file. This parameter is useful if you are modifying the target files, in which case you need to look at the <i>model.rtw</i> file.
Instruct the TLC profiler to analyze the performance of TLC code executed during code generation and generate a report	Profile TLC. The report is in HTML format and can be read in your Web browser.
Start the TLC debugger during code generation	Start TLC debugger when generating code. Alternatively, enter the argument <code>-dc</code> for the System Target File parameter on the Real-Time Workshop pane. To start the debugger and run a debugger script, enter <code>-df filename</code> for System Target File .

To...	Select...
To generate a report containing statistics indicating how many times Real-Time Workshop reads each line of TLC code during code generation	Start TLC coverage when generating code. Alternatively, enter the argument <code>-dg</code> for the System Target File parameter on the Real-Time Workshop pane.
Halt a build if any user-supplied TLC file contains an <code>%assert</code> directive that evaluates to <code>FALSE</code>	<p>Enable TLC assertion. Alternatively, you can use MATLAB commands to control TLC assertion handling. To set the flag on or off, use the <code>set_param</code> command. The default is off.</p> <pre>set_param(model, 'TLCAssertion', 'on off')</pre> <p>To check the current setting, use <code>get_param</code>.</p> <pre>get_param(model, 'TLCAssertion')</pre>

See the Target Language Compiler documentation for details. Also, consider using the Model Advisor as a tool for troubleshooting model builds.

For descriptions of Debug pane parameters, see “Real-Time Workshop Pane: Debug” in the Real-Time Workshop reference documentation.

Configuring Model Interfaces

Use the Interface pane to control which math library is used at run time, whether to include one of three APIs in generated code, and certain other interface options.

To...	Select or Enter...
<p>Specify the target-specific math library to use when generating code</p>	<p>Select C89/C90 (ANSI), C99 (ISO), or GNU99 (GNU) for Target function library. (Additional values may be listed if you have created and registered target function libraries with Real-Time Workshop Embedded Coder, or if you have licensed any Link or Target products.)</p> <p>Selecting C89/C90 (ANSI) provides the ANSI C set of library functions. For example, selecting C89/C90 (ANSI) would result in generated code that calls <code>sin()</code> whether the input argument is double precision or single precision. However, if you select C99 (ISO), the call instead is to the function <code>sinf()</code>, which is single precision. If your compiler supports the ISO C math extensions, selecting the ISO C library can result in more efficient code.</p> <p>For more information about target function libraries, see “Selecting and Viewing Target Function Libraries” on page 2-68.</p>
<p>Direct where Real-Time Workshop should place fixed-point and other utility code</p>	<p>Select Auto or Shared location for Utility function generation. The shared location directs code for utilities to be placed within the <code>s1prj</code> directory in your working directory, which is used for building model reference targets. If you select Auto,</p> <ul style="list-style-type: none"> • When the model contains Model blocks, utilities are placed within the <code>s1prj/target/_sharedutils</code> directory. • When the model does not contain Model blocks, utilities are placed in the build directory (generally, in <code>model.c</code> or <code>model.cpp</code>).
<p>Specify a string to be added to the variable names used when logging data to MAT-files, to distinguish logging data from Real-Time Workshop applications and Simulink</p>	<p>Enter a prefix or suffix, such as <code>rt_</code> or <code>(_rt</code>, for MAT-file variable name modifier. Real-Time Workshop prefixes or appends the string to the variable names for system outputs, states, and simulation time specified in the Data Import/Export pane. See “Configuring a Model for Data Logging” on page 2-25 for information on MAT-file data logging.</p>

To...	Select or Enter...
Specify an API to be included in generated code	Select C-API, External mode, or ASAP2 for Interface . When you select C-API or External mode, other options appear. C-API and External mode are mutually exclusive. However, this is not the case for C-API and ASAP2. For more information on working with these interfaces, see “C-API for Interfacing with Signals and Parameters” on page 17-2 and Chapter 6, “External Mode”.

Note Before setting **Target function library**, verify that your compiler supports the library you want to use. If you select a parameter value that your compiler does not support, compiler errors can occur. For example, if you select C99 (ISO) and your compiler does not support the ISO C math extensions, compile-time errors likely will occur.

When Real-Time Workshop Embedded Coder is installed on your system, the Interface pane expands to include several additional options. For details, see “Configuring Model Interfaces” in the Real-Time Workshop Embedded Coder documentation.

For a summary of option dependencies, see “Interface Dependencies” on page 2-65. For details on using the external mode interface, see Chapter 6, “External Mode”. For information on using C-API and ASAP2 interfaces see Chapter 17, “Data Exchange APIs”.

For descriptions of Interface pane parameters, see “Real-Time Workshop Pane: Interface” in the Real-Time Workshop reference documentation.

Interface Dependencies

Several parameters available on the Interface pane have dependencies on settings of other parameters. The following table summarizes the dependencies.

Parameter	Dependencies?	Dependency Details
Target function library	No	
Utility function generation	Yes	
Support floating-point numbers (ERT targets only)	No	
Support non-finite numbers (ERT targets only)	Yes	Enabled by Support floating-point numbers
Support complex numbers (ERT targets only)	No	
Support absolute time (ERT targets only)	No	
Support continuous time (ERT targets only)	No	
Support non-inlined S-functions (ERT targets only)	Yes	Requires that you enable Support floating-point numbers and Support non-finite numbers
GRT compatible call interface (ERT targets only)	Yes	Requires that you enable Support floating-point numbers and disable Single output/update function
Single output/update function (ERT targets only)	Yes	Disable for GRT compatible call interface
Terminate function required (ERT targets only)	Yes	
Generate reusable code (ERT targets only)	Yes	
Reusable code error diagnostic (ERT targets only)	Yes	Enabled by Generate reusable code
Pass root-level I/O as (ERT targets only)	Yes	Enabled by Generate reusable code

Parameter	Dependencies?	Dependency Details
Create Simulink S-Function block (ERT targets only)	No	
MAT-file logging	Yes	For ERT targets, requires that you enable Support floating-point numbers , Support non-finite numbers , and Terminate function required
MAT-file file variable name modifier (ERT targets only)	Yes	Enabled by MAT-file logging
Suppress error status in real-time model data structure (ERT targets only)	No	
Interface	No	
Signals in C API	Yes	Set Interface to C-API
Parameters in C API	Yes	Set Interface to C-API
Transport layer	Yes	Set Interface to External mode
MEX-file arguments	Yes	Set Interface to External mode
Static memory allocation	Yes	Set Interface to External mode
Static memory buffer size	Yes	Enable Static memory allocation

Selecting and Viewing Target Function Libraries

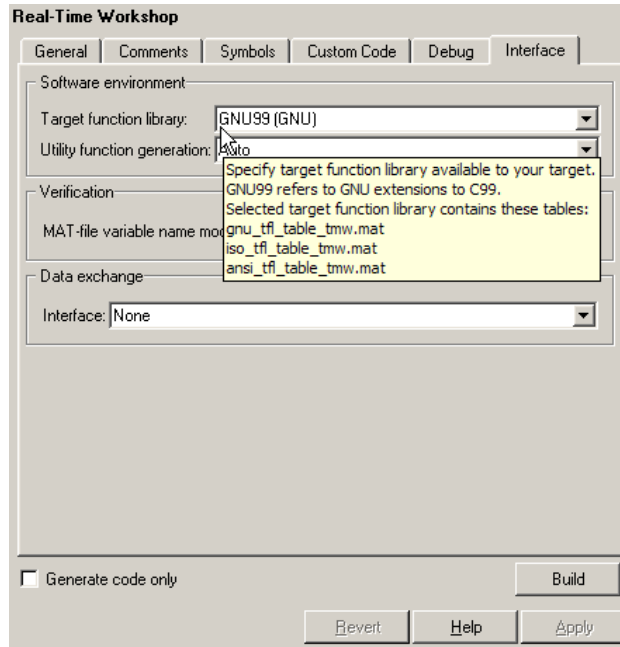
- “Selecting a Target-Specific Math Library for Your Model” on page 2-68
- “Function Replacement Table Overview” on page 2-69
- “Using the Target Function Library Viewer” on page 2-71

Selecting a Target-Specific Math Library for Your Model

A *target function library* (TFL) is a set of one or more function replacement tables that define the target-specific implementations of math functions and operators to be used in generating code for your Simulink model. Real-Time Workshop provides three default TFLs, which you can select from the **Target function library** drop-down list on the **Interface** pane of the Configuration Parameters dialog box.

TFL	Description	Contains tables...
C89/C90 (ANSI)	Generates calls to the ISO/IEC 9899:1990 C standard math library for floating-point functions.	ansi_tfl_table_tmw.mat
C99 (ISO)	Generates calls to the ISO/IEC 9899:1999 C standard math library.	iso_tfl_table_tmw.mat ansi_tfl_table_tmw.mat
GNU99 (GNU)	Generates calls to the GNU gcc math library, which provides C99 extensions as defined by compiler option <code>-std=gnu99</code> .	gnu_tfl_table_tmw.mat iso_tfl_table_tmw.mat ansi_tfl_table_tmw.mat

TFL tables provide the basis for replacing default math functions and operators in your model code with target-specific code. If you select a library and then hover over the selected library with the cursor, a tool tip is displayed that describes the TFL and lists the function replacement tables it contains. Tables are listed in the order in which they are searched for a function or operator match.



Real-Time Workshop allows you to view the content of TFL function replacement tables using the Target Function Library Viewer, as described in “Using the Target Function Library Viewer” on page 2-71. If you are licensed to use Real-Time Workshop Embedded Coder, you additionally can create and register the function replacement tables that make up a TFL.

Function Replacement Table Overview

Each TFL function replacement table contains one or more table entries, with each table entry representing a potential replacement for a single math function or an operator. Each table entry provides a mapping between a *conceptual view* of the function or operator (similar to the Simulink block view of the function or operator) and a *target-specific implementation* of that function or operator.

The conceptual view of a function or operator is represented in a TFL table entry by the following elements, which identify the function or operator entry to the code generation process:

- A function or operator key (a function name such as 'cos' or an operator ID string such as 'RTW_OP_ADD')
- A set of conceptual arguments that observe Simulink-based naming ('y1', 'u1', 'u2', ...), along with their I/O types (output or input) and data types
- Other attributes, such as fixed-point saturation and rounding characteristics for operators, as needed to identify the function or operator to the code generation process as exactly as required for matching purposes

The target-specific implementation of a function or operator is represented in a TFL table entry by the following elements:

- The name of an implementation function (such as 'cos_dbl' or 'u8_add_u8_u8')
- A set of implementation arguments, along with their I/O types (output or input) and data types
- Parameters providing the build information for the implementation function, including header file and source file names and paths as necessary

Additionally, a TFL table entry includes a priority value (0-100, with 0 as the highest priority), which defines the entry's priority relative to other entries in the table.

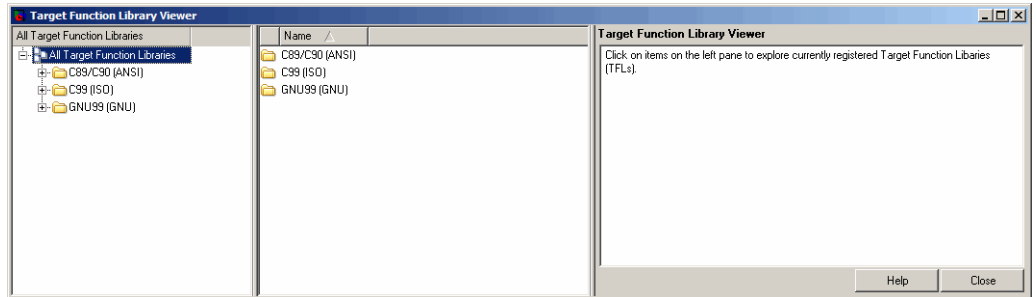
During code generation for your model, when the code generation process encounters a call site for a math function or operator, it creates and partially populates a TFL entry object, for the purpose of querying the TFL database for a replacement function. The information provided for the TFL query includes the function or operator key and the conceptual argument list. The TFL entry object is then passed to the TFL and, if there is a matching table entry in the TFL, a fully-populated TFL entry, including the implementation function name, argument list, and build information, is returned to the call site and used to generate code.

Within the TFL that is selected for your model, the tables that comprise the TFL are searched in the order in which they are listed (in the left or right pane of the TFL Viewer or in the TFL's **Target function library** tool tip). Within each table, if multiple matches are found for a TFL entry object, priority level determines the match that is returned. A higher-priority (lower-numbered) entry will be used over a similar entry with a lower priority (higher number).

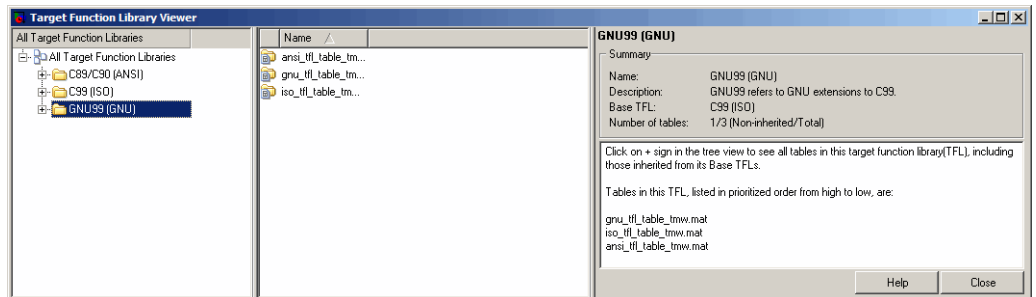
Using the Target Function Library Viewer

The Target Function Library Viewer allows you to examine the content of TFL function replacement tables. (For an overview of function replacement tables and the information they contain, see the preceding section.) To launch the Viewer with all currently registered TFLs displayed, issue the following MATLAB command:

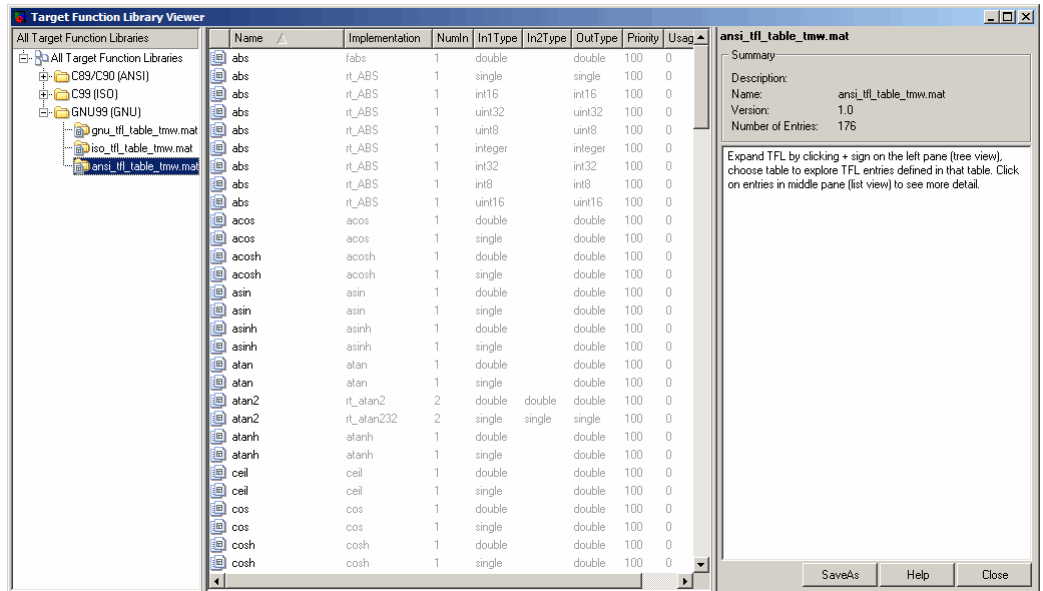
```
>> RTW.viewTfl
```



Select the name of a TFL in the left pane, and the Viewer displays information about the TFL in the right pane. For example, the tables that make up the TFL are listed in priority order. In the following display, the GNU TFL has been selected.



Click the plus sign (+) next to a TFL name in the left pane to expand its list of tables, and select a table from the list. The Viewer displays all function and operator entries in the selected table in the middle pane, along with abbreviated table entry information for each entry. In the following display, the ANSI table has been selected.



The following fields appear in the abbreviated table entry information provided in the middle pane:

Field	Description
Name	Name of the function or ID of the operator to be replaced (for example, cos or RTW_OP_ADD).
Implementation	Name of the implementation function, which can match or differ from Name.
NumIn	Number of input arguments.
In1Type	Data type of the first conceptual input argument.
In2Type	Data type of the second conceptual input argument.
OutType	Data type of the conceptual output argument.

Field	Description
Priority	The entry's search priority, 0-100, relative to other entries of the same name and conceptual argument list within this table. Highest priority is 0, and lowest priority is 100. The default is 100. If the table provides two implementations for a function or operator, the implementation with the higher priority will shadow the one with the lower priority.
UsageCount	Not used.

Select a function or operator entry in the middle pane. The Viewer displays detailed information from the table entry in the right pane. In the following display, the second entry for the cos function has been selected.

The screenshot shows the Target Function Library Viewer window. The left pane displays a tree view of target function libraries, including C89/C90 (ANSI), C99 (ISO), GNU99 (GNU), and various math libraries. The middle pane shows a table of functions with columns: Name, Implementation, NumIn, In1Type, In2Type, OutType, Priority, and Usage. The 'cos' function is selected, and the right pane displays its detailed information.

Name	Implementation	NumIn	In1Type	In2Type	OutType	Priority	Usage
abs	fabs	1	double		double	100	0
abs	rt_ABS	1	single		single	100	0
abs	rt_ABS	1	int16		int16	100	0
abs	rt_ABS	1	uint32		uint32	100	0
abs	rt_ABS	1	uint8		uint8	100	0
abs	rt_ABS	1	integer		integer	100	0
abs	rt_ABS	1	int32		int32	100	0
abs	rt_ABS	1	int8		int8	100	0
abs	rt_ABS	1	uint16		uint16	100	0
acos	acos	1	double		double	100	0
acos	acos	1	single		double	100	0
acosh	acosh	1	single		double	100	0
asin	asin	1	double		double	100	0
asin	asin	1	single		double	100	0
asinh	asinh	1	double		double	100	0
asinh	asinh	1	single		double	100	0
atan	atan	1	double		double	100	0
atan	atan	1	single		double	100	0
atan2	rt_atan2	2	double	double	double	100	0
atan2	rt_atan232	2	single	single	single	100	0
atanh	atanh	1	double		double	100	0
atanh	atanh	1	single		double	100	0
ceil	ceil	1	double		double	100	0
ceil	ceil	1	single		double	100	0
cos	cos	1	double		double	100	0
cos	cos	1	single		double	100	0
cosh	cosh	1	double		double	100	0
cosh	cosh	1	single		double	100	0

cos

General Information

-Summary-

Description:

Key: cos with 1 input(s)

Implementation: cos () with 1 input(s)

Implementation type: FCN_IMPL_FUNCT

Saturation mode: RTW_SATURATE_UNSPECIFIED

Rounding mode: RTW_ROUND_UNSPECIFIED

GenCallback file:

Implementation header: <math.h>

Implementation source:

Priority: 100

Total Usage Count: 0

Entry argument(s)

Conceptual argument(s):

Name	I/O type	Data type
y1	RTW_IQ_OUTPUT	single
u1	RTW_IQ_INPUT	single

Implementation:

Name	I/O type	Data type
y1	RTW_IQ_OUTPUT	double
u1	RTW_IQ_INPUT	single

Help Close

The following fields appear in the detailed table entry information provided in the right pane.

Field	Description
Description	Text description of the table entry (can be empty).
Key	Name of the function or ID of the operator to be replaced (for example, <code>cos</code> or <code>RTW_OP_ADD</code>), and the number of conceptual input arguments.
Implementation	Name of the implementation function, and the number of implementation input arguments.
Implementation type	Type of implementation: <code>FCN_IMPL_FUNCT</code> for function or <code>FCN_IMPL_MACRO</code> for macro.
Saturation mode	Saturation mode supported by the implementation function for an operator replacement: <code>RTW_SATURATE_ON_OVERFLOW</code> , <code>RTW_WRAP_ON_OVERFLOW</code> , or <code>RTW_SATURATE_UNSPECIFIED</code> .
Rounding mode	Rounding mode supported by the implementation function for an operator replacement: <code>RTW_ROUND_FLOOR</code> , <code>RTW_ROUND_CEILING</code> , <code>RTW_ROUND_ZERO</code> , <code>RTW_ROUND_NEAREST</code> , <code>RTW_ROUND_NEAREST_ML</code> , <code>RTW_ROUND_SIMPLEST</code> , <code>RTW_ROUND_CONV</code> , or <code>RTW_ROUND_UNSPECIFIED</code> .
GenCallback file	Not used.
Implementation header	Name of the header file that declares the implementation function.
Implementation source	Name of the implementation source file.
Priority	The entry's search priority, 0-100, relative to other entries of the same name and conceptual argument list within this table. Highest priority is 0, and lowest priority is 100. The default is 100. If the table provides two implementations for a function or operator, the implementation with the higher priority will shadow the one with the lower priority.

Field	Description
Total Usage Count	Not used.
Conceptual argument(s)	Name, I/O type (RTW_IO_OUTPUT or RTW_IO_INPUT), and data type for each conceptual argument.
Implementation	Name, I/O type (RTW_IO_OUTPUT or RTW_IO_INPUT), and data type for each implementation argument.

If you select an operator entry, an additional tab containing fixed-point setting information is displayed in the right pane. For example:

The screenshot shows the **RTW_OP_ADD** dialog box with two tabs: **General Information** and **Fixed-point Settings**. The **Fixed-point Settings** tab is active, displaying a **Summary** section with the following values:

- Slopes must be the same: no
- Must have zero net bias: no
- Relative scaling factor F: 1
- Relative scaling factor E: 0

Below the summary is the **Entry argument(s)** section, which contains two tables:

Conceptual argument(s):

Name	I/O type	Data type
y1	RTW_IO_OUTPUT	int16
u1	RTW_IO_INPUT	int16
u2	RTW_IO_INPUT	int16

Implementation:

Name	I/O type	Data type
y1	RTW_IO_OUTPUT	int16
u1	RTW_IO_INPUT	int16
u2	RTW_IO_INPUT	int16

At the bottom of the dialog are **Help** and **Close** buttons.

The following fields appear in the fixed-point setting information provided in the right pane:

Field	Description
Slopes must be the same	Indicates whether TFL replacement request processing must check that the slopes on all arguments (input and output) are equal. Used with fixed-point addition and subtraction replacement to disregard specific slope and bias values and map relative slope and bias values to a replacement function.
Must have zero net bias	Indicates whether TFL replacement request processing must check that the net bias on all arguments is zero. Used with fixed-point addition and subtraction replacement to disregard specific slope and bias values and map relative slope and bias values to a replacement function.
Relative scaling factor F	Slope adjustment factor (F) part of the relative scaling factor, $F2^E$, for relative scaling TFL entries. Used with fixed-point multiplication and division replacement to map a range of slope and bias values to a replacement function.
Relative scaling factor E	Fixed exponent (E) part of the relative scaling factor, $F2^E$, for relative scaling TFL entries. Used with fixed-point multiplication and division replacement to map a range of slope and bias values to a replacement function.

Configuring Generated Code with TLC

In this section...
“Introduction” on page 2-77
“Assigning Target Language Compiler Variables” on page 2-77
“Setting Target Language Compiler Options” on page 2-79

Introduction

You can use the Target Language Compiler (TLC) to fine tune your generated code. TLC supports extended code generation variables and options in addition to those included in the code generation options categories of the **Real-Time Workshop** pane. There are two ways to set TLC variables and options, as described in this section.

Note You should not customize TLC files in the directory `matlabroot/rtw/c/tlc` even though the capability exists to do so. Such TLC customizations might not be applied during the code generation process and can lead to unpredictable results.

Assigning Target Language Compiler Variables

The `%assign` statement lets you assign a value to a TLC variable, as in

```
%assign MaxStackSize = 4096
```

This is also known as creating a *parameter name/parameter value pair*.

For a description of the `%assign` statement see the Target Language Compiler documentation. You should write your `%assign` statements in the **Configure RTW code generation settings** section of the system target file.

The following table lists the code generation variables you can set with the `%assign` statement.

Target Language Compiler Optional Variables

Variable	Description
MaxStackSize=N	<p>When the Local block outputs check box is selected, the total allocation size of local variables that are declared by all block outputs in the model cannot exceed MaxStackSize (in bytes). MaxStackSize can be any positive integer. If the total size of local block output variables exceeds this maximum, the remaining block output variables are allocated in global, rather than local, memory. The default value for MaxStackSize is <code>rtInf</code>, that is, unlimited stack size.</p> <p>Note: Local variables in the generated code from sources other than local block outputs, such as Stateflow or the Embedded MATLAB Function block, and stack usage from sources such as function calls and context switching are not included in the MaxStackSize calculation. For overall executable stack usage metrics, do a target-specific measurement by using run-time (empirical) analysis or static (code path) analysis with object code.</p>
MaxStackVariableSize=N	<p>When the Local block outputs check box is selected, this limits the size of any local block output variable declared in the code to N bytes, where $N > 0$. A variable whose size exceeds MaxStackVariableSize is allocated in global, rather than local, memory. The default is 4096.</p>
WarnNonSaturatedBlocks= <i>value</i>	<p>Flag to control display of overflow warnings for blocks that have saturation capability, but have it turned off (unchecked) in their dialog. These are the options:</p> <ul style="list-style-type: none"> • 0 — No warning is displayed. • 1 — Displays one warning for the model during code generation • 2 — Displays one warning that contains a list of all offending blocks

For more information, see the Target Language Compiler documentation.

Setting Target Language Compiler Options

You can enter TLC options directly into the **System target file** field in the **Real-Time Workshop** general pane of the Configuration Parameters dialog box, by appending the options and arguments to the system target filename. This is equivalent to invoking the Target Language Compiler with options on the MATLAB command line. The most common options are shown in the following table.

Target Language Compiler Options

Option	Description
-I <i>path</i>	Adds <i>path</i> to the list of paths in which to search for target files (.tlc files).
-m[<i>N</i> <i>a</i>]	Maximum number of errors to report when an error is encountered (default is 5). For example, -m3 specifies that at most three errors will be reported. To report all errors, specify -ma.
-d[g n o]	Specifies debug mode (generate, normal, or off). Default is off. When -dg is specified, a .log file is create for each of your TLC files. When debug mode is enabled (that is, generate or normal), the Target Language Compiler displays the number of times each line in a target file is encountered.
-aRTWCAPI	-aRTWCAPI=1 to generate API for both signals and parameters
-aRTWCAPISignals	-aRTWCAPISignals=1 to generate API for signals only

Target Language Compiler Options (Continued)

Option	Description
-aRTWCAPIParams	-aRTWCAPIParams=1 to generate API for parameters only
-aVariable=val	Equivalent to the TLC statement %assign Variable = val Note: It is best to use %assign statements in the TLC files, rather than the -a option.

You can speed your TLC development cycle by not rebuilding code when your TLC files have changed, but your model has not. See “Retain .rtw file” in the Real-Time Workshop reference documentation for information on how to do this.

For more information on TLC options, see the Target Language Compiler documentation.

Interacting with the Build Process

In this section...

- “Introduction” on page 2-81
- “Initiating the Build Process” on page 2-81
- “Construction of Symbols” on page 2-82
- “Generated Source Files and File Dependencies” on page 2-84
- “Reloading Code from the Model Explorer” on page 2-104
- “Rebuilding Generated Code” on page 2-104
- “Profiling Generated Code” on page 2-105

Introduction

Real-Time Workshop generates code into a set of source files that vary little among different targets. Not all possible files are generated for every model. Some files are created only when the model includes subsystems, calls external interfaces, or uses particular types of data. Real-Time Workshop handles most of the code formatting decisions (such as identifier construction and code packaging) in consistent ways.

Initiating the Build Process

You can initiate code generation and the build process by using the following options:

- Clear the **Generate code only** option on the **Real-Time Workshop** pane of the Configuration Parameters dialog box and click **Build**.
- Press **Ctrl+B**.
- Select **Tools > Real-Time Workshop > Build Model**.
- Invoke the `rtwbuild` command from the MATLAB command line, using one of the following syntax options:

```
rtwbuild src
rtwbuild('src')
```

For *src*, specify the name of a model or subsystem. The command initiates the build process with the current model configuration settings and creates an executable. If the model or subsystem is not loaded into Simulink, `rtwbuild` loads it before initiating the build process.

For more information on using subsystems, see Chapter 4, “Building Subsystems and Working with Referenced Models”.

- Invoke the `slbuild` command from the MATLAB command line, using one of the following syntax options:

```
slbuild model
slbuild model 'buildtype'
slbuild('model')
slbuild('model' 'buildtype')
```

For *model*, specify the name of a model for which you want to build a stand-alone Real-Time Workshop target executable or a model reference target. The *buildtype* can be one of the following:

- `ModelReferenceSimTarget` builds a model reference simulation target
- `ModelReferenceRTWTarget` builds a model reference simulation and Real-Time Workshop targets
- `ModelReferenceRTWTargetOnly` builds a model reference Real-Time Workshop target

The command initiates the build process with the current model configuration settings. If the model is not loaded into Simulink, `slbuild` loads it before initiating the build process.

For more information on model referencing, see “Generating Code for Model Referencing” on page 4-26.

Construction of Symbols

For GRT, GRT-malloc and RSim targets, Real-Time Workshop automatically constructs identifiers for variables and functions in the generated code. These symbols identify

- Signals and parameters that have Auto storage class
- Subsystem function names that are not user defined

- All Stateflow names

The components of a generated symbol include

- The root model name, followed by
- The name of the generating object (signal, parameter, state, and so on), followed by
- A unique *name mangling* string

The name mangling string is conditionally generated only when necessary to resolve potential conflicts with other generated symbols.

The length of generated symbols is limited by the **Maximum identifier length** parameter specified on the **Symbols** pane of the Configuration Parameters dialog box. When there is a potential name collision between two symbols, a name mangling string is generated. The string has the minimum number of characters required to avoid the collision. The other symbol components are then inserted. If **Maximum identifier length** is not large enough to accommodate full expansions of the other components, they are truncated. To avoid this outcome, it is good practice to

- Avoid name collisions in general. One way to do this is to avoid using default block names (for example, Gain1, Gain2. . .) when there are many blocks of the same type in the model. Also, whenever possible, make subsystems atomic and reusable.
- Where possible, increase the **Maximum identifier length** parameter to accommodate the length of the symbols you expect to generate.

Maximum identifier length can be longer for top model than referenced models. Model referencing can involve additional naming constraints. For information, see “Configuring Generated Identifiers” on page 2-57 and “Parameterizing Model References”.

Users of Real-Time Workshop Embedded Coder have additional flexibility over how symbols are constructed, by using a **Symbol format** field that controls the symbol formatting in much greater detail. See “Code Generation Options and Optimizations” in the Real-Time Workshop Embedded Coder documentation for more information.

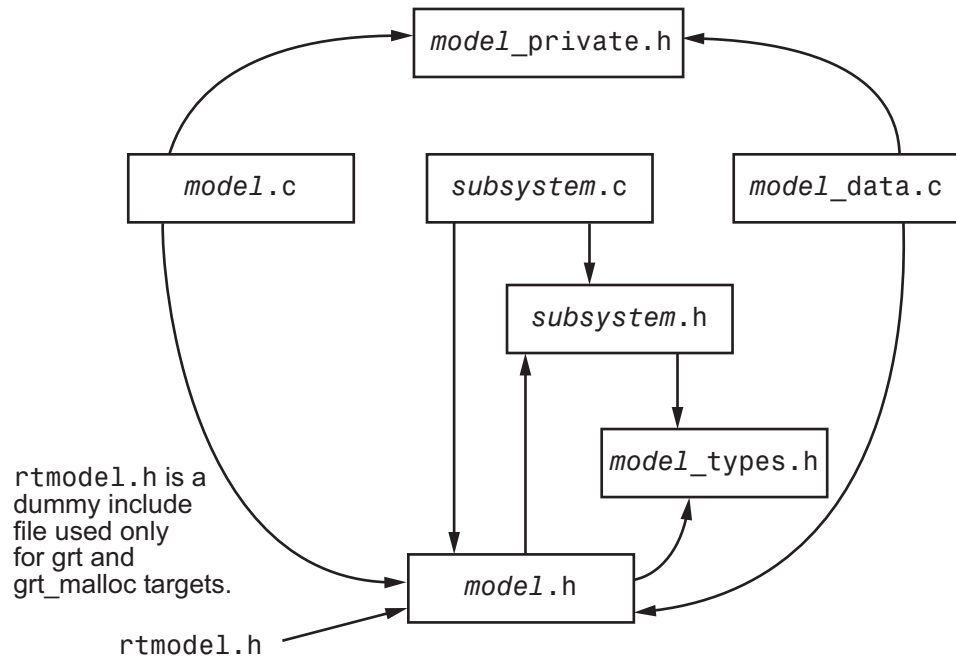
Generated Source Files and File Dependencies

The source and make files created by Real-Time Workshop are generated into your build directory, which is created or reused in your current directory. Some files are unconditionally generated, while the existence of others depend on target settings and options (for example, support files for C-API or external mode). See “Files and Directories Created by the Build Process” in Getting Started for descriptions of the generated files.

Note The file packaging of Real-Time Workshop Embedded Coder targets differs slightly from the file packaging described below. See “Code Modules” in the Real-Time Workshop Embedded Coder documentation for more information.

Real-Time Workshop generated source file dependencies are depicted in the next figure. Arrows coming from a file point to files it includes. As the figure notes, other dependencies exist, for example on Simulink header files `tmwtypes.h`, `simstruc_types.h`, and optionally on `rtlibsrc.h`, plus C or C++ library files. The figure maps inclusion relations between only those files that are generated in the build directory. Utility and model reference code located in a project directory might also be referenced by these files. See “Project Directory Structure for Model Reference Targets” on page 4-28 for details.

The figure shows that parent system header files (`model.h`) include all child subsystem header files (`subsystem.h`). In more layered models, subsystems similarly include their children’s header files, on down the model hierarchy. As a consequence, subsystems are able to recursively “see” into all their descendants’ subsystems, as well as to see into the root system (because every `subsystem.c` or `subsystem.cpp` includes `model.h` and `model_private.h`).



Real-Time Workshop Generated File Dependencies

Note In the preceding figure, files *model.h*, *model_private.h*, and *subsystem.h* also depend on Real-Time Workshop header file *rtwtypes.h*, and conditionally on *rtlibsrc.h*. Targets that are not based on the ERT target can have additional dependencies on *tmwtypes.h* and *simstruct_types.h*.

Header Dependencies When Interfacing Legacy/Custom Code with Generated Code

You can incorporate legacy or custom code into a Real-Time Workshop build in any of several ways. One common approach is by creating S-functions. For details on this approach, see Chapter 10, “Writing S-Functions for Real-Time Workshop Code Generation”.

Another approach is to interface code using global variables created by declaring storage classes for signals and parameters. This requires

customizing an outer code harness, typically referred to as a `main.c` or `main.cpp` file, to properly execute to the generated code. In addition, the harness can contain custom code.

These scenarios require you to include header files specific to Real-Time Workshop to make available the needed function declarations, type definitions, and defines to the legacy or custom code.

rtwtypes.h. The header file `rtwtypes.h` defines data types, structures, and macros required by the code that Real-Time Workshop generates. Normally, you should include `rtwtypes.h` for both GRT and ERT targets instead of including `tmwtypes.h` or `simstruct_types.h`. However, the contents of the header file varies depending on your target selection.

For...	rtwtypes.h
GRT target	Provides a complete set of definitions by including <code>tmwtypes.h</code> and <code>simstruct_types.h</code> , both of which depend on <ul style="list-style-type: none"> • System headers <code>limits.h</code> and <code>float.h</code> • Headers specific to Real-Time Workshop: <code>rtw_matlogging.h</code>, <code>rtw_extmode.h</code>, <code>rtw_continuous.h</code>, and <code>rtw_solver.h</code>
ERT target and targets based on the ERT target	Is optimized, when possible, to include a minimum set of <code>#define</code> statements, enumerations, and so on; does not include <code>tmwtypes.h</code> and <code>simstruct_types.h</code>

Real-Time Workshop generates the optimized version of `rtwtypes.h` for the ERT target when both of the following conditions exist:

- The **GRT compatible call interface** option on the **Real-Time Workshop > Interface**pane of the Configuration Parameters dialog box is cleared.
- The model contains no noninlined S-functions

You should always include `rtwtypes.h`. If you include it for GRT targets, for example, it is easier to use your code with ERT-based targets.

rtwtypes.h for GRT targets:

```

#ifndef __RTWTYPES_H__
#define __RTWTYPES_H__
#include "tmwtypes.h"

/* This ID is used to detect inclusion of an incompatible
 * rtwtypes.h
 */
#define RTWTYPES_ID_C08S16I32L32N32F1

#include "simstruc_types.h"
#ifndef POINTER_T
# define POINTER_T
typedef void * pointer_T;
#endif
#ifndef TRUE
# define TRUE (1)
#endif
#ifndef FALSE
# define FALSE (0)
#endif
#endif

```

Top of rtwtypes.h for ERT targets:

```

#ifndef __RTWTYPES_H__
#define __RTWTYPES_H__
#ifndef __TMWTYPES__
#define __TMWTYPES__

#include <limits.h>

/*=====
 * Target hardware information
 * Device type: 32-bit Generic
 * Number of bits:   char:   8   short:  16   int:  32
 *                   long:  32   native word size:  32
 * Byte ordering: Unspecified
 * Signed integer division rounds to: Undefined
 * Shift right on a signed integer as arithmetic shift: on
 */

```

```

*=====*/

/* This ID is used to detect inclusion of an incompatible rtwtypes.h */
#define RTWTYPES_ID_C08S16I32L32N32F1

/*=====*
 * Fixed width word size data types:
 *
 * int8_T, int16_T, int32_T    - signed 8, 16, or 32 bit integers
 * uint8_T, uint16_T, uint32_T - unsigned 8, 16, or 32 bit integers
 * real32_T, real64_T        - 32 and 64 bit floating point numbers
 *=====*/

typedef signed char int8_T;
typedef unsigned char uint8_T;
typedef short int16_T;
typedef unsigned short uint16_T;
typedef int int32_T;
typedef unsigned int uint32_T;
typedef float real32_T;
typedef double real64_T;
. . .

```

For GRT and ERT targets, the location of `rtwtypes.h` depends on whether the build uses the *shared utilities* location. If you use a shared location, Real-Time Workshop places `rtwtypes.h` in `slprj/target/_sharedutils`; otherwise, it places `rtwtypes.h` in the standard build directory (*model_target_rtw*). See “Sharing Utility Functions” on page 4-49 for more information on when and how to use the shared utilities location.

The header file `rtwtypes.h` should be included by source files that use Real-Time Workshop type names or other Real-Time Workshop definitions. A typical example is for files that declare variables using a Real-Time Workshop data type, for example, `uint32_T myvar;`

A source file that is intended to be used by Real-Time Workshop and by a Simulink S-function can leverage the preprocessor macro `MATLAB_MEX_FILE`, which is defined by the mex function:

```
#ifdef MATLAB_MEX_FILE
#include "tmwtypes.h"

```

```
#else
#include "rtwtypes.h"
#endif
```

A source file meant to be used as the Real-Time Workshop `main.c` (or `.cpp`) file would also include `rtwtypes.h` without any preprocessor checks.

```
#include "rtwtypes.h"
```

Custom source files that are generated using the Target Language Compiler can also emit these `include` statements into their generated file.

model.h. The header file `model.h` declares model data structures and a public interface to the model entry points and data structures. This header file also provides an interface to the real-time model data structure (`model_M`) by using access macros. If your code interfaces to model functions or model data structures, as illustrated below, you should include `model.h`:

- Exported global signals

```
extern int32_T INPUT;    /* '<Root>/In' */
```

- Global structure definitions

```
/* Block parameters (auto storage) */
extern Parameters_mymodel mymodel_P;
```

- RTM macro definitions

```
#ifndef rtmGetSampleTime
# define rtmGetSampleTime(rtm, idx)
((rtm)->Timing.sampleTimes[idx])
#endif
```

- Model entry point functions (ERT example)

```
extern void mymodel_initialize(void);
extern void mymodel_step(void);
extern void mymodel_terminate(void);
```

A Real-Time Workshop target's `main.c` (or `.cpp`) file should include `model.h`. If the `main.c` (or `.cpp`) file is generated from a TLC script, the TLC source can include `model.h` using:

```
#include "%<CompiledModel.Name>.h"
```

If `main.c` or `main.cpp` is a static source file, a fixed header filename can be used, `rtmodel.h` for GRT or `autobuild.h` for ERT. These files include the `model.h` header file:

```
#include "model.h" /* If main.c is generated */
```

or

```
#include "rtmodel.h" /* If static main.c is used with GRT */
```

or

```
#include "autobuild.h" /* If static main.c is used with ERT */
```

Other custom source files may also need to include `model.h` if there is a need to interface to model data, for example exported global parameters or signals. The `model.h` file itself can have additional header dependencies, as listed in the tables System Header Files on page 2-90 and Real-Time Workshop Header Files on page 2-93, due to requirements of generated code.

System Header Files

Header File	Purpose	GRT Targets	ERT Targets
<float.h>	Defines math constants	Not included	Included when generated code honors the Stop time solver configuration parameter due to one of the following Real-Time Workshop interface option settings: <ul style="list-style-type: none"> • MAT-file logging selected • Interface set to External mode

System Header Files (Continued)

Header File	Purpose	GRT Targets	ERT Targets
<math.h>	Provides floating-point math functions	Always included	Included if you select the Real-Time Workshop interface configuration parameter Support floating-point numbers
<stddef.h>	Defines NULL	Always included	Always included
<stdio.h>	Provides file I/O functions	Included when the model includes a To File block	Included when the model includes a To File block and you select the MAT-file logging Real-Time Workshop interface configuration parameter

System Header Files (Continued)

Header File	Purpose	GRT Targets	ERT Targets
<stdlib.h>	Provides utility functions such as <code>div()</code> and <code>abs()</code>	Included when the model includes <ul style="list-style-type: none"> • A Stateflow chart • A Math Function block configured for <code>mod()</code> or <code>rem()</code>, which generate calls to <code>div()</code> 	Included when the model includes <ul style="list-style-type: none"> • A Stateflow chart and you select the Support floating-point numbers Real-Time Workshop interface configuration parameter • A Math Function block configured for <code>mod()</code> or <code>rem()</code>, which generate calls to <code>div()</code>
<string.h>	Provides memory functions such as <code>memset()</code> and <code>memcpy()</code>	Always included due to use of <code>memset()</code> in model initialization code	Included when block or model initialization code calls <code>memcpy()</code> or <code>memset()</code> For a list of relevant blocks, enter <code>showblockdatatypetable</code> in the MATLAB Command Window and look for blocks with the N2 note. To omit calls to <code>memset()</code> from model initialization code, select the Remove root level I/O zero initialization and Remove internal state zero initialization optimization configuration parameters.

Real-Time Workshop Header Files

Header File	Purpose	GRT Targets	ERT Targets
<code>dt_info.h</code>	Defines data structures for external mode	Included when you configure a model for external mode	Included when you configure a model for external mode
<code>ext_work.h</code>	Defines external mode functions	Included when you configure a model for external mode	Included when you configure a model for external mode
<code>fixedpoint.h</code>	Provides fixed-point support for noninlined S-functions	Always included	Included when either of the following conditions exists: <ul style="list-style-type: none"> • The model uses noninlined S-functions • You select the Real-Time Workshop interface configuration parameter GRT compatible call interface
<code>model_types.h</code>	Defines model-specific data types	Always included	Always included
<code>rt_logging.h</code>	Supports MAT-file logging	Always included	Included when you select the Real-Time Workshop interface configuration parameter MAT-file logging
<code>rt_nonfinite.h</code>	Provides support for nonfinite numbers in the generated code	Always included	Included when you select one of the following Real-Time Workshop interface configuration parameters: <ul style="list-style-type: none"> • MAT-file logging • Support non-finite numbers (and the generated code requires non-finite numbers)

Real-Time Workshop Header Files (Continued)

Header File	Purpose	GRT Targets	ERT Targets
rtlibsrc.h	Provides functions, macros, and constants defined in the Real-Time Workshop library	Included when generated code uses the Real-Time Workshop library	Included when generated code uses the Real-Time Workshop library
rtw_continuous.h	Supports continuous time	Always included by simstruc_types.h	Included when you select the Real-Time Workshop interface configuration parameter Support continuous time and simstruc.h is not already included
rtw_extmode.h	Supports external mode	Always included by simstruc_types.h	Included when you configure the model for external mode and simstruc.h is not already included
rtw_matlogging.h	Supports MAT-file logging	Included by simstruc_types.h and rtw_logging.h	Included by rtw_logging.h
rtw_solver.h	Supports continuous states	Always included by simstruc_types.h	Included when you select the Real-Time Workshop interface configuration parameter Support floating-point numbers and simstruc.h is not already included

Real-Time Workshop Header Files (Continued)

Header File	Purpose	GRT Targets	ERT Targets
rtwtypes.h	Defines Real-Time Workshop data types; generated file	Always included; use the complete version of the file, which includes tmwtypes.h and simstruc_types.h (see simstruc_types.h for dependencies)	Always included; use the complete or optimized version of the file as explained in “rtwtypes.h” on page 2-86
simstruc.h	Provides support for calling noninlined S-functions that use the Simstruct definition; also includes limits.h, string.h, tmwtypes.h, and simstruc_types.h	Always included	Included when either of the following conditions exists: <ul style="list-style-type: none"> • The model uses noninlined S-functions • You select the Real-Time Workshop interface configuration parameter GRT compatible call interface
simstruc_types.h	Provides definitions used by generated code and includes the header files rtw_matlogging.h, rtw_extmode.h, rtw_continuous.h, rtw_solver.h, and sysran_types.h	Always included with rtwtypes.h	Not included; rtwtypes.h contains needed definitions and <i>model.h</i> contains needed header files
sysran_types.h	Supports external mode	Always included by simstruc_types.h	Included when you configure the model for external mode and simstruc.h is not already included

Note Header file dependencies noted in the preceding table apply to the system target files `grt.tlc` and `ert.tlc`. Targets derived from these base targets may have additional header dependencies. Also, code generation for blocks from blocksets, embedded targets, and custom S-functions may introduce additional header dependencies.

Dependencies of the Model's Generated code

Real-Time Workshop can directly build standalone executables for the host system such as when using the GRT target. Several processor- and OS-specific targets also provide automated builds using a cross-compiler. All of these targets are typically makefile-based interfaces for which Real-Time Workshop provides a “Template MakeFile (TMF) to makefile” conversion capability. Part of this conversion process is to include in the generated makefile all of the source file, header file, and library file information needed (the dependencies) for a successful compilation.

In other instances, the generated model code needs to be integrated into a specific application. Or, it may be desired to enter the generated files and any file dependencies into a configuration management system. This section discusses the various aspects of the generated code dependencies and how to determine them.

Typically, the generated code for a model consists of a small set of files:

- `model.c` or `model.cpp`
- `model.h`
- `model_data.c` or `model_data.cpp`
- `model_private.h`
- `rtwtypes.h`

These are generated in the build directory for a standalone model or a subdirectory under the `slprj` directory for a model reference target. There is also a top-level `main.c` (or `.cpp`) file that calls the top-level model functions to execute the model. `main.c` (or `.cpp`) is a static (not generated) file (such as `grt_main.c` or `grt_main.cpp` for GRT-based targets), and is either a

static file (`ert_main.c` or `ert_main.cpp`) or is dynamically generated for ERT-based targets.

The preceding files also have dependencies on other files, which occur due to:

- Including other header files
- Using macros declared in other header files
- Calling functions declared in other source files
- Accessing variables declared in other source files

These dependencies are introduced for a number of reasons such as:

- Blocks in a model generate code that makes function calls. This can occur in several forms:
 - The called functions are declared in other source files. In some cases such as a blockset, these source file dependencies are typically managed by compiling them into a library file.
 - In other cases, the called functions are provided by the compilers own run-time library, such as for functions in the ANSI-C header, `math.h`.
 - Some function dependencies are themselves generated files. Some examples are for fixed-point utilities and nonfinite support. These dependencies are referred to as shared utilities. The generated functions can appear in files in the build directory for standalone models or in the `_sharedutils` directory under the `slprj` directory for builds that involve model reference.
- Models with continuous time require solver source code files.
- Real-Time Workshop options such as external mode, C-API, and MAT-file logging are examples that trigger additional dependencies.
- Specifying custom code can introduce dependencies.

Providing the Dependencies. Real-Time Workshop provides several mechanisms for feeding file dependency information into the Real-Time Workshop build process. The mechanisms available to you depend on whether your dependencies are block based or are model or target based.

For block dependencies, consider using

- S-functions and blocksets
 - Directories that contain S-function MEX-files used by a model are added to the header include path.
 - Makefile rules are created for these directories to allow source code to be found.
 - For S-functions that are not inlined with a TLC file, the S-function source filename is added to the list of sources to compile.
 - The S-Function block parameter `SFunctionModules` provides the ability to specify additional source filenames.
 - The `rtwmakecfg.m` mechanism provides further capability in specifying dependencies. See “Using the `rtwmakecfg.m` API” on page 10-84 for more information.

For more information on applying these approaches to legacy or custom code integration, see Chapter 10, “Writing S-Functions for Real-Time Workshop Code Generation”.

- S-Function Builder block, which provides its own GUI for specifying dependency information

For model- or target-based dependencies, such as custom header files, consider using

- The **Real-Time Workshop/Custom Code** pane of the Configuration Parameters dialog box, which provides the ability to specify additional libraries, source files, and include directories.
- TLC functions `LibAddToCommonIncludes()` and `LibAddToModelSources()`, which allow you to specify dependencies during the TLC phase. See “`LibAddToCommonIncludes(incFileName)`” and “`LibAddSourceFileCustomSection(file, builtInSection, newSection)`” in the Target Language Compiler documentation for details. Real-Time Workshop Embedded Coder also provides a TLC-based customization template capability for generating additional source files.

Makefile Considerations. As previously mentioned, Real-Time Workshop targets are typically makefile based and Real-Time Workshop provides a “Template MakeFile (TMF) to makefile” conversion capability. The template makefile contains a token expansion mechanism in which the build process expands different tokens in the makefile to include the additional dependency information. The resulting makefile contains the complete dependency information. See Developing Embedded Targets in the Real-Time Workshop Embedded Coder documentation for more information on working with template makefiles.

The generated makefile contains the following information:

- Names of the source file dependencies (by using various SRC variables)
- Directories where source files are located (by using unique rules)
- Location of the header files (by using the INCLUDE variables)
- Precompiled library dependencies (by using the LIB variables)
- Libraries which need to be compiled and created (by using rules and the LIB variables)

A property of make utilities is that the specific location for a given source C or C++ file does not need to be specified. If there is a rule for that directory and the source filename is a prerequisite in the makefile, the make utility can find the source file and compile it. Similarly, the C or C++ compiler (preprocessor) does not require absolute paths to the headers. Given the name of header file by using an `#include` directive and an include path, it is able to find the header. The generated C or C++ source code depends on this standard compiler capability.

Also, libraries are typically created and linked against, but occlude the specific functions that are being used.

Although the build process is successful and can create a minimum-size executable, these properties can make it difficult to manually determine the minimum list of file dependencies along with their fully qualified paths. The makefile can be used as a starting point to determining the dependencies that the generated model code has.

An additional approach to determining the dependencies is by using linker information, such as a linker map file, to determine the symbol dependencies. The location of Real-Time Workshop and blockset source and header files is provided below to assist in locating the dependencies.

Real-Time Workshop Static File Dependencies. Several locations in the MATLAB directory tree contain static file dependencies specific to Real-Time Workshop:

- *matlabroot/rtw/c/libsrc/*

This directory contains many functions on which the generated code can be dependent. The directory contains a *rtwmakecfg.m* file which is used to create the appropriate rules and variables in the generated makefile. The files in this directory are compiled into a library. For host based targets, Real-Time Workshop provides a precompiled library for the functions in this directory. If the optimization options (OPT_OPTS) are changed for a Real-Time Workshop build, the makefile recompiles the library; otherwise the precompiled library is used.

- *matlabroot/rtw/c/src/*

This directory has subdirectories and contains additional files that may need to be compiled. Examples include solver functions (for continuous time support), external mode support files, C-API support files, and S-function support files. Source files in this directory are included into the build process using in the SRC variables of the makefile.

- *matlabroot/rtw/extern/include/*.h*
- *matlabroot/simulink/include/*.h*

These directories contain additional header file dependencies such as *tmwtypes.h*, *simstruc_types.h*, and *simstruc.h*.

Note For ERT-based targets, several header dependencies from the above locations can be avoided. ERT-based targets generate the minimum necessary set of type definitions, macros, and so on, in the file *rtwtypes.h*.

Blockset Static File Dependencies. Blockset products leverage the `rtwmakecfg.m` mechanism to provide Real-Time Workshop with dependency information. As such, the `rtwmakecfg.m` file provided by the blockset contains the listing of include path and source path dependencies for the blockset. Typically, blocksets create a library from the source files which the generated model code can then link against. The libraries are created and identified using the `rtwmakecfg.m` mechanism, similar to the Real-Time Workshop `libsrc` directory. The locations of the `rtwmakecfg.m` files for the blocksets are

- `matlabroot/commblocks/commblocksdemos/rtwmakecfg.m`
- `matlabroot/commblocks/commex/rtwmakecfg.m`
- `matlabroot/dspblocks/dspex/rtwmakecfg.m`
- `matlabroot/fuzzy/fuzzy/rtwmakecfg.m`
- `matlabroot/physmod/drive/drive/rtwmakecfg.m`
- `matlabroot/physmod/mech/mech/rtwmakecfg.m`
- `matlabroot/physmod/powersys/powersys/rtwmakecfg.m`

If the model being compiled uses one or more of these blocksets, you can determine directory and file dependency information from the respective `rtwmakecfg.m` file.

Specifying Include Paths in Real-Time Workshop Generated Source Files

You can add `#include` statements to generated code. Such references can come from several sources, including TLC scripts for inlining S-functions, custom storage classes, bus objects, and data type objects. The included files typically consist of header files for legacy code or other customizations. Additionally, you can specify compiler include paths with the `-I` compiler option. Real-Time Workshop uses the specified paths to search for included header files.

Usage scenarios for the generated code include, but are not limited to, the following:

- Real-Time Workshop generated code is compiled with a custom build process that requires an environment-specific set of `#include` statements.

In this scenario, Real-Time Workshop would likely be invoked with the **Generate code only** check box selected. It may be appropriate to use fully qualified paths, relative paths, or just the header filenames in the `#include` statements, and additionally leverage include paths.

- The generated code is compiled using the Real-Time Workshop build process.

In this case, compiler include paths (`-I`) can be provided to the Real-Time Workshop build process in several ways:

- The **Real-Time Workshop > Custom Code** pane of the Configuration Parameters dialog box allows you to specify additional include paths. The include paths are propagated into the generated makefile when the template makefile (TMF) is converted to the actual makefile.
- The `rtwmakecfg.m` mechanism allows S-functions to introduce additional include paths into the Real-Time Workshop build process. The include paths are propagated when the template makefile (TMF) is converted to the actual makefile.
- When building a custom Real-Time Workshop target that is makefile-based, the desired include paths can be directly added into the targets template makefile.
- A `USER_INCLUDES` make variable that specifies a directory in which Real-Time Workshop should search for included files can be specified on the Real-Time Workshop `make` command. For example,

```
make_rtw USER_INCLUDES=-Id:\work\feature1
```

The user includes are passed to the command-line invocation of the `make` utility, which will add them to the overall flags passed to the compiler.

Recommended Approaches. The following are recommended approaches for using `#include` statements and include paths in conjunction with the Real-Time Workshop build process to help ensure that the generated code remains portable and that compatibility problems with future versions of Real-Time Workshop are minimized.

Assume that additional header files are located at

```
c:\work\feature1\foo.h  
c:\work\feature2\bar.h
```

- A simple approach is to ensure all `#include` statements contain only the filename such as

```
#include "foo.h"
#include "bar.h"
```

Then, the include path passed to the compiler should contain all directories where the headers files exist:

```
cc -Ic:\work\feature1 -Ic:\work\feature2    ...
```

- A second recommended approach is to use relative paths in `#include` statements and provide an anchor directory for these relative paths using an include path, for example,

```
#include "feature1\foo.h"
#include "feature2\bar.h"
```

Then specify the anchor directory (for example `\work`) to the compiler:

```
cc -Ic:\work    ...
```

Directory Dependencies to Avoid. When using the Real-Time Workshop build process, avoid dependencies on its build and project directory structure, such as the `model_ert_rtw` build directory or the `slprj` project directory. Thus, the `#include` statements should not just be relative to where the generated source file exists. For example, if your MATLAB current working directory is `c:\work`, a generated `model.c` source file would be generated into a subdirectory such as

```
c:\work\model_ert_rtw\model.c
```

The `model.c` file would have `#include` statements of the form

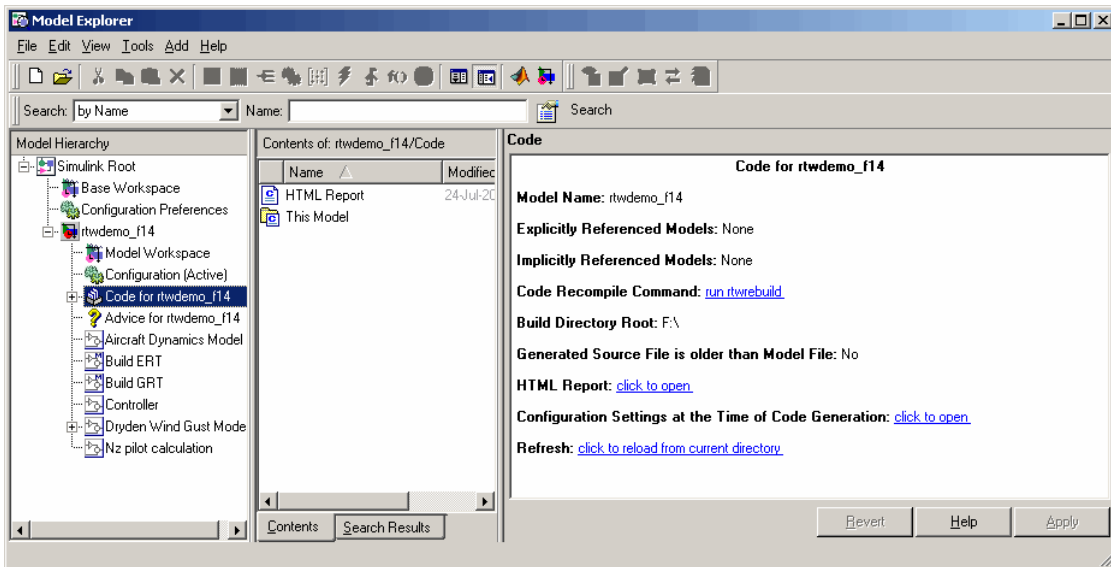
```
#include "..\feature1\foo.h"
#include "..\feature2\bar.h"
```

However, as this creates a dependency on the Real-Time Workshop directory structure, you should instead use one of the approaches described above.

Reloading Code from the Model Explorer

You can reload the code generated for a model from the Model Explorer.

- 1 Click the **Code for *model*** node in the **Model Hierarchy** pane.
- 2 In the **Code** pane, click the **Refresh** link.



Real-Time Workshop reloads the code for the model from the build directory.

Rebuilding Generated Code

If you update generated source code or makefiles manually to add customizations, you can rebuild the files with the `rtwrebuild` command. This command recompiles the modified files by invoking the generated makefile. To use this command from the Model Explorer,

- 1 In the **Model Hierarchy** pane, expand the node for the model of interest.
- 2 Click the **Code for *model*** node.
- 3 In the **Code** pane, click `run rtwrebuild`, listed to the right of the label **Code Recompile Command**.

Alternatively, you can use the command as follows:

If...	Issue the Command...
Your current working directory is the model's build directory	<code>rtwrebuild()</code>
Your current working directory is one level above the model's build directory (pwd when the Real-Time Workshop build was initiated)	<code>rtwrebuild(model)</code>
You want to specify the path to the model's build directory	<code>rtwrebuild(path)</code>

If your model includes submodels, Real-Time Workshop builds the submodels recursively before rebuilding the top model.

Profiling Generated Code

If you have a need to profile the code Real-Time Workshop generates for a model, you can do so with the TLC hook function interface demonstrated in `rtwdemo_profile`. To use the profile hook interface, you

- 1 Set up a TLC file that defines the following TLC hook functions:

Function	Input Arguments	Description
<code>ProfilerHeaders</code>	<code>void</code>	Return an array of the header filenames to be included in the generated code.
<code>ProfilerTypedefs</code>	<code>void</code>	Generate code statements for profiler type definitions.
<code>ProfilerGlobalData</code>	<code>system</code>	Generate code statements that declare global data.
<code>ProfilerExternDataDecls</code>	<code>system</code>	Generate code statements that create global extern declarations.

Function	Input Arguments	Description
ProfilerSysDecl	system, functionType	Generate code for variable declarations that needed within the scope of an atomic subsystem's Output, Update, OutputUpdate, or Derivatives function.
ProfilerSysStart	system, functionType	Generate code that starts the profiler within the scope of an atomic subsystem's Output, Update, OutputUpdate, or Derivatives function.
ProfilerSysEnd	system, functionType	Generate code that stops the profiler within the scope of an atomic subsystem's Output, Update, OutputUpdate, or Derivatives function.
ProfilerSysTerminate	system	Generate code that terminates profiling (and possibly reports results) for an atomic subsystem.

For an example of a .tlc file that applies these functions, see *matlabroot/toolbox/rtw/rtwdemos/rtwdemo_profile_hook.tlc*.

- 2** In your *target.tlc* file, define the following global variables:

Define...	To Be...
ProfilerTLC	The name of the TLC file you created in step 1
ProfileGenCode	TLC_TRUE

- 3** Build the model. Real-Time Workshop embeds the profiling code in appropriate locations in the generated code for your model.

For details on the hook function interface, see the instructions and sample .tlc file provided with *rtwdemo_profile*. For details on programming a

.t1c file and defining TLC configuration variables, see the Target Language Compiler documentation.

Customizing the Build Process

In this section...

“Controlling the Compiling and Linking Phases of the Build Process” on page 2-108

“Cross-Compiling Code Generated on Windows” on page 2-109

“Controlling the Location and Naming of Libraries During the Build Process” on page 2-112

“Recompiling Precompiled Libraries” on page 2-117

“Customizing Post Code Generation Build Processing” on page 2-117

Controlling the Compiling and Linking Phases of the Build Process

After generating code for a model, Real-Time Workshop determines whether or not to compile and link an executable program. This decision is governed by the following:

- **Generate code only** option

When you select this option, Real-Time Workshop generates code for the model, including a makefile.

- **Generate makefile** option

When you clear this option, Real-Time Workshop does not generate a makefile for the model. You must specify any post code generation processing, including compilation and linking, as a user-defined command, as explained in “Customizing Post Code Generation Build Processing” on page 2-117.

- **Makefile-only target**

The Visual C/C++ Project Makefile versions of the `grt`, `grt_malloc`, and Real-Time Workshop Embedded Coder target configurations generate a Visual C/C++ project makefile (*model.mak*). To build an executable, you must open *model.mak* in the Visual C/C++ IDE and compile and link the model code.

- **HOST template makefile variable**

The template makefile variable `HOST` identifies the type of system upon which your executable is intended to run. The variable can be set to one of three possible values: `PC`, `UNIX`, or `ANY`.

By default, `HOST` is set to `UNIX` in template makefiles designed for use with UNIX (such as `grt_unix.tmf`), and to `PC` in the template makefiles designed for use with development systems for the PC (such as `grt_vc.tmf`).

If Simulink is running on the same type of system as that specified by the `HOST` variable, then the executable is built. Otherwise,

- If `HOST = ANY`, an executable is still built. This option is useful when you want to cross-compile a program for a system other than the one Simulink is running on.
- Otherwise, processing stops after generating the model code and the makefile; the following message is displayed on the MATLAB command line.

```
### Make will not be invoked - template makefile is for a different host
```

- **TGT_FCN_LIB** template makefile variable

The template makefile variable `TGT_FCN_LIB` specifies compiler command line options. The line in the makefile is `TGT_FCN_LIB = |>TGT_FCN_LIB<|`. By default, Real-Time Workshop expands the `|>TGT_FCN_LIB<|` token to match the setting of the **Target function library** option on the **Real-Time Workshop/Interface** pane of the Configuration Parameters dialog box. Possible values for this option include `ANSI_C`, `C99 (ISO)`, and `GNU99 (GNU)`. You can use this token in a makefile conditional statement to specify compiler options to be used. For example, if you set the token to `C99 (ISO)`, the compiler might need an additional option set to support C99 library functions.

Cross-Compiling Code Generated on Windows

If you need to generate code with Real-Time Workshop on a Windows system but compile the generated code on a supported platform other than Windows, you can do so by modifying your TMF and model configuration parameters. For example, you would need to do this if you develop applications with MATLAB and Simulink on Windows, but you run your generated code on a Linux system.

To set up a cross-compilation development environment, do the following (here Linux is the destination platform):

1 On your Windows system, copy the UNIX TMF for your target to a local directory. This will be your working directory for initiating code generation. For example, you might copy *matlabroot/rtw/c/grt/grt_unix.tmf* to *D:/work/my_grt_unix.tmf*.

2 Make the following changes to your copy of the TMF:

- Add the following line near the `SYS_TARGET_FILE =` line:

```
MAKEFILE_FILESEP = /
```

- Search for the line `'ifeq ($(OPT_OPTS),$(DEFAULT_OPT_OPTS))'` and, for each occurrence, remove the conditional logic and retain only the `'else'` code. That is, remove everything from the `'if'` to the `'else'`, inclusive, as well as the closing `'endif'`. Only the lines from the `'else'` portion should remain. This forces the run-time libraries to build for Linux.

3 Open your model and make the following changes in the **Real-Time Workshop** pane of the Configuration Parameters dialog:

- Specify the name of your new TMF in the **Template makefile** text box (for example, *my_grt_unix.tmf*).
- Select **Generate code only** and click **Apply**.

4 Generate the code.

5 If the build directory (directory from which the model was built) is not already Linux accessible, copy it to a Linux accessible path. For example, if your build directory for the generated code was *D:\work\mymodel_grt_rtw*, copy that entire directory tree to a path such as */home/user/mymodel_grt_rtw*.

6 If the Windows MATLAB directory tree is Linux accessible, skip this step. Otherwise, you must copy all the include and source directories to a Linux accessible drive partition, for example, */home/user/myinstall*. These directories appear in the makefile after `MATLAB_INCLUDES =` and `ADD_INCLUDES =` and can be found by searching for `$(MATLAB_ROOT)`. Any

path that contains `$(MATLAB_ROOT)` must be copied. Here is an example list (your list will vary depending on your model):

```
$(MATLAB_ROOT)/rtw/c/grt
$(MATLAB_ROOT)/extern/include
$(MATLAB_ROOT)/simulink/include
$(MATLAB_ROOT)/rtw/c/src
$(MATLAB_ROOT)/rtw/c/libsrc
$(MATLAB_ROOT)/rtw/c/tools
```

Additionally, paths containing `$(MATLAB_ROOT)` in the build rules (lines with `%.o :`) must be copied. For example, based on the build rule

```
%.o : $(MATLAB_ROOT)/rtw/c/src/ext_mode/tcpip/%.c
```

the following directory should be copied:

```
$(MATLAB_ROOT)/rtw/c/src/ext_mode/tcpip
```

Note The path hierarchy relative to the MATLAB root must be maintained. For example, `c:\MATLAB\rtw\c\tools*` would be copied to `/home/user/mlroot/rtw/c/tools/*`.

For some blocksets, it is easiest to copy a higher-level directory that includes the subdirectories listed in the makefile. For example, the Signal Processing Blockset requires the following directories to be copied:

```
$(MATLAB_ROOT)/toolbox/dspblks
$(MATLAB_ROOT)/toolbox/rtw/dspblks
```

7 Make the following changes to the generated makefile:

- Set both `MATLAB_ROOT` and `ALT_MATLAB_ROOT` equal to the Linux accessible path to *matlabroot* (for example, `home/user/myinstall`).
- Set `COMPUTER` to the appropriate computer value, such as `GLNX86`. Enter `help computer` in the MATLAB Command Window for a list of computer values.

- In the `ADD_INCLUDES` list, change the build directory (designating the location of the generated code on the Windows system) and parent directories to Linux accessible include directories. For example, change `D:\work\mymodel_grt_rtw\` to `/home/user/mymodel_grt_rtw`.

Additionally, if `matlabroot` is a UNC path, such as `\\my-server\myapps\matlab`, replace the hard-coded MATLAB root with `$(MATLAB_ROOT)`.

- 8 From a Linux shell, compile the code you generated on Windows. You can do this by running the generated `model.bat` file or by typing the make command line as it appears in the `.bat` file.

Note If errors occur during makefile execution, you may need to run the `dos2unix` utility on the makefile (for example, `dos2unix mymodel.mk`).

Controlling the Location and Naming of Libraries During the Build Process

Two configuration parameters, `TargetPreCompLibLocation` and `TargetLibSuffix`, are available for you to use to control values placed in Real-Time Workshop generated makefiles during the token expansion from template makefiles (TMFs). You can use these parameters to

- Specify the location of precompiled libraries, such as blockset libraries or the Real-Time Workshop library. Typically, a target has cross-compiled versions of these libraries and places them in a target-specific directory.
- Control the suffix applied to library file names (for example, `_target.a` or `_target.lib`).

Targets can set the parameters inside the system target file (STF) select callback. For example:

```
function mytarget_select_callback_handler(varargin)
    hDig=varargin{1};
    hSrc=varargin{2};
    slConfigUISetVal(hDig, hSrc,...
        'TargetPreCompLibLocation', 'c:\mytarget\precomplib');
    slConfigUISetVal(hDig, hSrc, 'TargetLibSuffix',...
```

```
'_diab.library');
```

The TMF has corresponding expansion tokens:

```
>EXPAND_LIBRARY_LOCATION<  
>EXPAND_LIBRARY_SUFFIX<
```

Alternatively, you can use a call to the `set_param` function. For example:

```
set_param(model, 'TargetPreCompLibLocation', ...  
'c:\mytarget\precomplib');
```

Note If your model contains referenced models, you can use the make option `USE_MDLREF_LIBPATHS` to control whether libraries used by the referenced models are copied to the parent model's build directory. For more information, see “Controlling the Location of Model Reference Libraries” on page 2-114.

Specifying the Location of Precompiled Libraries

Use the `TargetPreCompLibLocation` configuration parameter to:

- Override the precompiled library location specified in the `rtwmakecfg.m` file (see “Using the `rtwmakecfg.m` API” on page 10-84 for details)
- Precompile and distribute target-specific versions of product libraries (for example, Signal Processing Blockset, `rtlibsrc`, and so on)

For a precompiled library, such as a blockset library or the Real-Time Workshop library, the location specified in `rtwmakecfg.m` is typically a location specific to the blockset or to Real-Time Workshop. It is expected that the library will exist in this location and it is linked against during Real-Time Workshop builds.

However, for some applications, such as custom targets, it is preferable to locate the precompiled libraries in a target-specific or other alternate location rather than in the location specified in `rtwmakecfg.m`. For a custom target, the library is expected to be created using the target-specific cross-compiler and placed in the target-specific location for use during the Real-Time Workshop build process. All libraries intended to be supported by the target should be compiled and placed in the target-specific location.

You can set up the `TargetPreCompLibLocation` parameter in its select callback. The path that you specify for the parameter must be a fully qualified absolute path to the library location. Relative paths are not supported. For example:

```
slConfigUISetVal(hDlg, hSrc, 'TargetPreCompLibLocation', ...  
  'c:\mytarget\precomplibs');
```

Alternatively, you set the parameter with a call to the `set_param` function. For example:

```
set_param(model, 'TargetPreCompLibLocation', ...  
  'c:\mytarget\precomplibs');
```

During the TMF-to-makefile conversion, Real-Time Workshop replaces the token `|>EXPAND_LIBRARY_LOCATION<|` with the specified location in the `rtwmakecfg.m` file. For example, if the library name specified in the `rtwmakecfg.m` file is `'rtwlib'`, the TMF expands from:

```
LIBS += |>EXPAND_LIBRARY_LOCATION<| |>EXPAND_LIBRARY_NAME<| \  
|>EXPAND_LIBRARY_SUFFIX<|
```

to:

```
LIBS += c:\mytarget\precomplibs\rtwlib_diab.library
```

By default, `TargetPreCompLibLocation` is an empty string and Real-Time Workshop uses the location specified in `rtwmakecfg.m` for the token replacement.

Controlling the Location of Model Reference Libraries

On platforms other than the Macintosh, when building a model that uses referenced models, Real-Time Workshop by default:

- Copies libraries used by the referenced models to the parent model's build directory
- Assigns the filenames of the libraries to `MODELREF_LINK_LIBS` in the generated makefile

For example, if a model includes a referenced model sub, Real-Time Workshop assigns the library name `sub_rtwlib.lib` to `MODELREF_LINK_LIBS` and copies the library file to the parent model's build directory. This definition is then used in the final link line, which links the library into the final product (usually an executable). This technique minimizes the length of the link line.

On the Macintosh platform, and optionally on other platforms, Real-Time Workshop:

- Does not copy libraries used by the referenced models to the parent model's build directory
- Assigns the relative paths and filenames of the libraries to `MODELREF_LINK_LIBS` in the generated makefile

When using this technique, Real-Time Workshop assigns a relative path such as `../slprj/grt/sub/sub_rtwlib.lib` to `MODELREF_LINK_LIBS` and uses the path to gain access to the library file at link time.

To change to the non-default behavior on platforms other than the Macintosh, enter the following command in the **Make command** field of the Real-Time Workshop pane of the Configuration Parameters dialog box:

```
make_rtw USE_MDLREF_LIBPATHS=1
```

If you specify other Make command arguments, such as `OPTS="-g"`, you can specify the multiple arguments in any order.

To return to the default behavior, set `USE_MDLREF_LIBPATHS` to 0, or remove it.

Controlling the Suffix Applied to Library File Names

Use the `TargetLibSuffix` configuration parameter to control the suffix applied to library names (for example, `_target.lib` or `_target.a`). The specified suffix string must include a period (.). You can apply `TargetLibSuffix` to the following libraries:

- Libraries on which a target depends, as specified in the `rtwmakecfg.m` API. You can use `TargetLibSuffix` to affect the suffix of both precompiled and non-precompiled libraries configured from the `rtwmakecfg` API. For details, see "Using the `rtwmakecfg.m` API" on page 10-84.

In this case, a target can set the parameter in its select callback. For example:

```
slConfigUISetVal(hDlg, hSrc, 'TargetLibSuffix',...  
'_diab.library');
```

Alternatively, you can use a call to the `set_param` function. For example:

```
set_param(model, 'TargetLibSuffix', '_diab.library');
```

During the TMF-to-makefile conversion, Real-Time Workshop replaces the token `|>EXPAND_LIBRARY_SUFFIX<|` with the specified suffix. For example, if the library name specified in the `rtwmakecfg.m` file is `'rtwlib'`, the TMF expands from:

```
LIBS += |>EXPAND_LIBRARY_LOCATION<|\ |>EXPAND_LIBRARY_NAME<|\  
|>EXPAND_LIBRARY_SUFFIX<|
```

to:

```
LIBS += c:\mytarget\precomplibs\rtwlib_diab.library
```

By default, `TargetLibSuffix` is set to an empty string. In this case, Real-Time Workshop replaces the token `|>EXPAND_LIBRARY_SUFFIX<|` with an empty string.

- Shared utility library and the model libraries created with model reference. For these cases, associated makefile variables do not require the `|>EXPAND_LIBRARY_SUFFIX<|` token. Instead, Real-Time Workshop includes `TargetLibSuffix` implicitly. For example, for a top model named `topmodel` with submodels named `submodel1` and `submodel2`, the top model's TMF is expanded from:

```
SHARED_LIB          = |>SHARED_LIB<|  
MODELLIB           = |>MODELLIB<|  
MODELREF_LINK_LIBS = |>MODELREF_LINK_LIBS<|
```

to:

```
SHARED_LIB          = \  
..\slprj\ert\_sharedutils\rtwshared_diab.library  
MODELLIB           = topmodellib_diab.library  
MODELREF_LINK_LIBS = \  

```

```
submodel1_rtwlib_diab.library submodel2_rtwlib_diab.library
```

By default, the `TargetLibSuffix` parameter is an empty string. In this case, Real-Time Workshop chooses a default suffix for these three tokens using a file extension of `.lib` on Windows hosts and `.a` on UNIX hosts. (For model reference libraries, the default suffix additionally includes `_rtwlib`.) For example, on a Windows host, the expanded makefile values would be:

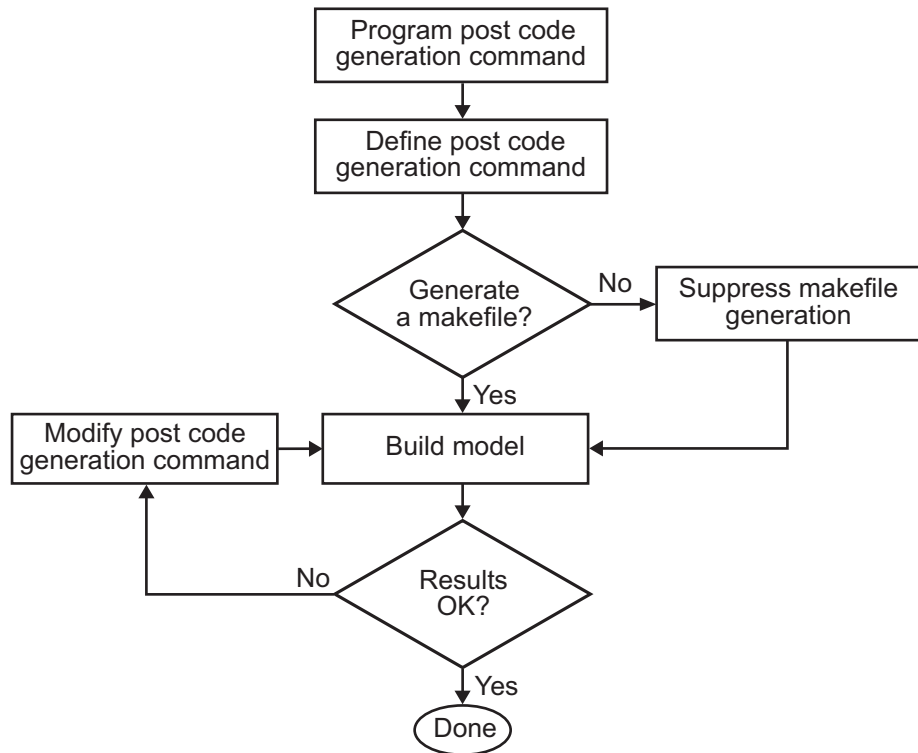
```
SHARED_LIB          = ..\slprj\ert\_sharedutils\rtwshared.lib
MODELLIB            = topmodellib.lib
MODELREF_LINK_LIBS = submodel1_rtwlib.lib submodel2_rtwlib.lib
```

Recompiling Precompiled Libraries

You can recompile precompiled libraries included as part of Real-Time Workshop, such as `rtwlib` or `dsplib`, by using a supplied M-file function, `rtw_precompile_libs`. You might consider doing this if you need to customize compiler settings for various platforms or environments. For details on using `rtw_precompile_libs`, see “Precompiling S-Function Libraries” on page 10-90.

Customizing Post Code Generation Build Processing

Real-Time Workshop provides a set of tools, including a build information object, you can use to customize build processing that occurs after code generation. You might use such customizations for target development or the integration of third-party tools into your application development environment. The next figure and the steps that follow show the general workflow for setting up such customizations.



- 1 Program the post code generation command.
- 2 Define the post code generation command.
- 3 Suppress makefile generation, if appropriate for your application.
- 4 Build the model.
- 5 Modify the command, if necessary, and rebuild the model. Repeat this step until the build results are acceptable.

Build Information Object

At the start of a model build, Real-Time workshop logs the following build option and dependency information to a temporary build information object:

- Compiler options
- Preprocessor identifier definitions
- Linker options
- Source files and paths
- Include files and paths
- Precompiled external libraries

You can retrieve information from and add information to this object by using an extensive set of functions. For a list of available functions and detailed function descriptions, see “Functions — Alphabetical List” in the Real-Time Workshop documentation. “Programming a Post Code Generation Command” on page 2-119 explains how to use the functions to control post code generation build processing.

Programming a Post Code Generation Command

For certain applications, it might be necessary to control aspects of the build process after Real-Time Workshop generates code. For example, this is necessary when you develop your own target, or you want to apply an analysis tool to the generated code before continuing with the build process. You can apply this level of control to the build process by programming and then defining a post code generation command.

A post code generation command is an M-file that typically calls functions that get data from or add data to the model’s build information object. You can program the command as a script or function.

If You Program the Command as a...	Then the...
Script	Script can gain access to the model name and the build information directly
Function	Function can pass the model name and the build information as arguments

If your post code generation command calls user-defined functions, make sure the functions are on the MATLAB path. If Real-Time Workshop cannot find a function you use in your command, the build process errors out.

You can then call any combination of build information functions to customize the model's post code generation build processing.

The following example shows a fragment of a post code generation command that gets the filenames and paths of the source and include files generated for a model for analysis.

```
function analyzegenerate(buildInfo)
% Get the names and paths of all source and include files
% generated for the model and then analyze them.

% buildInfo - build information for my model.

% Define cell array to hold data.
MyBuildInfo={};

% Get source file information.
MyBuildInfo.srcfiles=getSourceFiles(buildInfo, true, true);
MyBuildInfo.srcpaths=getSourcePaths(buildInfo, true);

% Get include (header) file information.
MyBuildInfo.incfiles=getIncludeFiles(buildInfo, true, true);
MyBuildInfo.incpaths=getIncludePaths(buildInfo, true);

% Analyze generated code.
.
.
.
```

For a list of available functions and detailed function descriptions, see “Functions — Alphabetical List” in the Real-Time Workshop documentation.

Defining a Post Code Generation Command

After you program a post code generation command, you need to inform Real-Time Workshop that the command exists and to add it to the model's build processing. You do this by defining the command with the

PostCodeGenCommand model configuration parameter. When you define a post code generation command, Real-Time Workshop evaluates the command after generating and writing the model's code to disk and before generating a makefile.

As the following syntax lines show, the arguments that you specify when setting the configuration parameter varies depending on whether you program the command as a script, function, or set of functions.

Note When defining the command as a function, you can specify an arbitrary number of input arguments. To pass the model's name and build information to the function, specify identifiers `modelName` and `buildInfo` as arguments.

Script

```
set_param(model, 'PostCodeGenCommand', ...
    'pcgScriptName');
```

Function

```
set_param(model, 'PostCodeGenCommand', ...
    'pcgFunctionName(modelName)');
```

Multiple Functions

```
pcgFunctions=...
    'pcgFunction1Name(modelName);...
    'pcgFunction2Name(buildInfo)';
set_param(model, 'PostCodeGenCommand', ...
    'pcgFunctions');
```

The following call to `set_param` defines `PostCodGenCommand` to evaluate the function `analyzeencode`.

```
set_param(model, 'PostCodeGenCommand', ...
    'analyzeencode(buildInfo)');
```

Suppressing Makefile Generation

Real-Time Workshop provides the ability to suppress makefile generation during the build process. For example, you might do this to integrate tools into the build process that are not driven by makefiles.

To instruct Real-Time Workshop to not generate a makefile during a model's build processing, do one of the following:

- Clear the **Generate makefile** option on the Real-Time Workshop pane of the Configuration Parameters dialog box.
- Set the value of the configuration parameter `GenerateMakefile` to `off`.

When you suppress makefile generation,

- You no longer can explicitly specify a make command or template makefile.
- You must specify your own instructions for any post code generation processing, including compilation and linking, in a post code generation command as explained in “Programming a Post Code Generation Command” on page 2-119 and “Defining a Post Code Generation Command” on page 2-120.

Validating Generated Code

In this section...
“Viewing Generated Code” on page 2-123
“Tracing Generated Code Back to Your Simulink Model” on page 2-125
“Getting Model Optimization Advice” on page 2-127

Viewing Generated Code

You can view generated code in HTML reports or in the Model Explorer.

Viewing Generated Code in Generated HTML Reports

One way to view the code that Real-Time Workshop generates is to set the **Generate HTML report** option on the **Real-Time Workshop** pane of the Configuration Parameters dialog box. When set, this option generates a report that contains the following code generation details:

- A Summary section that lists version and date information, and a link to open configuration settings used for generating the code, including TLC options and Simulink model settings.
- A Generated Source Files section that contains a table of source code files generated from your model. You can view the source code in the MATLAB Help browser. When Real-Time Workshop Embedded Coder is installed, hyperlinks are placed within the source code that let you trace lines of code back to the blocks or subsystems from which the code was generated. Click the hyperlinks to highlight the relevant blocks or subsystems in a Simulink model window.

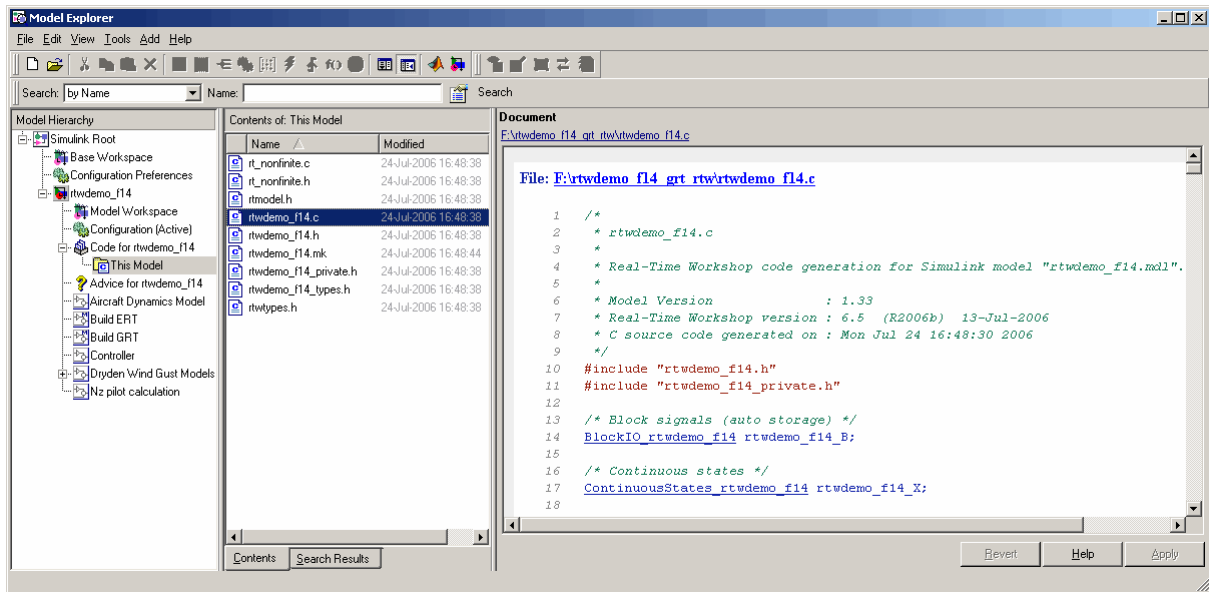
Note The report generated for various targets may vary slightly.

Viewing Generated Code in Model Explorer

Another way to view the HTML source code report is to use the Code Viewer that is built into Model Explorer. You can browse files generated by Real-Time

Workshop, Real-Time Workshop Embedded Coder, and other products directly in the Model Explorer.

When you generate code, or open a model that has generated code for its current target configuration in your working directory, the **Hierarchy** (left) pane of Model Explorer contains a node named **Code for model**. Under that node are other nodes, typically called This Model and Shared Code. Clicking This Model displays in the **Contents** (middle) pane a list of source code files in the build directory of each model that is currently open. The next figure shows code for the vdp model.



In this example, the file `D:/work/test/vdp_grt_rtw/vdp.c` is being viewed. To view any file in the **Contents** pane, click it once.

The views in the **Document** (right) pane are read only. The code listings there contain hyperlinks to functions and macros for the generated code. A hyperlink for the source file (not the HTML version you are looking at) being viewed sits above it. Clicking it opens that file in a text editing window where you can modify its contents. This is not something you typically do with generated source code, but in the event you have placed custom code files in

the build directory, you can edit them as well in this fashion. You can also take advantage of your editor's features such as multipane display or custom syntax coloring.

If an open model contains Model blocks, and if generated code for any of these models exists in the current `slprj` directory, nodes for the referenced models appear in the **Hierarchy** pane one level below the node for the top model. Such referenced models do not need to be open for you to browse and read their generated source files.

If Real-Time Workshop generates shared utility code for a model, a node named `Shared Code` appears directly under the **This Model** node. It collects any source files that exist in the appropriate `./slprj/target/_sharedutils` subdirectory.

Note Currently, you cannot use the **Search** tool built into Model Explorer's toolbar to search generated code displayed in the Code Viewer. On PCs, typing **Ctrl+F** when focused on the **Document** pane opens a Find dialog box you can use to search for strings in the currently displayed file. You can also search for text in the HTML report window, and can open any of the files in the editor.

Tracing Generated Code Back to Your Simulink Model

Real-Time Workshop writes system/block identification tags in the generated code. The tags are designed to help you identify the block in your source model that generated a given line of code. Tags are located in comment lines above each line of generated code, and are provided with hyperlinks in HTML code generation reports that you can optionally generate.

The tag format is `<system>/block_name`, where

- `system` is either
 - The string `'root'`, or
 - A unique system number assigned by Simulink
- `block_name` is the name of the block.

The following code shows a tag comment adjacent to a line of code generated by a Gain block at the root level of the source model:

```
/* Gain: '<Root>/UnDeadGain1' */
rtb_UnDeadGain1_h = dead_gain_U.In1 *
    dead_gain_P.UnDeadGain1_Gain;
```

The following code shows a tag comment adjacent to a line of code generated by a Gain block within a subsystem one level below the root level of the source model:

```
/* Gain Block: <S1>/Gain */
dead_gain_B.temp0 *= (dead_gain_P.s1_Gain_Gain);
```

In addition to the tags, Real-Time Workshop documents the tags for each model in comments in the generated header file *model.h*. The following code illustrates such a comment, generated from a source model, *foo*, that has a subsystem *Outer* with a nested subsystem *Inner*:

```
/* Here is the system hierarchy for this model.
 *
 * <Root> : foo
 * <S1>   : foo/Outer
 * <S2>   : foo/Outer/Inner
 */
```

There are two ways to trace code back to subsystems, blocks, and parameters in your model:

- Through HTML code generation reports by using the Help browser
- By typing the appropriate `hilite_system` commands to MATLAB

When you are licensed for Real-Time Workshop Embedded Coder, the HTML report for your *model.c* or *model.cpp* file displays hyperlinks in “Regarding,” “Outport,” and other comment lines. Clicking such links in comments causes the associated block or subsystem to be highlighted in the model. For more information, see “HTML Code Generation Reports” in Getting Started.

Using HTML reports is generally the fastest way to trace code back to the model, but when you know what you are looking for you might achieve

the same result at the command line. To manually trace a tag back to the generating block using the `hilite_system` command,

- 1 Open the source model.
- 2 Close any other model windows that are open.
- 3 Use the MATLAB `hilite_system` command to view the desired system and block.

As an example, consider the model `foo` mentioned above. If `foo` is open,

```
hilite_system('<S1>')
```

opens the subsystem `Outer` and

```
hilite_system('<S2>/Gain1')
```

opens the subsystem `Outer` and selects and highlights the Gain block `Gain1` within that subsystem.

Getting Model Optimization Advice

The Model Advisor is a tool that helps you configure any model to optimally achieve your code generation objectives. Clicking **Advice** for `model` in the **Model Hierarchy** pane launches the Model Advisor from Model Explorer. This node is directly below the **Code for model** node, as the previous figure shows. Clicking the **Advice for** node causes the **Dialog** pane to be labeled Model Advisor, and to contain a link, **Start model advisor**. When you click that link, Model Advisor opens a separate HTML window with a set of button and check box controls.

Another way to invoke Model Advisor is to type

```
ModelAdvisor('model')
```

specifying the name of an open model, at the MATLAB prompt.

You can also select **Model Advisor** from the **Tools** menu.

See “Using the Model Advisor” on page 9-5 for more information on Model Advisor.

Integrating Legacy and Custom Code

In this section...
“Introduction” on page 2-129
“Block-Based Integration” on page 2-129
“Model or Target-Based Integration” on page 2-131

Introduction

Real-Time Workshop includes mechanisms for integrating generated code with legacy or custom code. *Legacy code* is existing C or C++ hand code or code for environments that needs to be integrated with code generated by Real-Time Workshop. *Custom code* can be legacy code or any other user-specified lines of code that need to be included in the Real-Time Workshop build process.

You can achieve code integration from either of two contexts. You can integrate

- Code generated by Real-Time Workshop into an existing code base for a larger system. For example, you might want to use generated code as a plug-in function. For this type of integration, you should use Real-Time Workshop Embedded Coder. The Real-Time Workshop Embedded Coder documentation explains how to use entry points and header files to interface your existing code with generated code.
- Existing code into code generated by Real-Time Workshop. This type of integration can be either block based or model based. “Block-Based Integration” on page 2-129 and “Model or Target-Based Integration” on page 2-131 list available code integration mechanisms based on various application requirements.

Block-Based Integration

The following table lists available block-based integration mechanisms based on application requirements. The table also provides information on where to find details on how to apply each mechanism.

If You Need or Prefer to...	Consider Using...	For Details, See...
<ul style="list-style-type: none"> • Simulate and generate code such that block behavior is the same or unique for the two environments. • Develop a complete interface to all Simulink block functions, block memory, and block capabilities. • Use input and output ports for interaction between and placement with respect to other blocks. • Use Simulink parameters (for example, run-time parameters). • Apply code generation optimizations, such as expression folding and the use of local block output ports. • Add file and path information for existing code into the Real-Time Workshop build process. An extensive, block-based <code>rtwmakecfg</code> API is available. • Control the location of generated code through block placement. • Use TLC library functions for the block or overall model code. • Maximize ease-of-use for model designers. 	<p>User written S-Function blocks</p>	<ul style="list-style-type: none"> • Chapter 10, “Writing S-Functions for Real-Time Workshop Code Generation” • “Build Support for S-Functions” on page 10-81 — information on specifying additional dependencies for the Real-Time Workshop build process • Target Language Compiler documentation — information on inlining S-functions • Simulink Writing S-Functions documentation

If You Need or Prefer to...	Consider Using...	For Details, See...
<ul style="list-style-type: none"> • Use a graphical user interface to create S-Function blocks. • Specify build information through a graphical user interface. 	S-Function Builder block	Information on the S-Function Builder block in the Simulink documentation
<ul style="list-style-type: none"> • Not affect simulation or simulation-based targets, such as S-function targets, accelerated simulation targets, and model reference simulation targets. • Insert lines of code into functions at the atomic system or model level. • Minimize development effort by just typing in lines of custom code. 	Real-Time Workshop Custom Code blocks	Chapter 14, “Inserting Custom Code Into Generated Code”

S-Function blocks offer the most capable and flexible means of integrating code and specifying additional build information. Their use in a model carries the build information as well.

Model or Target-Based Integration

The following table lists available model or target-based integration mechanisms based on application requirements. The table also provides information on where to find details on how to apply each mechanism.

If You Need or Prefer to...	Consider Using...	For Details, See...
<ul style="list-style-type: none"> • Not affect simulation or simulation-based targets, such as S-function targets, accelerated simulation targets, and model reference simulation targets. • Add lines of custom code in the generated model header or source file. • Add lines of custom code to generated initialization and termination functions. • Specify the files and path to be used for the Real-Time Workshop build process. • Minimize development effort by just typing in lines of custom code, paths, or filenames. • Use a modeling approach; include model information as configuration parameters. 	<p>Real-Time Workshop/Custom Code pane of the Configuration Parameters dialog box</p>	<p>Chapter 2, “Code Generation and the Build Process”</p>
<ul style="list-style-type: none"> • Use a mechanism that affects all model builds for a given target — model and block independent. • Include paths, source file rules, and libraries in the makefile. • Control the build process by selecting a custom Real-Time Workshop system target file. 	<p>Custom target template makefile</p>	<p>Real-Time Workshop Embedded Coder documentation — details on makefiles</p>

Note It is also possible to affect the Real-Time Workshop build process by specifying libraries or sources in the **Make command** field on the **Real-Time Workshop** pane of the Configuration Parameters dialog box. This approach requires knowledge of the make variables used in a target template makefile and is not generally recommended.

Relocating Code to Another Development Environment

In this section...
“Introduction” on page 2-134
“Deciding on a Structure for the Zip File” on page 2-134
“Deciding on a Name for the Zip File” on page 2-135
“Packaging Model Code Files in a Zip File” on page 2-136
“Inspecting the Generated Zip File” on page 2-137
“Relocating and Unpacking the Zip File” on page 2-137
“Code Packaging Example” on page 2-137
“packNGo Function Limitations” on page 2-138

Introduction

If you need to relocate the static and generated code files for a model to another development environment, such as a secure system or an integrated development environment (IDE) that does not include MATLAB and Simulink, use the Real-Time Workshop pack-and-go utility. This utility uses the tools for customizing the build process after code generation and a packNGo function to find and package all files needed to build an executable image. The files are packaged in a compressed file that you can relocate and unpack using a standard zip utility.

To relocate a model’s code files,

- 1 Decide on a structure of the zip file.
- 2 Decide on a name for the zip file.
- 3 Package the model code files in the zip file.
- 4 Relocate and unpack the zip file.

Deciding on a Structure for the Zip File

Before you generate and package the files for a model build, decide whether you want the files to be packaged in a flat or hierarchical directory structure.

By default, the `packNGo` function packages all the necessary files in single, flat directory structure. This is the simplest approach and might be the optimal choice.

If...	Then Use a...
You are relocating files to an IDE that does not use the generated makefile or the code is not dependent on the relative location of required static files	Single, flat directory structure
The target development environment must maintain the directory structure of the source environment because it uses the generated makefile or the code is dependent on the relative location of files	Hierarchical structure

If you use a hierarchical structure, the `packNGo` function creates two levels of zip files, a primary zip file, which in turn contains the following secondary zip files:

- `m1rFiles.zip` — files in your *matlabroot* directory tree
- `sDirFiles.zip` — files in and under your build directory where you initiated the model's code generation
- `otherFiles.zip` — required files not in the *matlabroot* or start directory trees

Paths for the secondary zip files are relative to the root directory of the primary zip file, maintaining the source development directory structure.

Deciding on a Name for the Zip File

By default, the `packNGo` function names the primary zip file `model.zip`. You have the option of specifying a different name. If you specify a file name and omit the file type extension, the function appends `.zip` to the name you specify.

Packaging Model Code Files in a Zip File

You package model code files by using the `PostCodeGenCommand` configuration parameter, `packNGo` function, and the model's build information object. You can set up the packaging operation to use

- A system generated build information object.

In this case, use `set_param` to set the configuration parameter `PostCodeGenCommand` to an explicit call to the `packNGo` function before generating the model code. For example:

```
set_param(bdroot, 'PostCodeGenCommand', 'packNGo(buildInfo);');
```

This command instructs Real-Time Workshop to evaluate the call to `packNGo`, using the system generated build information object for the currently selected model, after generating and writing the model's code to disk and before generating a makefile.

- A build information object that you construct programmatically, as explained in “Customizing Post Code Generation Build Processing” on page 2-117.

In this case, you might use other build information functions to selectively include paths and files in the build information object that you then specify with the `packNGo` function. For example:

```
.  
. .  
. .  
myModelBuildInfo = RTW.BuildInfo;  
addSourceFiles(myModelBuildInfo, {'test1.c' 'test2.c' 'driver.c'});  
. .  
. .  
packNGo(myModelBuildInfo);
```

To change the default behavior of `packNGo`, see the following examples:

To...	Specify...
Change the structure of the file packaging to hierarchical	<code>packNGo(buildInfo, {'packType' 'hierarchical'});</code>
Rename the primary zip file	<code>packNGo(buildInfo, {'fileName' 'zippedsrcs'});</code>
Change the structure of the file packaging to hierarchical and rename the primary zip file	<code>packNGo(buildInfo, {'packType' 'hierarchical'... 'fileName' 'zippedsrcs'});</code>

Inspecting the Generated Zip File

Inspect the resulting zip file in your working directory on the source system to verify that it is ready for relocation to the destination system. Depending on the zip tool you use you might be able to open and inspect the file without unpacking it. If you need to unpack the file and you packaged the model code files as a hierarchical structure, you will need to unpack the primary and secondary zip files. When you unpack the secondary zip files, relative paths of all files are preserved.

Relocating and Unpacking the Zip File

Relocate the resulting zip file to the destination development environment and unpack the file.

Code Packaging Example

The following example guides you through the steps for packaging code files generated for the demo model `rtwdemo_f14`.

- 1 Set your working directory to a writable directory.
- 2 Open the model `rtwdemo_f14` and save a copy to your working directory.
- 3 Enter the following command in the MATLAB Command Window:

```
set_param('rtwdemo_f14', 'PostCodeGenCommand',...
'packNGo(buildInfo, {'packType' 'hierarchical'}));
```

Note that it is necessary to double the single-quotes due to the nesting of character arrays 'packType' and 'hierarchical' within the character array that specifies the call to packNGo.

- 4 Generate code for the model.
- 5 Inspect the generated zip file, `rtwdemo_f14.zip`. The zip file contains the two secondary zip files, `m1rFiles.zip` and `sDirFiles.zip`.
- 6 Inspect the zip files `m1rFiles.zip` and `sDirFiles.zip`.
- 7 Relocate the zip file to a destination environment and unpack it.

packNGo Function Limitations

The following limitations apply to use of the packNGo function:

- The function operates on source files, such as `*.c`, `*.cpp`, `*.h` files, only. The function does not support compile flags, defines, or makefiles.
- Unnecessary files may be included. For example, the function includes all S-function libraries in an all-or-nothing manner and all header files from every include directory, even if they are not used.

Generated Code Formats

Introduction (p. 3-2)	Introduces the concept of code formats
Targets and Code Formats (p. 3-3)	Explains the relationship of code formats to targets
Choosing a Code Format for Your Application (p. 3-10)	Discusses the applicability and limitations of code formats and targets with regard to types of applications
Real-Time Code Format (p. 3-14)	Describes code generation for building nonembedded applications
Real-Time malloc Code Format (p. 3-16)	Describes code generation for building nonembedded applications with dynamic allocation
S-Function Code Format (p. 3-18)	Describes code generation for building S-function targets
Embedded Code Format (p. 3-18)	Describes code generation for building embedded applications

Introduction

Real-Time Workshop provides five different *code formats*. Each code format specifies a framework for code generation suited for specific applications. The five code formats and corresponding application areas are

- **Real-time** — Rapid prototyping
- **Real-time malloc** — Rapid prototyping
- **S-function** — Creating proprietary S-function MEX-file objects, code reuse, and speeding up your simulation
- **Model reference** — Creating MEX-file objects from entire models that other models can use, sometimes in place of S-functions
- **Embedded C** — Deeply embedded systems

This chapter discusses the relationship of code formats to the available target configurations, and factors you should consider when choosing a code format and target. This chapter also summarizes the real-time, real-time malloc, S-function, model referencing, and embedded C/C++ code formats.

Targets and Code Formats

In this section...
“Introduction” on page 3-3
“Backwards Compatibility of Code Formats” on page 3-4
“How Symbols Are Formatted in Generated Code” on page 3-7

Introduction

A *target* (such as the GRT target) is an environment for generating and building code intended for execution on a certain hardware or operating system platform. A target is defined at the top level by a system target file, which in turn invokes other target-specific files.

A *code format* (such as embedded or real-time) is one property of a target. The code format controls decisions made at several points in the code generation process. These include whether and how certain data structures are generated (for example, `SimStruct` or `rtModel`), whether or not static or dynamic memory allocation code is generated, and the calling interface used for generated model functions. In general, the Embedded-C code format is more efficient than the `RealTime` code format. Embedded-C code format provides more compact data structures, a simpler calling interface, and static memory allocation. These characteristics make the Embedded-C code format the preferred choice for production code generation.

In prior releases, only the ERT target and targets derived from the ERT target used the Embedded-C code format. Non-ERT targets used other code formats (for example, `RealTime` or `RealTimeMalloc`).

In Release 14, the GRT target uses the Embedded-C code format for back end code generation. This includes generation of both algorithmic model code and supervisory timing and task scheduling code. The GRT target (and derived targets) generates a `RealTime` code format wrapper around the Embedded-C code. This wrapper provides a calling interface that is backward compatible with existing GRT-based custom targets. The wrapper calls are compatible with the main program module of the GRT target (`grt_main.c` or `grt_main.cpp`). This use of wrapper calls incurs some calling overhead;

the pure Embedded-C calling interface generated by the ERT target is more highly optimized.

For a description of the calling interface generated by the ERT target, see “Data Structures, Code Modules, and Program Execution” in the Real-Time Workshop Embedded Coder documentation. The calling interface generated by the GRT target is described in Chapter 7, “Program Architecture”.

Code format unification simplifies the conversion of GRT-based custom targets to ERT-based targets. See “Making GRT-Based Targets ERT-Compatible” on page 3-21 for a discussion of target conversion issues.

Backwards Compatibility of Code Formats

Because GRT targets now use Embedded-C code format, existing applications that depend on the RealTime code format’s calling interface could have compatibility issues. To address this, a set of macros is generated (in *model.h*) that maps Embedded-C data structures to the identifiers that RealTime code format used. The following, which can be found in any *model.h* file created for a GRT target, describes these identifier mappings:

```
/* Backward compatible GRT Identifiers */
#define rtB                               model_B
#define BlockIO                           BlockIO_model
#define rtXdot                             model_Xdot
#define StateDerivatives                  StateDerivatives_model
#define tXdis                             model_Xdis
#define StateDisabled                     StateDisabled_model
#define rtY                               model_Y
#define ExternalOutputs                   ExternalOutputs_model
#define rtP                               model_P
#define Parameters                        Parameters_model
```

Since the GRT target now uses the Embedded-C code format for back end code generation, many Embedded-C optimizations are available to all Real-Time Workshop users. In general, the GRT and ERT targets now have many more common features, but the ERT target offers additional controls for common features. The availability of features is now determined by licensing, rather than being tied to code format. The following table compares features

available with a Real-Time Workshop license with those available under a Real-Time Workshop Embedded Coder license:

Comparison of Features Licensed with Real-Time Workshop Versus Real-Time Workshop Embedded Coder

Feature	Real-Time Workshop License	Real-Time Workshop Embedded Coder License
rtModel data structure	Full rtModel structure generated. GRT variable declaration: <code>rtModel_model model_M;</code>	rtModel is optimized for the model. Suppression of error status field, data logging fields, and in the structure is optional. ERT variable declaration: <code>RT_MODEL_model model_M;</code>
Custom storage classes (CSCs)	Code generation ignores CSCs; objects are assigned a CSC default to Auto storage class.	Code generation with CSCs is supported.
HTML code generation report	Basic HTML code generation report	Enhanced report with additional detail and hyperlinks to the model.
Symbol formatting	Symbols (for signals, parameters and so on) are generated in accordance with hard-coded default.	Detailed control over generated symbols.
User-defined maximum identifier length for generated symbols	Supported	Supported
Generation of terminate function	Always generated	Option to suppress terminate function
Combined output/update function	Separate output/update functions are generated.	Option to generate combined output/update function
Optimized data initialization	Not available	Options to suppress generation of unnecessary initialization code for zero-valued memory, I/O ports, and so on

Comparison of Features Licensed with Real-Time Workshop Versus Real-Time Workshop Embedded Coder (Continued)

Feature	Real-Time Workshop License	Real-Time Workshop Embedded Coder License
Comments generation	Basic options to include or suppress comment generation	Options to include Simulink block descriptions, Stateflow object descriptions, and Simulink data object descriptions in comments
Module Packaging Features (MPF)	Not supported	Extensive code customization features. See the Real-Time Workshop Embedded Coder documentation.
Target-optimized data types header file	Requires full <code>tmwtypes.h</code> header file.	Generates optimized <code>rtwtypes.h</code> header file, including only the necessary definitions required by the target.
User-defined types	User-defined types default to base types in code generation	User defined data type aliases are supported in code generation.
Simplified call interface	Non-ERT targets default to GRT interface.	ERT and ERT-based targets generate simplified interface.
Rate grouping	Not supported	Supported
Auto-generation of main program module	Not supported; static main program module is provided.	Automated and customizable generation of main program module is supported. Static main program also available.
MAT-file logging	No option to suppress MAT-file logging data structures	Option to suppress MAT-file logging data structures
Reusable (multi-instance) code generation with static memory allocation	Not supported	Option to generate reusable code
Software constraint options	Support for floating point, complex, and nonfinite numbers is always enabled.	Options to enable or disable support for floating-point, complex, and nonfinite number

Comparison of Features Licensed with Real-Time Workshop Versus Real-Time Workshop Embedded Coder (Continued)

Feature	Real-Time Workshop License	Real-Time Workshop Embedded Coder License
Application life span	Defaults to inf	User-specified; determines most efficient word size for integer timers.
Software-in-the-loop (SIL) testing	Model reference simulation target can be used for SIL testing.	Additional SIL testing support by using auto-generation of Simulink S-Function block
ANSI-C/C++ code generation	Supported	Supported
ISO-C/C++ code generation	Supported	Supported
GNU-C/C++ code generation	Supported	Supported
Generate scalar inlined parameters as #DEFINE statements	Not supported	Supported
MAT-file variable name modifier	Supported	Supported
Data exchange: C-API, external mode, ASAP2	Supported	Supported

How Symbols Are Formatted in Generated Code

Real-Time Workshop constructs identifiers automatically for GRT targets. The symbols that are so constructed include those for

- Signals and parameters that have Auto storage class
- Subsystem function names that are not user defined
- All Stateflow names

Prior to Release 14, you could exercise these options (on the Simulation Parameters dialog box **Code appearance** pane) to format identifiers:

- **Prefix model name to global identifiers**
- **Include System Hierarchy Number in Identifiers**
- **Include data type acronym in identifier**

These options have been removed from the Real-Time Workshop GUI and replaced by a default symbol formatting specification. The components of a generated symbol are

- The root model name, followed by
- The name of the generating object (signal, parameter, state, and so on), followed by
- A unique *name mangling* string (if required)

The number of characters that any generated symbol can have is limited by the **Maximum identifier length** parameter specified on the **Symbols** pane of the Configuration Parameters dialog box. When there is a potential name collision between two symbols, a name mangling string is generated. The string has the minimum number of characters required to avoid the collision. The other symbol components are then inserted. If the **Maximum identifier length** parameter is not large enough to accommodate full expansions of the other components, they are truncated. To avoid this outcome, it is good practice to

- Avoid name collisions in general. One way to do this is to avoid using default block names (for example, Gain1, Gain2. . .) when there are many blocks of the same type in the model. Also, whenever possible, make subsystems atomic and reusable.
- Where possible, increase the **Maximum identifier length** to accommodate the length of the symbols you expect to generate. The maximum length you can specify is 256 characters.

Model Referencing Considerations

Within a model that uses model referencing, there can be no collisions between the names of the constituent models. When you generate code from

a model that uses model referencing, the **Maximum identifier length** parameter must be large enough to accommodate the root model name and the name mangling string (if needed). A code generation error occurs if **Maximum identifier length** is not large enough.

When a name conflict occurs between a symbol within the scope of a higher-level model and a symbol within the scope of a referenced model, the symbol from the referenced model is preserved. Name mangling is performed on the symbol from the higher-level model.

Real-Time Workshop Embedded Coder provides a **Symbol format** field that lets you control the formatting of generated symbols in much greater detail. See “Code Generation Options and Optimizations” in the Real-Time Workshop Embedded Coder documentation for more information.

Choosing a Code Format for Your Application

Your choice of code format is the most important code generation option. The code format specifies the overall framework of the generated code and determines its style.

When you choose a target, you implicitly choose a code format. Typically, the system target file will specify the code format by assigning the TLC variable `CodeFormat`. The following example is from `ert.tlc`.

```
%assign CodeFormat = "Embedded-C"
```

If the system target file does not assign `CodeFormat`, the default is `RealTime` (as in `grt.tlc`).

If you are developing a custom target, you must consider which code format is best for your application and assign `CodeFormat` accordingly.

Choose the `RealTime` or `RealTime_malloc` code format for rapid prototyping. If your application does not have significant restrictions in code size, memory usage, or stack usage, you might want to continue using the generic real-time (GRT) target throughout development.

For production deployment, and when your application demands that you limit source code size, memory usage, or maintain a simple call structure, the Embedded-C code format is appropriate. Consider using Real-Time Workshop Embedded Coder, if you need added flexibility to configure and optimize code.

Finally, you should choose the Model Reference or the S-function formats if you are not concerned about RAM and ROM usage and want to

- Use a model as a component, for scalability
- Create a proprietary S-function MEX-file object
- Interface the generated code using the S-function C API
- Speed up your simulation

The following table summarizes how different targets support applications:

Application	Targets
Fixed- or variable-step acceleration	RSIM, S-Function, Model Reference
Fixed-step real-time deployment	GRT, GRT-Malloc, ERT, xPC, Tornado, Real-Time Windows, TI-DSP, MPC5xx, ...

The following table summarizes the various options available for each Real-Time Workshop code format/target, with the exceptions noted.

Features Supported by Real-Time Workshop Targets and Code Formats

Feature	GRT	Real-time malloc	ERT	ERT Shared Library	VxWorks /Tornado	S-Func	RSIM	RT Win	xPC	Other Supported Targets ¹
Static memory allocation	X		X		X			X	X	X
Dynamic memory allocation		X			X	X	X			
Continuous time	X	X	X		X	X	X	X	X	
C/C++ MEX S-functions (noninlined)	X	X	X		X	X	X	X	X	
S-function (inlined)	X	X	X		X	X	X	X	X	X
Minimize RAM/ROM usage			X		X ²				X ²	X
Supports external mode	X	X	X		X		X	X	X	

Features Supported by Real-Time Workshop Targets and Code Formats (Continued)

Feature	GRT	Real-time malloc	ERT	ERT Shared Library	VxWorks /Tornado	S-Func	RSIM	RT Win	xPC	Other Supported Targets¹
Rapid prototyping	X	X			X			X	X	X
Production code			X		X ²				X ²	X ³
Batch parameter tuning and Monte Carlo methods				X			X			
System-level Simulator				X						
Executes in hard real time	X ⁴	X ⁴	X ⁴		X			X	X	X ⁵
Non real-time executable included	X	X	X				X			
Multiple instances of model		X ⁶	X ^{6, 7}			X ⁶			X ^{2, 6, 7}	X ^{2, 6, 7}
Supports variable-step solvers						X	X			
Supports SIL/PIL			X							X

¹The Other Supported Targets are: Link for CCS, Target for C2000, Target for C6000, Link for Tasking, Target for C166, and Target for MPC555.

²Does not apply to GRT based targets. Applies only to an ERT based target.

³Except MPC5xx (algorithm export) targets

⁴The default GRT, GRT malloc, and ERT `rt_main` files emulate execution of hard real time, and when explicitly connected to a real-time clock execute in hard real time.

⁵Except MPC5xx (processor-in-the-loop) and MPC5xx (algorithm export) targets

⁶You can generate code for multiple instances of a Stateflow chart or subsystem containing a Stateflow chart, except when the Stateflow chart contains exported graphical functions or the Stateflow model contains machine parented events.

⁷You must enable **Generate reusable code** in the Configuration Parameters Real-Time Workshop: Interface pane.

Real-Time Code Format

In this section...
“Introduction” on page 3-14
“Unsupported Blocks” on page 3-14
“System Target Files” on page 3-15
“Template Makefiles” on page 3-15

Introduction

The real-time code format (corresponding to the generic real-time target) is useful for rapid prototyping applications. If you want to generate real-time code while iterating model parameters rapidly, you should begin the design process with the generic real-time target. The real-time code format supports:

- Continuous time
- Continuous states
- C/C++ MEX S-functions (inlined and noninlined)

For more information on inlining S-functions, see Chapter 10, “Writing S-Functions for Real-Time Workshop Code Generation”, and the Target Language Compiler documentation.

The real-time code format declares memory statically, that is, at compile time.

Unsupported Blocks

The real-time format does not support the following built-in user-defined blocks:

- MATLAB Fcn (note that Simulink Fcn blocks *are* supported)
- S-Function — M-file S-functions, Fortran S-functions, or C/C++ MEX S-functions that call into MATLAB (Simulink Fcn calls *are* supported)

System Target Files

- `grt.tlc` — Generic real-time target
- `rsim.tlc` — Rapid simulation target
- `tornado.tlc` — Tornado (VxWorks) real-time target

Template Makefiles

- `grt`
 - `grt_bc.tmf` — Borland C
 - `grt_vc.tmf` — Visual C
 - `grt_watc.tmf` — Watcom C
 - `grt_lcc.tmf` — Lcc compiler
 - `grt_unix.tmf` — UNIX host
- `rsim`
 - `rsim_bc.tmf` — Borland C
 - `rsim_vc.tmf` — Visual C
 - `rsim_watc.tmf` — Watcom C
 - `rsim_lcc.tmf` — Lcc compiler
 - `rsim_unix.tmf` — UNIX host
- `tornado.tmf`
- `win_watc.tmf`

Real-Time malloc Code Format

In this section...

- “Introduction” on page 3-16
- “Unsupported Blocks” on page 3-16
- “System Target Files” on page 3-17
- “Template Makefiles” on page 3-17

Introduction

The real-time malloc code format (corresponding to the generic real-time malloc target) is very similar to the real-time code format. The differences are

- Real-time malloc declares memory dynamically.
For blocks provided by The MathWorks, malloc calls are limited to the model initialization code. Generated code is designed to be free from memory leaks, provided that the model termination function is called.
- Real-time malloc allows you to deploy multiple instances of the same model with each instance maintaining its own unique data.
- Real-time malloc allows you to combine multiple models together in one executable. For example, to integrate two models into one larger executable, real-time malloc maintains a unique instance of each of the two models. If you do not use the real-time malloc format, Real-Time Workshop will not necessarily create uniquely named data structures for each model, potentially resulting in name clashes.

`grt_malloc_main.c` (or `.cpp`), the main routine for the generic real-time malloc (`grt_malloc`) target, supports one model by default. See “Combining Multiple Models” on page 17-35 for information on modifying `grt_malloc_main.c` (or `.cpp`) to support multiple models. `grt_malloc_main.c` and `grt_malloc_main.cpp` are located in the directory `matlabroot/rtw/c/grt_malloc`.

Unsupported Blocks

The real-time malloc format does not support the following built-in blocks, as shown:

- Functions & Tables
 - MATLAB Fcn (note that Simulink Fcn blocks *are* supported)
 - S-Function — M-file S-functions, Fortran S-functions, or C/C++ MEX S-functions that call into MATLAB (Simulink Fcn calls *are* supported)

System Target Files

- grt_malloc.tlc
- tornado.tlc — Tornado (VxWorks) real-time target

Template Makefiles

- grt_malloc
 - grt_malloc_bc.tmf — Borland C
 - grt_malloc_vc.tmf — Visual C
 - grt_malloc_watc.tmf — Watcom C
 - grt_malloc_lcc.tmf — Lcc compiler
 - grt_malloc_unix.tmf — UNIX host
- tornado.tmf

S-Function Code Format

The S-function code format (corresponding to the S-function target) generates code that conforms to the Simulink MEX S-function API. Using the S-function target, you can build an S-function component and use it as an S-Function block in another model.

The S-function code format is also used by the accelerated simulation target to create the Accelerator MEX-file.

In general, you should not use the S-function code format in a system target file. However, you might need to do special handling in your inlined TLC files to account for this format. You can check the TLC variable `CodeFormat` to see if the current target is a MEX-file. If `CodeFormat = "S-Function"` and the TLC variable `Accelerator` is set to 1, the target is an accelerated simulation MEX-file.

See Chapter 11, “S-Function Target”, for more information.

Embedded Code Format

In this section...
“Introduction” on page 3-18
“Using the Real-Time Model Data Structure” on page 3-19
“Making GRT-Based Targets ERT-Compatible” on page 3-21

Introduction

The Embedded-C code format corresponds to the Real-Time Workshop Embedded Coder target (ERT), and targets derived from ERT. This code format includes a number of memory-saving and performance optimizations. See the Real-Time Workshop Embedded Coder documentation for details.

Using the Real-Time Model Data Structure

The Embedded C format uses the real-time model (RT_MODEL) data structure. This structure is also referred to as the `rtModel` data structure. You can access `rtModel` data by using a set of macros analogous to the `ssSetxxx` and `ssGetxxx` macros that S-functions use to access `SimStruct` data, including noninlined S-functions compiled by Real-Time Workshop, and are documented in the Simulink Writing S-Functions documentation.

You need to use the set of macros `rtmGetxxx` and `rtmSetxxx` to access the real-time model data structure, which is specific to Real-Time Workshop. The `rtModel` is an optimized data structure that replaces `SimStruct` as the top level data structure for a model. The `rtmGetxxx` and `rtmSetxxx` macros are used in the generated code as well as from the `main.c` or `main.cpp` module. If you are customizing `main.c` or `main.cpp` (either a static file or a generated file), you need to use `rtmGetxxx` and `rtmSetxxx` instead of the `ssSetxxx` and `ssGetxxx` macros.

Usage of `rtmGetxxx` and `rtmSetxxx` macros is the same as for the `ssSetxxx` and `ssGetxxx` versions, except that you replace `SimStruct` S by real-time model data structure `rtM`. The following table lists `rtmGetxxx` and `rtmSetxxx` macros that are used in `grt_main.c`, `grt_main.cpp`, `grt_malloc_main.c`, and `grt_malloc_main.cpp`.

Macros for Accessing the Real-Time Model Data Structure

rtm Macro Syntax	Description
<code>rtmGetdX(rtm)</code>	Get the derivatives of a block's continuous states
<code>rtmGetOffsetTimePtr(RT_MDL rtM)</code>	Return the pointer of vector that store all sample time offset of the model associated with <code>rtM</code>
<code>rtmGetNumSampleTimes(RT_MDL rtM)</code>	Get the number of sample times that a block has
<code>rtmGetPerTaskSampleHitsPtr(RT_MDL)</code>	Return a pointer of <code>NumSampleTime × NumSampleTime</code> matrix

Macros for Accessing the Real-Time Model Data Structure (Continued)

rtm Macro Syntax	Description
<code>rtmGetRTWExtModeInfo(RT_MDL rtm)</code>	Return an external mode information data structure of the model. This data structure is used internally for external mode.
<code>rtmGetRTWLogInfo(RT_MDL)</code>	Return a data structure used by Real-Time Workshop logging. Internal use.
<code>rtmGetRTWRModelMethodsInfo(RT_MDL)</code>	Return a data structure of Real-Time Workshop real-time model methods information. Internal use.
<code>rtmGetRTWSolverInfo(RT_MDL)</code>	Return data structure containing solver information of the model. Internal use.
<code>rtmGetSampleHitPtr(RT_MDL)</code>	Return a pointer of Sample Hit flag vector
<code>rtmGetSampleTime(RT_MDL rtm, int TID)</code>	Get a task's sample time
<code>rtmGetSampleTimePtr(RT_MDL rtm)</code>	Get pointer to a task's sample time
<code>rtmGetSampleTimeTaskIDPtr(RT_MDL rtm)</code>	Get pointer to a task's ID
<code>rtmGetSimTimeStep(RT_MDL)</code>	Return simulation step type ID (MINOR_TIME_STEP, MAJOR_TIME_STEP)
<code>rtmGetStepSize(RT_MDL)</code>	Return the fundamental step size of the model
<code>rtmGetT(RT_MDL, t)</code>	Get the current simulation time
<code>rtmSetT(RT_MDL, t)</code>	Set the time of the next sample hit
<code>rtmGetTaskTime(RT_MDL, tid)</code>	Get the current time for the current task
<code>rtmGetTFinal(RT_MDL)</code>	Get the simulation stop time
<code>rtmSetTFinal(RT_MDL, finalT)</code>	Set the simulation stop time
<code>rtmGetTimingData(RT_MDL)</code>	Return a data structure used by timing engine of the model. Internal use.
<code>rtmGetTPtr(RT_MDL)</code>	Return a pointer of the current time
<code>rtmGetTStart(RT_MDL)</code>	Get the simulation start time
<code>rtmIsContinuousTask(rtm)</code>	Determine whether a task is continuous

Macros for Accessing the Real-Time Model Data Structure (Continued)

rtm Macro Syntax	Description
rtmIsMajorTimeStep(rtm)	Determine whether the simulation is in a major step
rtmIsSampleHit(RT_MDL, tid)	Determine whether the sample time is hit

For additional details on usage, see “SimStruct Functions — Alphabetical List” in the Simulink Writing S-Functions documentation.

Making GRT-Based Targets ERT-Compatible

If you have developed a GRT-based custom target, it is simple to make your target ERT compatible. By doing so, you can take advantage of many efficiencies.

There are several approaches to ERT compatibility:

- If your installation is not licensed for Real-Time Workshop Embedded Coder, you can convert a GRT-based target as described in “Converting Your Target to Use rtModel” on page 3-22. This enables your custom target to support all current GRT features, including back end Embedded-C code generation.
- You can create an ERT-based target, but continue to use your customized version of the `grt_main.c` or `grt_main.cpp` module. To do this, you can configure the ERT target to generate a GRT-compatible calling interface, as described in “Generating GRT Wrapper Code from the ERT target” on page 3-23. This lets your target support the full ERT feature set, without changing your GRT-based run-time interface. This approach requires that your installation be licensed for Real-Time Workshop Embedded Coder.
- If your installation is licensed for Real-Time Workshop Embedded Coder, you can reimplement your custom target as a completely ERT-based target, including use of an ERT generated main program. This approach lets your target support the full ERT feature set, without the overhead caused by wrapper calls.

Note If you intend to use custom storage classes (CSCs) with a custom target, you must use an ERT-based target. See “Custom Storage Classes” in the Real-Time Workshop Embedded Coder documentation for detailed information on CSCs.

For details on how GRT targets are made call-compatible with previous versions of Real-Time Workshop, see “The Real-Time Model Data Structure” on page 7-31.

Converting Your Target to Use `rtModel`

The real-time model data structure (`rtModel`) encapsulates model-specific information in a much more compact form than the `SimStruct`. Many ERT-related efficiencies depend on generation of `rtModel` rather than `SimStruct`, including

- Integer absolute and elapsed timing services
- Independent timers for asynchronous tasks
- Generation of improved C-API code for signal and parameter monitoring
- Pruning the data structure to minimize its size (ERT-derived targets only)

To take advantage of such efficiencies, you must update your GRT-based target to use the `rtModel` (unless you already did so for Release 13). The conversion requires changes to your system target file, template makefile, and main program module.

The following changes to the system target file and template makefile are required to use `rtModel` instead of `SimStruct`:

- In the system target file, add the following global variable assignment:

```
%assign GenRTModel = TLC_TRUE
```

- In the template makefile, define the symbol `USE_RTMODEL`. See one of the GRT template makefiles for an example.

The following changes to your main program module (that is, your customized version of `grt_main.c` or `grt_main.cpp`) are required to use `rtModel` instead of `SimStruct`:

- Include `rtmodel.h` instead of `simstruc.h`.
- Since the `rtModel` data structure has a type that includes the model name, define the following macros at the top of the main program file:

```
#define EXPAND_CONCAT(name1,name2) name1 ## name2
#define CONCAT(name1,name2) EXPAND_CONCAT(name1,name2)
#define RT_MODEL CONCAT(MODEL,_rtModel)
```

- Change the extern declaration for the function that creates and initializes the `SimStruct` to

```
extern RT_MODEL *MODEL(void);
```

- Change the definitions of `rt_CreateIntegrationData` and `rt_UpdateContinuousStates` to be as shown in the Release 14 version of `grt_main.c`.
- Change all function prototypes to have the argument '`RT_MODEL`' instead of the argument '`SimStruct`'.
- The prototypes for the functions `rt_GetNextSampleHit`, `rt_UpdateDiscreteTaskSampleHits`, `rt_UpdateContinuousStates`, `rt_UpdateDiscreteEvents`, `rt_UpdateDiscreteTaskTime`, and `rt_InitTimingEngine` have changed. Change their names to use the prefix `rt_Sim` instead of `rt_` and then change the arguments you pass in to them. See the Release 14 version of `grt_main.c` for the list of arguments passed in to each function.
- Modify all macros that refer to the `SimStruct` to now refer to the `rtModel`. `SimStruct` macros begin with the prefix `ss`, whereas `rtModel` macros begin with the prefix `rtm`. For example, change `ssGetErrorStatus` to `rtmGetErrorStatus`.

Generating GRT Wrapper Code from the ERT target

Real-Time Workshop Embedded Coder supports the **GRT compatible call interface** option. When this option is selected, Real-Time Workshop

Embedded Coder generates model function calls that are compatible with the main program module of the GRT target (`grt_main.c` or `grt_main.cpp`). These calls act as wrappers that interface to ERT (Embedded-C format) generated code.

This option provides a quick way to use ERT target features with a GRT-based custom target that has a main program module based on `grt_main.c` or `grt_main.cpp`.

See the “Code Generation Options and Optimizations” in the Real-Time Workshop Embedded Coder documentation for detailed information on the **GRT compatible call interface** option.

Building Subsystems and Working with Referenced Models

Nonvirtual Subsystem Code Generation (p. 4-2)

Discusses ways to generate separate code modules from nonvirtual subsystems

Generating Code and Executables from Subsystems (p. 4-23)

Describes how to generate and build a standalone executable from a subsystem

Generating Code for Model Referencing (p. 4-26)

Explains how referenced models can be incorporated into generated code

Sharing Utility Functions (p. 4-49)

Explains how to use the shared utility feature to modularize generated code.

Supporting Shared Utility Directories in the Build Process (p. 4-55)

Discusses changes you need to make to a template make file to support the shared utilities directory

Nonvirtual Subsystem Code Generation

In this section...
“Introduction” on page 4-2
“Nonvirtual Subsystem Code Generation Options” on page 4-3
“Modularity of Subsystem Code” on page 4-14
“Code Reuse Limitations” on page 4-15
“Determining Why Subsystem Code Is Not Reused” on page 4-15

Introduction

Real-Time Workshop allows you to control how code is generated for any nonvirtual subsystem. The categories of nonvirtual subsystems are:

- *Conditionally executed* subsystems: execution depends upon a control signal or control block. These include triggered subsystems, enabled subsystems, action and iterator subsystems, subsystems that are both triggered and enabled, and function call subsystems. See “Creating Conditionally Executed Subsystems” in the Simulink documentation for more information.
- *Atomic* subsystems: Any virtual subsystem can be declared atomic (and therefore nonvirtual) by using the **Treat as atomic unit** option in the Block Parameters dialog box.

Note You should declare virtual subsystems as atomic subsystems to ensure consistent simulation and execution behavior for your model. If you generate code for a virtual subsystem, Real-Time Workshop treats the subsystem as atomic and generates the code accordingly. The resulting code can change the execution behavior of your model, for example, by applying algebraic loops, and introduce inconsistencies with the simulation behavior.

See “Systems and Subsystems” in the Simulink documentation, and run the `sl_subsys_semantics` demo for more information on nonvirtual subsystems and atomic subsystems.

You can control the code generated from nonvirtual subsystems as follows:

- You can instruct Real-Time Workshop to generate separate functions, within separate code files if desired, for selected nonvirtual systems. You can control both the names of the functions and of the code files generated from nonvirtual subsystems.
- You can cause multiple instances of a subsystem to generate *reusable* code, that is, as a single reentrant function, instead of replicating the code for each instance of a subsystem or each time it is called.
- You can generate inlined code from selected nonvirtual subsystems within your model. When you inline a nonvirtual subsystem, a separate function call is not generated for the subsystem.

Nonvirtual Subsystem Code Generation Options

For any nonvirtual subsystem, you can choose the following code generation options from the **Real-Time Workshop system code** menu in the subsystem Block parameters dialog box:

- **Auto:** This is the default option, and provides the greatest flexibility in most situations. See “Auto Option” on page 4-4 below.
- **Inline:** This option explicitly directs Real-Time Workshop to inline the subsystem unconditionally.
- **Function:** This option explicitly directs Real-Time Workshop to generate a separate function with no arguments, and (optionally), place the subsystem in a separate file. You can name the generated function and file. As functions created with this option rely on global data, they are not reentrant.
- **Reusable function:** Generates a function with arguments that allows the subsystem’s code to be shared by other instances of it in the model. To enable sharing, Real-Time Workshop must be able to determine (by using checksums) that subsystems are identical. The generated function will have arguments for block inputs and outputs (`rtB_*`), continuous states (`rtDW_*`), parameters (`rtP_*`), and so on.

Note You should not directly call reusable functions generated by Real-Time Workshop. The call interface is subject to change.

The following sections discuss these options further.

Auto Option

The Auto option is the default, and is generally appropriate. Auto causes Real-Time Workshop to inline the subsystem when there is only one instance of it in the model. When multiple instances of a subsystem exist, the Auto option results in a single copy of the function whenever possible (as a reusable function). Otherwise, the result is as though you selected Inline (except for function call subsystems with multiple callers, which is handled as if you specified Function). Choose Inline to always inline subsystem code, or Function when you specifically want to generate a separate function without arguments for each instance, optionally in a separate file.

Note When you want multiple instances of a subsystem to be represented as one reusable function, you can designate each one of them as Auto or as Reusable function. It is best to use one or the other, as using both creates two reusable functions, one for each designation. The outcomes of these choices differ only when reuse is not possible.

To use the Auto option,

- 1 Select the subsystem block. Then select **Subsystem Parameters** from the Simulink **Edit** menu. The Block Parameters dialog box opens, as shown in the next figure.

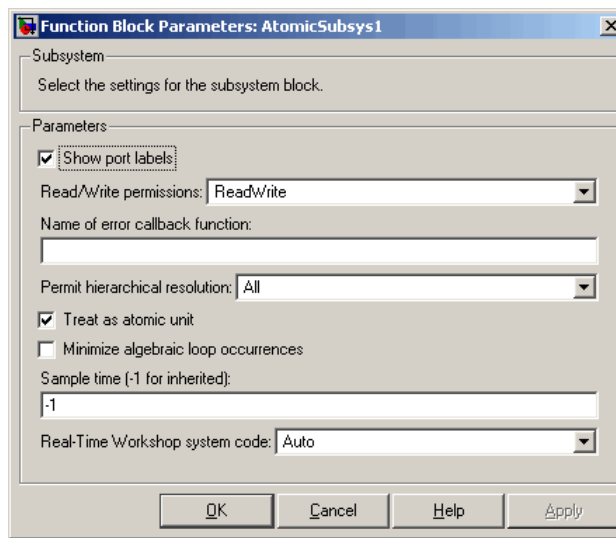
Alternatively, you can open the Block Parameters dialog box by

- Shift-double-clicking the subsystem block
- Right-clicking the subsystem block and selecting **Block parameters** from the menu

- 2 If the subsystem is virtual, select **Treat as atomic unit** as shown in the next figure. This makes the subsystem nonvirtual, and the **Real-Time Workshop system code** option becomes enabled.

If the system is already nonvirtual, the **Real-Time Workshop system code** option is already enabled.

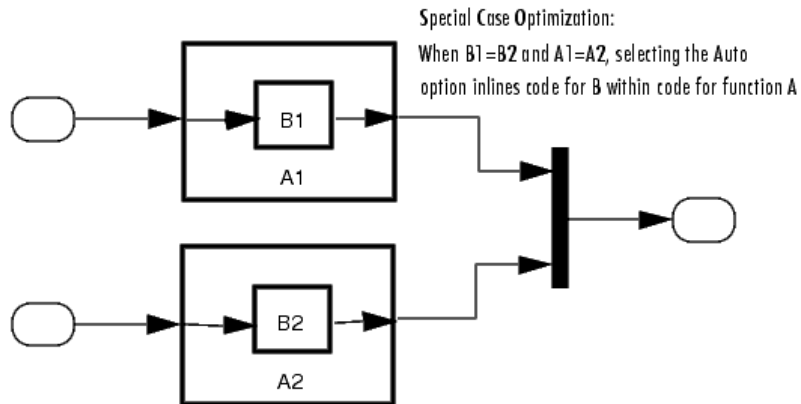
- 3 Select **Auto** from the **Real-Time Workshop system code** menu as shown in the figure below.



- 4 Click **Apply** and close the dialog box.

The border of the subsystem thickens, indicating that it is nonvirtual.

Auto Optimization for Special Cases. Rather than reverting to **Inline**, the **Auto** option can optimize code in special situations in which identical subsystems contain other identical subsystems, by both reusing and inlining generated code. Suppose a model, such as the one shown in **Reuse of Identical Nested Subsystems with the Auto Option** on page 4-6, contains identical subsystems A1 and A2. A1 contains subsystem B1, and A2 contains subsystem B2, which are themselves identical. In such cases, the **Auto** option causes one function to be generated which is called for both A1 and A2, and this function contains one piece of inlined code to execute B1 and B2, ensuring that the resulting code will run as efficiently as possible.



Reuse of Identical Nested Subsystems with the Auto Option

Inline Option

As noted above, you can choose to inline subsystem code when the subsystem is nonvirtual (virtual subsystems are always inlined).

Exceptions to Inlining. There are certain cases in which Real-Time Workshop does not inline a nonvirtual subsystem, even though the **Inline** option is selected. These cases are

- If the subsystem is a function-call subsystem that is called by a noninlined S-function, the **Inline** option is ignored. Noninlined S-functions make such

calls by using function pointers; therefore the function-call subsystem must generate a function with all arguments present.

- In a feedback loop involving function-call subsystems, Real-Time Workshop forces one of the subsystems to be generated as a function instead of inlining it. Real-Time Workshop selects the subsystem to be generated as a function based on the order in which the subsystems are sorted internally.
- If a subsystem is called from an S-Function block that sets the option `SS_OPTION_FORCE_NONINLINED_FCNCALL` to `TRUE`, it is not inlined. This might be the case when user-defined Asynchronous Interrupt blocks or Task Synchronization blocks are required. Such blocks must be generated as functions. The VxWorks Asynchronous Interrupt and Task Synchronization blocks, shipped with Real-Time Workshop, use the `SS_OPTION_FORCE_NONINLINED_FCNCALL` option.

To generate inlined subsystem code,

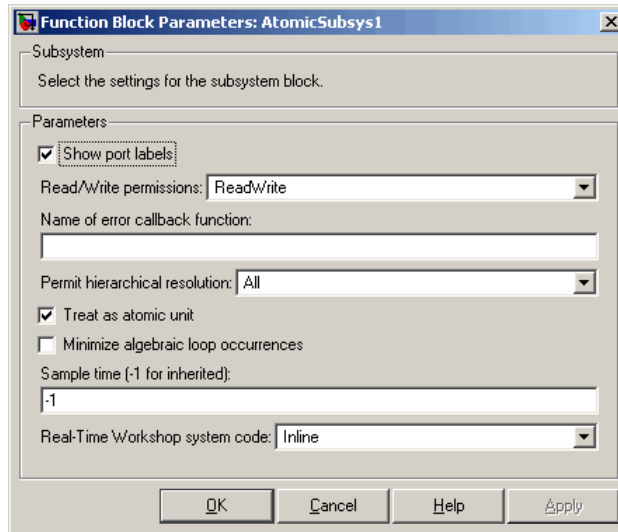
- 1** Select the subsystem block. Then select **Subsystem Parameters** from the Simulink **Edit** menu. The Block Parameters dialog box opens.

Alternatively, you can open the Block Parameters dialog box by

- Shift-double-clicking the subsystem block
 - Right-clicking the subsystem block and selecting **Block parameters** from the menu
- 2** If the subsystem is virtual, select **Treat as atomic unit** as shown in the next figure. This makes the subsystem atomic, and the **Real-Time Workshop system code** menu becomes enabled.

If the system is already nonvirtual, the **Real-Time Workshop system code** menu is already enabled.

- 3** Select **Inline** from the **Real-Time Workshop system code** menu as shown in the figure below.



4 Click **Apply** and close the dialog box.

When you generate code from your model, Real-Time Workshop writes inline code within *model.c* or *model.cpp* (or in its parent system's source file) to perform subsystem computations. You can identify this code by system/block identification tags, such as the following.

```
/* Atomic SubSystem Block: <Root>/AtomicSubsys1 */
```

See “Tracing Generated Code Back to Your Simulink Model” on page 2-125 for more information on system/block identification tags.

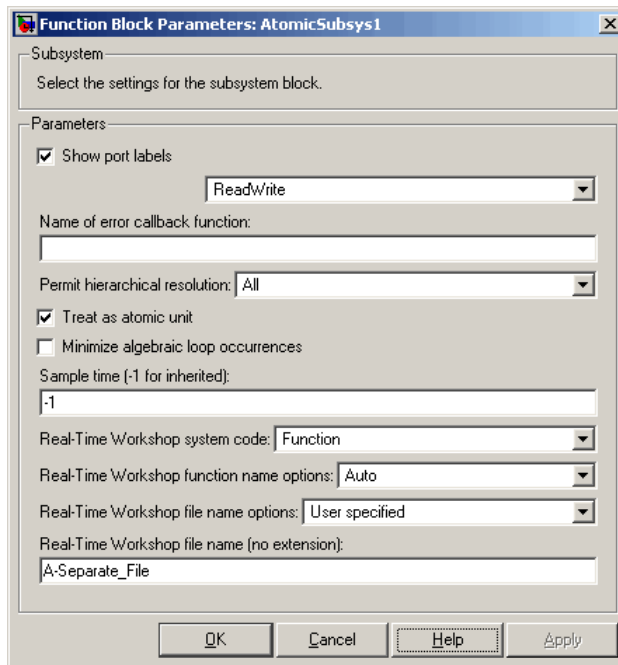
Function Option

Choosing the Function or Reusable function option lets you direct Real-Time Workshop to generate a separate function and optionally a separate file for the subsystem. When you select the Function option, two additional options are enabled:

- The **Real-Time Workshop function name options** menu lets you control the naming of the generated function.

- The **Real-Time Workshop file name options** menu lets you control the naming of the generated file (if a separate file is generated and you select the User specified option).

The figure below shows the Block Parameters dialog box with the Function option selected, with **Real-Time Workshop file name options** set to User specified, and with a name specified for the generated file.



Subsystem Function Code Generation Option with User-Specified File Name

Real-Time Workshop Function Name Options Menu. This menu offers the following choices, but the resulting identifiers are also affected by which General code appearance options are in effect for the model:

- Auto: By default, Real-Time Workshop assigns a unique function name using the default naming convention: `model_subsystem()`, where *subsystem* is the name of the subsystem (or that of an identical one when code is being reused).

- Use subsystem name: Real-Time Workshop uses the subsystem name as the function name.

Note When a subsystem is a library block, the Use subsystem name option causes its function identifier (and file name, see below) to be that of the library block, regardless of the names used for that subsystem in the model.

- User specified: When this option is selected, the **Real-Time Workshop function name** field is enabled. Enter any legal C or C++ function name (which must be unique).

Real-Time Workshop File Name Options Menu. This menu offers the following choices:

- Use subsystem name: Real-Time Workshop generates a separate file, using the subsystem (or library block) name as the file name.

Note When a subsystem's **Real-Time Workshop file name options** is set to Use subsystem name, the subsystem file name is mangled if the model contains Model blocks, or if a model reference target is being generated for the model. In these situations, the file name for the subsystem consists of the subsystem name prefixed by the model name.

- Use function name: Real-Time Workshop generates a separate file, using the function name (as specified by the **Real-Time Workshop function name options**) as the file name.
- User specified: When this option is selected, the **Real-Time Workshop file name (no extension)** text entry field is enabled. Real-Time Workshop generates a separate file, using the name you enter as the file name. Enter any file name, but do not include the .c or .cpp (or any other) extension. This file name need not be unique.

Note While a subsystem source file name need not be unique, you must avoid giving nonunique names that result in cyclic dependencies (for example, `sys_a.h` includes `sys_b.h`, `sys_b.h` includes `sys_c.h`, and `sys_c.h` includes `sys_a.h`).

- Auto: Real-Time Workshop does *not* generate a separate file for the subsystem. Code generated from the subsystem is generated within the code module generated from the subsystem's parent system. If the subsystem's parent is the model itself, code generated from the subsystem is generated within `model.c` or `model.cpp`.

To generate both a separate subsystem function and a separate file,

- 1** Select the subsystem block. Then select **Subsystem Parameters** from the Simulink **Edit** menu, to open the Block Parameters dialog box.

Alternatively, you can open the Block Parameters dialog box by

- Shift-double-clicking the subsystem block
 - Right-clicking the subsystem block and selecting **Block parameters** from the menu.
- 2** If the subsystem is virtual, select **Treat as atomic unit**. The **Real-Time Workshop system code** menu becomes enabled.

If the system is already nonvirtual, the **Real-Time Workshop system code** menu is already enabled.
 - 3** Select **Function** from the **Real-Time Workshop system code** menu as shown in Subsystem Function Code Generation Option with User-Specified File Name on page 4-9.
 - 4** Set the function name, using the **Real-Time Workshop function name** options described in “Real-Time Workshop Function Name Options Menu” on page 4-9.
 - 5** Set the file name, using any **Real-Time Workshop file name** option other than Auto (options are described in “Real-Time Workshop File Name Options Menu” on page 4-10).

Subsystem Function Code Generation Option with User-Specified File Name on page 4-9 shows the use of the User Specified file name option.

6 Click **Apply** and close the dialog box.

Reusable Function Option

The difference between functions and reusable functions is that the latter have data passed to them as arguments (enabling them to be reentrant), while the former communicate by using global data. Choosing the Reusable function option directs Real-Time Workshop to generate a single function (optionally in a separate file) for the subsystem, and to call that code for each identical subsystem in the model, if possible.

Note The Reusable function option yields code that is called from multiple sites (hence reused) only when the Auto option would also do so. The difference between these options' behavior is that when reuse is not possible, selecting Auto yields inlined code (or if circumstances prohibit inlining, creates a function without arguments), while choosing Reusable function yields a separate function (with arguments) that is called from only one site.

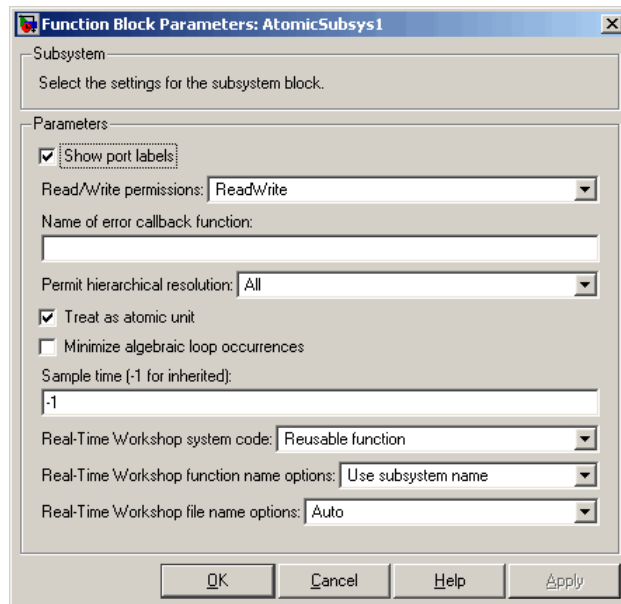
For a summary of code reuse limitations, see “Code Reuse Limitations” on page 4-15.

Generating Reusable Code from Stateflow Charts. You can generate reusable code from a Stateflow chart, or from a subsystem containing a Stateflow chart, *except* in the following cases:

- The Stateflow chart contains exported graphical functions.
- The Stateflow model contains machine parented events.

Generating Reusable Code for Subsystems Containing S-Function Blocks. Regarding S-Function blocks, there are several requirements that need to be met in order for subsystems containing them to be reused. See “Writing S-Functions That Support Code Reuse” on page 10-71 for the list of requirements.

When you select the `Reusable` function option, two additional options are enabled, **Real-Time Workshop function name options** and **Real-Time Workshop file name options**. See the explanation of “Function Option” on page 4-8 for descriptions of these options and fields. If you use these fields to enter a function name and/or a file name, you must specify exactly the same function name and file name for each instance of identical subsystems for Real-Time Workshop to be able to reuse the subsystem code.



Subsystem Reusable Function Code Generation Option

To request that Real-Time Workshop generate reusable subsystem code,

- 1 Select the subsystem block. Then select **Subsystem Parameters** from the Simulink **Edit** menu. The Block Parameters dialog box opens.

Alternatively, you can open the Block Parameters dialog box by:

- Shift-double-clicking the subsystem block
- Right-clicking the subsystem block and selecting **Block parameters** from the menu.

- 2 If the subsystem is virtual, select **Treat as atomic unit**. The **Real-Time Workshop system code** menu becomes enabled.

If the system is already nonvirtual, the **Real-Time Workshop system code** menu is already enabled.

- 3 Select **Reusable** function from the **Real-Time Workshop system code** menu as shown in Subsystem Reusable Function Code Generation Option on page 4-13.
- 4 If you want to give the function a specific name, set the function name, using the **Real-Time Workshop function name** options described in “Real-Time Workshop Function Name Options Menu” on page 4-9.

If you do not choose the **Real-Time Workshop function name** **Auto** option, and want code to be reused, you must assign exactly the same function name to all other subsystem blocks that you want to share this code.

- 5 If you want to direct the generated code to a specific file, set the file name using any **Real-Time Workshop file name** option other than **Auto** (options are described in “Real-Time Workshop File Name Options Menu” on page 4-10).

In order for code to be reused, you must repeat this step for all other subsystem blocks that you want to share this code, using the same file name.

- 6 Click **Apply** and close the dialog box.

Modularity of Subsystem Code

Code generated from nonvirtual subsystems, when written to separate files, is not completely independent of the generating model. For example, subsystem code may reference global data structures of the model. Each subsystem code file contains appropriate include directives and comments explaining the dependencies. Real-Time Workshop checks for cyclic file dependencies and warns about them at build time. For descriptions of how generated code is packaged, see “Generated Source Files and File Dependencies” on page 2-84.

Code Reuse Limitations

Real-Time Workshop uses a checksum to determine whether subsystems are identical. You cannot reuse subsystem code if:

- Multiple ports of a subsystem share the same source.
- A port used by multiple instances of a subsystem has different sample times, data types, complexity, frame status, or dimensions across the instances.
- The output of a subsystem is marked as a global signal.
- Subsystems contain identical blocks with different names or parameter settings.

Some of these situations can arise even when you copy and paste subsystems within or between models or you construct them manually such that they are identical. If you select `Reusable` function and Real-Time Workshop determines that code for a subsystem cannot be reused, it generates a separate function that is not reused. The code generation report can show that the separate function is reusable, even if it is used by only one subsystem. If you prefer that subsystem code be inlined in such circumstances rather than deployed as functions, you choose `Auto` for the **Real-Time Workshop system code** option.

Use of the following blocks in a subsystem can also prevent its code from being reused:

- Scope blocks (with data logging enabled)
- S-Function blocks that fail to meet certain criteria
- To File blocks (with data logging enabled)
- To Workspace blocks (with data logging enabled)

Determining Why Subsystem Code Is Not Reused

Due to the limitations noted in “Code Reuse Limitations” on page 4-15, Real-Time Workshop might not reuse generated code as you expect. To determine why code generated for a subsystem is not reused,

- 1 Review the Subsystems section of the HTML code generation report

- 2 If you cannot determine why based on the report, compare subsystem checksum data

Reviewing the Subsystems Section of the HTML Code Generation Report

If you determine that Real-Time Workshop does not generate code for a subsystem as reusable code and you specified the subsystem as reusable, examine the Subsystems section of the HTML code generation report (see “Configuring Report Generation” on page 2-52). The Subsystems section contains

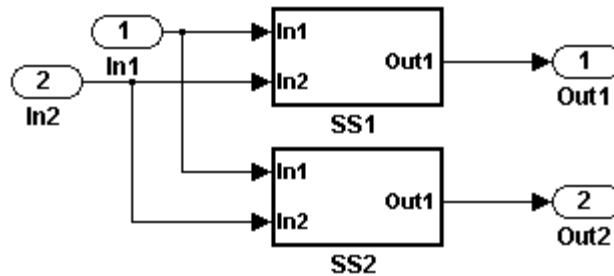
- A table that summarizes how nonvirtual subsystems were converted to generated code
- Diagnostic information that explains why the contents of some subsystems were not generated as reusable code

In addition to diagnosing exceptions, the Subsections section also indicates the mapping of each noninlined subsystem in the model to functions or reused functions in the generated code. For an example, open and build the `rtwdemo_atomic` demo model.

Comparing Subsystem Checksum Data

If the HTML code generation report indicates that no code reuse exceptions occurred and code for a subsystem you expect to be reused is not reused, you can determine why by accessing and comparing subsystem checksum data. Real-Time Workshop determines whether subsystems are identical by comparing subsystem checksums, as noted in “Code Reuse Limitations” on page 4-15.

Consider the demo model, `rtwdemo_ssreuse`.



SS1 and SS2 are instances of the same subsystem, and in both instances the subsystem parameter **Real-Time Workshop system code** is set to Reusable function.

The following example demonstrates how to use the method `Simulink.SubSystem.getChecksum` to get the checksum for a subsystem and compare the results to determine why code is not reused.

- 1 Open the model `rtwdemo_ssreuse` and save a copy of the demo in a directory where you have write access.
- 2 Select subsystem SS1 in the model window and in the command window enter

```
SS1 = gcb;
```

- 3 Select subsystem SS2 in the model window and in the command window enter

```
SS2 = gcb;
```

- 4 Use the method `Simulink.SubSystem.getChecksum` to get the checksum for each subsystem. This method returns two output values: the checksum value and details on the input used to compute the checksum.

```
[chksum1, chksum1_details] = ...
Simulink.SubSystem.getChecksum(SS1);
[chksum2, chksum2_details] = ...
Simulink.SubSystem.getChecksum(SS2);
```

- 5 Compare the two checksum values. They should be equal based on the subsystem configurations.

```
isequal(chksum1, chksum2)
ans =
    1
```

- 6 To see how you can use `Simulink.SubSystem.getChecksum` to determine why the checksums of two subsystems differ, change the data type mode of the output port of SS1 such that it differs from that of SS2.

- a Look under the mask of SS1 by right-clicking the subsystem and selecting **Look Under Mask** in the context menu. A block diagram of the subsystem appears.
- b Double click the Lookup Table block to open the Block Parameters dialog box.
- c Click **Signal Data Types**.
- d Select `int8` for **Output data type mode** and click **OK**.

- 7 Get the checksum for SS1 again and compare the checksums for the two subsystems again. This time, the checksums should not be equal.

```
[chksum1, chksum1_details] = ...
Simulink.SubSystem.getChecksum(SS1);
isequal(chksum1, chksum2)
ans =
    0
```

- 8 After you determine that the checksums are different, find out why. Simulink uses information, such as signal data types, some block parameter values, and block connectivity information, to compute the checksums. To determine why checksums are different, you compare the data used to compute the checksum values. You can get this information from the second value returned by `Simulink.SubSystem.getChecksum`, which is a structure array with four fields.

Look at the structure `chksum1_details`.

```
chksum1_details
```

```

chksum1_details =
    ContentsChecksum: [1x1 struct]
    InterfaceChecksum: [1x1 struct]
    ContentsChecksumItems: [221x1 struct]
    InterfaceChecksumItems: [91x1 struct]

```

ContentsChecksum and InterfaceChecksum are component checksums of the subsystem checksum. The remaining two fields ContentsChecksumItems and InterfaceChecksumItems contain the checksum details.

- 9** Determine whether a difference exists in the subsystem contents, interface, or both. For example:

```

isequal(chksum1_details.ContentsChecksum.Value,...
        chksum2_details.ContentsChecksum.Value)
ans =
    0
isequal(chksum1_details.InterfaceChecksum.Value,...
        chksum2_details.InterfaceChecksum.Value)
ans =
    0

```

In this case, differences exist in both the contents and interface.

- 10** Write a script like the following to find the differences.

```

idxForCDiffs=[];
for idx = 1:length(chksum1_details.ContentsChecksumItems)
    if (~strcmp(chksum1_details.ContentsChecksumItems(idx).Identifier, ...
               chksum2_details.ContentsChecksumItems(idx).Identifier))
        disp(['Identifiers different for contents item ', num2str(idx)]);
        idxForCDiffs=[idxForCDiffs, idx];
    end
    if (ischar(chksum1_details.ContentsChecksumItems(idx).Value))
        if (~strcmp(chksum1_details.ContentsChecksumItems(idx).Value, ...
                   chksum2_details.ContentsChecksumItems(idx).Value))
            disp(['String values different for contents item ', num2str(idx)]);
            idxForCDiffs=[idxForCDiffs, idx];
        end
    end
end

```

```
        if (isnumeric(chksum1_details.ContentsChecksumItems(idx).Value))
            if (chksum1_details.ContentsChecksumItems(idx).Value ~= ...
                chksum2_details.ContentsChecksumItems(idx).Value)
                disp(['Numeric values different for contents item ', num2str(idx)]);
                idxForCDiffs=[idxForCDiffs, idx];
            end
        end
    end
end

idxForIDiffs=[];
for idx = 1:length(chksum1_details.InterfaceChecksumItems)
    if (~strcmp(chksum1_details.InterfaceChecksumItems(idx).Identifier, ...
                chksum2_details.InterfaceChecksumItems(idx).Identifier))
        disp(['Identifiers different for interface item ', num2str(idx)]);
        idxForIDiffs=[idxForIDiffs, idx];
    end
end
if (ischar(chksum1_details.InterfaceChecksumItems(idx).Value))
    if (~strcmp(chksum1_details.InterfaceChecksumItems(idx).Value, ...
                chksum2_details.InterfaceChecksumItems(idx).Value))
        disp(['String values different for interface item ', num2str(idx)]);
        idxForIDiffs=[idxForIDiffs, idx];
    end
end
end
if (isnumeric(chksum1_details.InterfaceChecksumItems(idx).Value))
    if (chksum1_details.InterfaceChecksumItems(idx).Value ~= ...
        chksum2_details.InterfaceChecksumItems(idx).Value)
        disp(['Numeric values different for interface item ', num2str(idx)]);
        idxForIDiffs=[idxForIDiffs, idx];
    end
end
end
end
```

- 11** Run the script. The following example assumes you named the script `check_details`.

```
check_details
String values different for contents item 64
String values different for contents item 75
String values different for contents item 81
String values different for interface item 46
```

The results indicate that differences exist for index items 64, 75, and 81 in the subsystem contents and for item 46 in the subsystem interfaces.

- 12** Use the returned index values to get the handle , identifier, and value details for each difference found.

```

chksum1_details.ContentsChecksumItems(64)
ans =
    Handle: 'my_ssreuse/SS1/Lookup Table Output1'
    Identifier: 'CompiledPortAliasedThruDataType'
    Value: 'int8'
chksum2_details.ContentsChecksumItems(64)
ans =
    Handle: 'my_ssreuse/SS2/Lookup Table Output1'
    Identifier: 'CompiledPortAliasedThruDataType'
    Value: 'double'
chksum1_details.ContentsChecksumItems(75)
ans =
    Handle: 'my_ssreuse/SS1/Lookup Table'
    Identifier: 'RunTimeParameter{'OutputValues'}.DataType'
    Value: 'int8'
chksum2_details.ContentsChecksumItems(75)
ans =
    Handle: 'my_ssreuse/SS2/Lookup Table'
    Identifier: 'RunTimeParameter{'OutputValues'}.DataType'
    Value: 'double'
chksum1_details.ContentsChecksumItems(81)
ans =
    Handle: 'my_ssreuse/SS1/Lookup Table'
    Identifier: 'OutDataTypeMode'
    Value: 'int8'
chksum2_details.ContentsChecksumItems(81)
ans =
    Handle: 'my_ssreuse/SS2/Lookup Table'
    Identifier: 'OutDataTypeMode'
    Value: 'Same as input'
chksum1_details.InterfaceChecksumItems(46)
ans =
    Handle: 'my_ssreuse/SS1'
    Identifier: 'CanonicalParameter(1).DataType'

```

```
Value: 'int8'  
chksum2_details.InterfaceChecksumItems(46)  
ans =  
    Handle: 'my_ssreuse/SS2'  
    Identifier: 'CanonicalParameter(1).DataType'  
    Value: 'double'
```

As expected, the details identify the Lookup Table block and data type parameters as areas on which to focus for debugging a subsystem reuse issue.

- 13** Correct the problem by changing the output data type mode for the subsystems such that they match.

Generating Code and Executables from Subsystems

Real-Time Workshop can generate code and build an executable from any subsystem within a model. The code generation and build process uses the code generation and build parameters of the root model.

To generate code and build an executable from a subsystem,

- 1 Set up the desired code generation and build parameters in the Configuration Parameters dialog box, just as you would for code generation from a model.
- 2 Select the desired subsystem block.
- 3 Right-click the subsystem block and select **Build Subsystem** from the **Real-Time Workshop** submenu of the subsystem block's context menu.

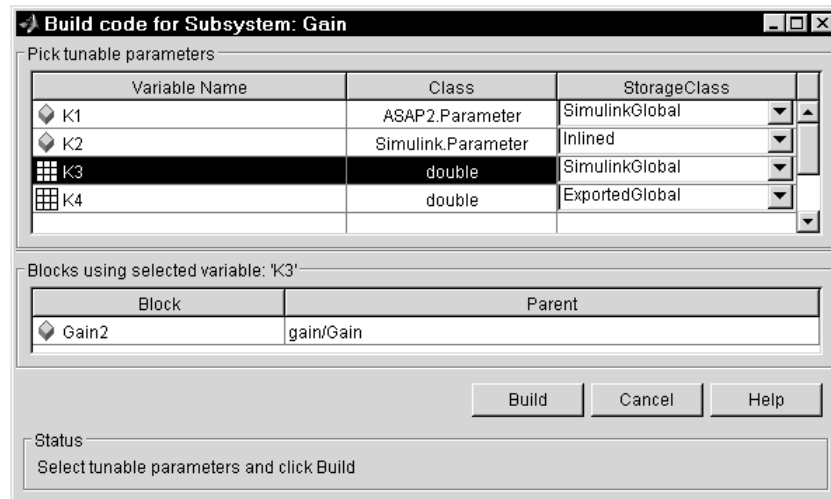
Note When you right-click build a subsystem that includes an Output block for which the signal specification **Specify properties via bus object** is selected, Real Time Workshop requires that you set the **Signal label mismatch** option on the **Diagnostics > Connectivity** pane of the Configuration Parameters dialog box for the parent model to error. You need to address any errors that occur by properly setting signal labels.

Alternatively, you can select **Build Subsystem** from the **Real-Time Workshop** submenu of the **Tools** menu. This menu item is enabled when a subsystem is selected in the current model.

Note If the model is operating in external mode when you select **Build Subsystem**, Real-Time Workshop automatically turns off external mode for the duration of the build, then restores external mode upon its completion.

- 4** The **Build Subsystem** window opens. This window displays a list of the subsystem parameters. The upper pane displays the name, class, and storage class of each variable (or data object) that is referenced as a block parameter in the subsystem. When you select a parameter in the upper pane, the lower pane shows all the blocks that reference the parameter and the parent system of each such block.

The **StorageClass** column contains a popup menu for each row. The menu lets you set the storage class of any parameter or inline the parameter. To inline a parameter, select the **Inline** option from the menu. To declare a parameter to be tunable, set the storage class to any value other than **Inline**.



In the previous figure, the parameter K2 is inlined, while the other parameters are tunable and have various storage classes.

See “Parameter Storage, Interfacing, and Tuning” on page 5-2 and “Simulink Data Objects and Code Generation” on page 5-46 for more information on tunable and inlined parameters and storage classes.

- 5** After selecting tunable parameters, click the **Build** button. This initiates the code generation and build process.

- 6 The build process displays status messages in the MATLAB Command Window. When the build completes, the generated executable is in your working directory. The name of the generated executable is *subsystem.exe* (PC) or *subsystem* (UNIX), where *subsystem* is the name of the source subsystem block.

The generated code is in a build subdirectory, named *subsystem_target_rtw*, where *subsystem* is the name of the source subsystem block and *target* is the name of the target configuration.

When you generate code for a subsystem, you can generate an S-function by selecting **Tools > Real-Time Workshop > Generate S-function**, or you can use a right-click subsystem build. See “Automated S-Function Generation” on page 11-15 and “Automatic S-Function Wrapper Generation” for more details.

Generating Code for Model Referencing

In this section...

- “Introduction” on page 4-26
- “Overview of Referenced Model Code Generation” on page 4-26
- “Project Directory Structure for Model Reference Targets” on page 4-28
- “Building Model Reference Targets” on page 4-28
- “Real-Time Workshop Model Referencing Requirements” on page 4-29
- “Storage Classes for Signals Used with Model Blocks” on page 4-36
- “Inherited Sample Time for Referenced Models” on page 4-40
- “Reusable Code and Referenced Models” on page 4-41
- “Customizing the Library File Suffix, Including the File Type Extension” on page 4-45
- “Real-Time Workshop Model Referencing Limitations” on page 4-45

Introduction

This section describes model referencing considerations that apply specifically to code generation by Real-Time Workshop® with GRT and ERT system targets. This section assumes that you understand referenced models and their terminology and requirements, as described in “Referencing a Model”. This section does not repeat information that appears in that chapter.

Overview of Referenced Model Code Generation

When generating code for a referenced model hierarchy, Real-Time Workshop generates a stand-alone executable for the top model, and a library module called a *Real-Time Workshop target* for each referenced model. When the code executes, the top executable invokes the Real-Time Workshop targets as needed to compute the referenced model outputs. Real-Time Workshop targets are often called *model reference targets*.

Be careful not to confuse a Real-Time Workshop target (Model Reference target) with a *simulation target*, which computes the outputs of a referenced model that executes in Accelerator mode; a *hardware target*, which is a

platform for which Real-Time Workshop generates code; or a *system target*, which is a file that tells Real-Time Workshop how to generate code for particular purpose.

Real-Time Workshop places the code for the top model of a hierarchy in the current working directory, and the code for submodels in a directory named `s1prj` within the current working directory. Subdirectories in `s1prj` provide separate places for different types of files. See “Project Directory Structure for Model Reference Targets” on page 4-28 for details.

By default, Real-Time Workshop uses *incremental code generation*. When generating code, it compares the date, and optionally, the structure of referenced model files with the generated code files to determine whether it is necessary to regenerate model reference targets. You can also force or prevent code generation by using a diagnostic setting **Configuration Parameters > Model Referencing > Rebuild** options.

In addition to incremental code generation, Real-Time Workshop uses *incremental loading*. The code for a referenced model is not loaded into memory until the code for its parent model executes and needs the outputs of the referenced model. Real-Time Workshop then loads the referenced model target and executes. Once loaded, the target remains in memory until it is no longer needed.

Most code generation considerations are the same whether or not a model includes any referenced models: Real-Time Workshop handles the details automatically insofar as possible. This chapter describes topics that you may need to consider when generating code for a model reference hierarchy.

Custom targets must declare themselves to be model reference compliant if they need to support Model blocks. See “Supporting Model Referencing” for details.

Referenced Model Code Generation Tutorial

You can get hands-on experience with creating referenced models and generating code for them by working through the model reference tutorial. See “Generating Code for a Referenced Model”.

Project Directory Structure for Model Reference Targets

Code for models referenced by using Model blocks is generated in project directories within the current working directory. The top-level project directory is always named `/slprj`. The next level within `slprj` contains parallel build area subdirectories.

The following table lists principal project directories and files. In the paths listed, *model* is the name of the model being used as a referenced model, and *target* is the Real-Time Workshop target acronym (for example, `grt`, `ert`, `rslim`, and so on).

Directories and Files	Description
<code>slprj/sim/model/</code>	Model reference simulation target files
<code>slprj/sim/model/tmwinternal</code>	MAT-files used during code generation
<code>slprj/target/model</code>	Model reference Real-Time Workshop target files
<code>slprj/target/model/tmwinternal</code>	MAT-files used during code generation of model reference Real-Time Workshop target and stand-alone code generation
<code>slprj/sl_proj.tmw</code> (marker file)	<code>slprj</code> marker file
<code>slprj/target/_sharedutils</code>	Utility functions for Real-Time Workshop targets, shared across models
<code>slprj/sim/_sharedutils</code>	Utility functions for simulation targets, shared across models

If you are building code for more than one referenced model within the same working directory, model reference files for all such models are added to the existing `slprj` directory.

Building Model Reference Targets

By default, Simulink rebuilds simulation targets as needed before Real-Time Workshop generates model reference targets. You can change the rebuild criteria or specify that Simulink always or never rebuilds targets. See “Rebuild options” for details.

Real-Time Workshop generates a model reference target directly from the Simulink model. Real-Time Workshop automatically generates or regenerates model reference targets as needed.

You can command Simulink and Real-Time Workshop to generate a simulation target for an Accelerator mode referenced model, and a model reference target for any referenced model, by executing the `slbuild` command with appropriate arguments in the MATLAB Command Window.

Real-Time Workshop generates only one model reference target for all instances of a referenced model. See “Reusable Code and Referenced Models” on page 4-41 for details.

Reducing Change Checking Time

You can reduce the time that Simulink and Real-Time Workshop spend checking whether any or all simulation targets and model reference targets need to be rebuilt by setting configuration parameter values as follows:

- In the top model, set **Configuration Parameters > Model Referencing > Rebuild options** to If any changes in known dependencies detected. (See “Rebuild options”.)
- In all referenced models throughout the hierarchy, set **Configuration Parameters > Diagnostics > Data Validity > Signal resolution** to Explicit only. (See “Signal resolution”.)

These parameter values exist in a referenced model’s configuration set, not in the individual Model block, so setting either value for any instance of a referenced model sets it for all instances of that model.

Real-Time Workshop Model Referencing Requirements

A model reference hierarchy must satisfy various Real-Time Workshop requirements, as described in this section. In addition to these requirements, a model referencing hierarchy to be processed by Real-Time Workshop must satisfy:

- The Simulink requirements listed in:

- “Configuration Requirements for All Referenced Model Simulation”
- “Model Structure Requirements”
- The Simulink limitations listed in “Limitations on All Model Referencing”
- The Real-Time Workshop limitations listed in “Real-Time Workshop Model Referencing Limitations” on page 4-45

Configuration Parameter Requirements

A referenced model uses a configuration set in the same way that any other model does, as described in “Configuration Sets”. By default, every model in a hierarchy has its own configuration set, which it uses in the same way that it would if the model executed independently.

Because each model can have its own configuration set, configuration parameter values can be different in different models. Furthermore, some parameter values are intrinsically incompatible with model referencing. Real-Time Workshop’s response to an inconsistent or unusable configuration parameter depends on the parameter:

- Where an inconsistency has no significance, or a trivial resolution exists that carries no risk, Real-Time Workshop ignores or resolves the inconsistency without posting a warning.
- Where a nontrivial and possibly acceptable solution exists, Real-Time Workshop resolves the conflict silently; resolves it with a warning; or generates an error. See “Model configuration mismatch” for details.
- Where no acceptable resolution is possible, Real-Time Workshop generates an error. You must then change some or all parameter values to eliminate the problem.

When a model reference hierarchy contains many submodels that have incompatible parameter values, or a changed parameter value must propagate to many submodels, manually eliminating all configuration parameter incompatibilities can be tedious. You can control or eliminate such overhead by using configuration references to assign an externally-stored configuration set to multiple models. See “Referencing Configuration Sets” for details.

The following tables list configuration parameters that can cause problems if set in certain ways, or if set differently in a referenced model than in a

parent model. Where possible, Real-Time Workshop resolves violations of these requirements automatically, but most cases require changes to the parameters in some or all models.

For general information about setting configuration parameters for code generation, see “Adjusting Simulation Configuration Parameters for Code Generation” on page 2-23.

Configuration Requirements for Model Referencing with All System Targets

Dialog Box Pane	Option	Requirement
Solver	Start time	Some system targets require the start time of all models to be zero.
Hardware Implementation	Emulation hardware options	All values must be the same for top and referenced models.
Real-Time Workshop	System target file	Must be the same for top and referenced models.
	Language	Must be the same for top and referenced models.
	Generate code only	Must be the same for top and referenced models.

Configuration Requirements for Model Referencing with All System Targets (Continued)

Dialog Box Pane	Option		Requirement
Symbols	Maximum identifier length		Cannot be longer for a referenced model than for its parent model.
Interface	Target function library		Must be the same for top and referenced models.
	Data exchange Interface	C-API	The C-API Signals and Parameters check boxes must be the same for top and referenced models.
		ASAP2	Can be on or off in a top model, but must be off in a referenced model. If it is not, Real-Time Workshop temporarily sets it to off during code generation.

Configuration Requirements for Model Referencing with ERT System Targets

Dialog Box Pane	Option	Requirement
Real-Time Workshop	Ignore custom storage classes	Must be the same for top and referenced models.
Symbols	Global variables Global types Subsystem methods Local temporary variables Constant macros	\$R token must appear.
	Signal naming	Must be the same for top and referenced models.
	M-function	If specified, must be the same for top and referenced models.
	Parameter naming	Must be the same for top and referenced models.
	#define naming	Must be the same for top and referenced models.

Configuration Requirements for Model Referencing with ERT System Targets (Continued)

Dialog Box Pane	Option	Requirement
Interface	Support floating- point numbers	If off for top model, must be off for referenced models.
	Support non-finite numbers	If off for top model, must be off for referenced models.
	Support complex numbers	If off for top model, must be off for referenced models.
	Terminate function required	Must be the same for top and referenced models.
	Suppress error status in real-time model	If on for top model, must be on for referenced models.
Templates	Target operating system	Must be the same for top and referenced models.

Configuration Requirements for Model Referencing with ERT System Targets (Continued)

Dialog Box Pane	Option	Requirement
Data Placement	Module Naming	Must be the same for top and referenced models.
	Module Name (if specified)	If set, must be the same for top and referenced models.
	Signal display level	Must be the same for top and referenced models.
	Parameter tune level	Must be the same for top and referenced models.

Naming Requirements

Within a model that uses model referencing, there can be no collisions between the names of the constituent models. When you generate code from a model that uses model referencing, the **Maximum identifier length** parameter must be large enough to accommodate the root model name and the name mangling string (if needed). A code generation error occurs if **Maximum identifier length** is not large enough.

When a name conflict occurs between a symbol within the scope of a higher-level model and a symbol within the scope of a referenced model, the symbol from the referenced model is preserved. Name mangling is performed on the symbol from the higher-level model.

Embedded Coder Naming Requirements. Real-Time Workshop Embedded Coder provides a **Symbol format** field that lets you control the formatting of generated symbols in much greater detail. When generating code with an ERT target from a model that uses model referencing:

- The \$R token must be included in the **Identifier format control** parameter specifications (in addition to the \$M token).
- The **Maximum identifier length** must be large enough to accommodate full expansions of the \$R and \$M tokens.

See “Real-Time Workshop Pane: Symbols” and “Code Generation Options and Optimizations” for more information.

Custom Target Requirements

A custom target must meet various requirements in order to support model referencing. See “Supporting Model Referencing” for details.

Storage Classes for Signals Used with Model Blocks

Models containing Model blocks can use signals of storage class Auto without restriction. However, when you declare signals to be global, you must be aware of how the signal data will be handled.

A global signal is a signal with a storage class other than Auto:

- ExportedGlobal
- ImportedExtern
- ImportedExternPointer
- Custom

The above are distinct from SimulinkGlobal signals, which are treated as test points with Auto storage class.

Global signals are declared, defined, and used as follows:

- An extern declaration is generated by all models that use any given global signal.

As a result, if a signal crosses a Model block boundary, the top model and the referenced model both generate extern declarations for the signal.

- For any exported signal, the top mode is responsible for defining (allocating memory for) the signal, whether or not the top model itself uses the signal.
- All global signals used by a referenced model are accessed directly (as global memory). They are not passed as arguments to the functions that are generated for the referenced models.

Custom storage classes also follow the above rules. However, certain custom storage classes are not currently supported for use with model reference. See “Custom Storage Class Limitations” for details.

Storage Classes for Parameters Used with Model Blocks

All storage classes are supported for both simulation and code generation, and all except Auto are tunable. The supported storage classes thus include

- SimulinkGlobal
- ExportedGlobal
- ImportedExtern
- ImportedExternPointer
- Custom

Note the following restrictions on parameters in referenced models:

- Tunable parameters are not supported for noninlined S-functions.
- Tunable parameters set using the Model Parameter Configuration dialog box are ignored.

Note the following considerations concerning how global tunable parameters are declared, defined, and used in code generated for targets:

- A global tunable parameter is a parameter in the base workspace with a storage class other than Auto.
- An extern declaration is generated by all models that use any given parameter.

- If a parameter is exported, the top model is responsible for defining (allocating memory for) the parameter (whether it uses the parameter or not).
- All global parameters are accessed directly (as global memory). They are not passed as arguments to any of the functions that are generated for any of the referenced models.
- Symbols for SimulinkGlobal parameters in referenced models are generated using unstructured variables (`rtP_xxx`) instead of being written into the `model_P` structure. This is so that each referenced model can be compiled independently.

Certain custom storage classes for parameters are not currently supported for model reference. See “Custom Storage Class Limitations” for details.

Parameters used as Model block arguments must be defined in the referenced model’s workspace. See “Parameterizing Model References” in the Simulink documentation for specific details.

Effects of Signal Name Mismatches

Within a parent model, the name and storage class for a signal entering or leaving a Model block might not match those of the signal attached to the root inport or outport within that referenced model. Because referenced models are compiled independently without regard to any parent model, they cannot adapt to all possible variations in how parent models label and store signals.

Real-Time Workshop accepts all cases where input and output signals in a referenced model have Auto storage class. When such signals are test pointed or are global, as described above, certain restrictions apply. The following table describes how mismatches in signal labels and storage classes between parent and referenced models are handled:

Relationships of Signals and Storage Classes Between Parent and Referenced Models

Referenced Model	Parent Model	Signal Passing Method	Signal Mismatch Checking
Auto	Any	Function argument	None
SimulinkGlobal or resolved to Signal Object	Any	Function argument	Label Mismatch Diagnostic (none / warning / error)
Global	Auto or SimulinkGlobal	Global variable	Label Mismatch Diagnostic (none / warning / error)
Global	Global	Global variable	Labels and storage classes must be identical (else error)

To summarize, the following signal resolution rules apply to code generation:

- If the storage class of a root input or output signal in a referenced model is Auto (or is SimulinkGlobal), the signal is passed as a function argument.
 - When such a signal is SimulinkGlobal or resolves to a Simulink.Signal object, the **Signal Mismatch** diagnostic is applied.
- If a root input or output signal in a referenced model is global, it is communicated by using direct memory access (global variable). In addition,
 - If the corresponding signal in the parent model is also global, the names and storage classes must match exactly.
 - If the corresponding signal in the parent model is not global, the **Signal Mismatch** diagnostic is applied.

You can set the **Signal Mismatch** diagnostic to error, warning, or none in the **Configuration Parameters > Diagnostics > Connectivity** dialog.

Inherited Sample Time for Referenced Models

See “Inheriting Sample Times” for information about Model block sample time inheritance in Simulink. In generated code, you can control inheriting sample time by using `ssSetModelReferenceSampleTimeInheritanceRule` in different ways:

- An S-function that precludes inheritance: If the sample time is used in the S-function’s run-time algorithm, then the S-function precludes a model from inheriting a sample time. For example, consider the following `mdlOutputs` code:

```
static void mdlOutputs(SimStruct *S, int_T tid)
{
    const real_T *u = (const real_T*)
        ssGetInputPortSignal(S,0);
    real_T      *y = ssGetOutputPortSignal(S,0);
    y[0] = ssGetSampleTime(S,tid) * u[0];
}
```

This `mdlOutputs` code uses the sample time in its algorithm, and the S-function therefore should specify

```
ssSetModelReferenceSampleTimeInheritanceRule
(S, DISALLOW_SAMPLE_TIME_INHERITANCE);
```

- An S-function that does not preclude Inheritance: If the sample time is only used for determining whether the S-function has a sample hit, then it does not preclude the model from inheriting a sample time. For example, consider the `mdlOutputs` code from the S-function demo `sfun_multirate.c`:

```
static void mdlOutputs(SimStruct *S, int_T tid)
{
    InputRealPtrsType enablePtrs;
    int                *enabled = ssGetIWork(S);

    if (ssGetInputPortSampleTime
        (S,ENABLE_IPORT)==CONTINUOUS_SAMPLE_TIME &&
        ssGetInputPortOffsetTime(S,ENABLE_IPORT)==0.0) {
        if (ssIsMajorTimeStep(S) &&
            ssIsContinuousTask(S,tid)) {
```



```

        enablePtrs =
        ssGetInputPortRealSignalPtrs(S,ENABLE_IPORT);
        *enabled = (*enablePtrs[0] > 0.0);
    }
} else {
    int enableTid =
    ssGetInputPortSampleTimeIndex(S,ENABLE_IPORT);
    if (ssIsSampleHit(S, enableTid, tid)) {
        enablePtrs =
        ssGetInputPortRealSignalPtrs(S,ENABLE_IPORT);
        *enabled = (*enablePtrs[0] > 0.0);
    }
}

if (*enabled) {
    InputRealPtrsType uPtrs =
    ssGetInputPortRealSignalPtrs(S,SIGNAL_IPORT);
    real_T          signal = *uPtrs[0];
    int             i;

    for (i = 0; i < NOUTPUTS; i++) {
        if (ssIsSampleHit(S,
            ssGetOutputPortSampleTimeIndex(S,i), tid)) {
            real_T *y = ssGetOutputPortRealSignal(S,i);
            *y = signal;
        }
    }
}
} /* end mdlOutputs */

```

The above code uses the sample times of the block, but only for determining whether there is a hit. Therefore, this S-function should set

```

ssSetModelReferenceSampleTimeInheritanceRule
(S, USE_DEFAULT_FOR_DISCRETE_INHERITANCE);

```

Reusable Code and Referenced Models

Models that employ model referencing might require special treatment when generating and using reusable code. The following sections identify general restrictions and discuss how reusable functions with inputs or outputs

connected to a referenced model's root Inport or Outport blocks can affect code reuse.

General Considerations

You can generate code for subsystems that contain referenced models using the same procedures and options described in “Nonvirtual Subsystem Code Generation” on page 4-2. However, the following restrictions apply to such builds:

- ERT S-functions do not support subsystems that contain a continuous sample time.
- The Real-Time Workshop S-function target is not supported.
- The Tunable parameters table (set by using the Model Parameter Configuration dialog box) is ignored; to make parameters tunable, you must define them as Simulink parameter objects in the base workspace.
- All other parameters are inlined into the generated code and S-function.

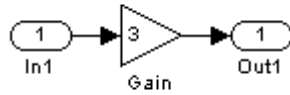
Note You can generate subsystem code using any target configuration available in the System Target File Browser. However, if the S-function target is selected, **Build Subsystem** behaves identically to **Generate S-function**. (See “Automated S-Function Generation” on page 11-15.)

Code Reuse and Model Blocks with Root Inport or Outport Blocks

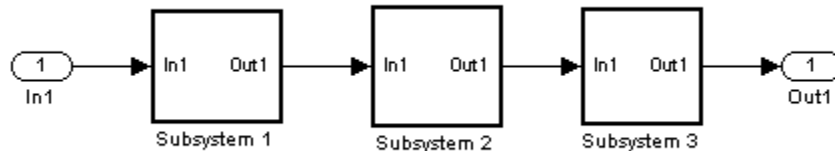
Reusable functions with inputs or outputs connected to a referenced model's root Inport or Outport block can affect code reuse. This means that code for certain atomic subsystems cannot be reused in a model reference context the same way it is reused in a standalone model.

For example, suppose you create the following subsystem and make the following changes to the subsystem's block parameters:

- Select **Treat as an atomic unit**
- Set **Real-Time Workshop system code** to Reusable function



Suppose you then create the following model, which includes three instances of the preceding subsystem.



With the **Inline parameters** option enabled in this stand-alone model, Real-Time Workshop can optimize the code by generating a single copy of the function for the reused subsystem, as shown below.

```
void reuse_subsys1_Subsystem1(
    real_T rtu_0,
    rtB_reuse_subsys1_Subsystem1 *localB)
{
    /* Gain: '<S1>/Gain' */
    localB->Gain_k = rtu_0 * 3.0;
}
```

When generated as code for a Model block (into an slprj project directory), the subsystems have three different function signatures:

```
/* Output and update for atomic system: '<Root>/Subsystem1' */
void reuse_subsys1_Subsystem1(const real_T *rtu_0,
    rtB_reuse_subsys1_Subsystem1
    *localB)
{
    /* Gain: '<S1>/Gain' */
```

```

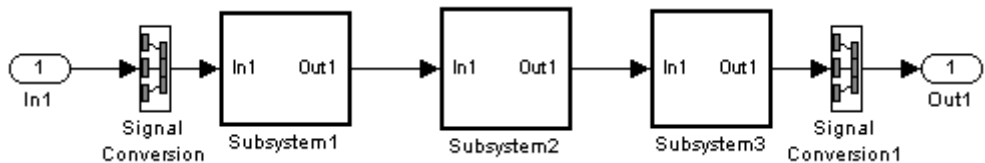
    localB->Gain_w = (*rtu_0) * 3.0;
}

/* Output and update for atomic system: '<Root>/Subsystem2' */
void reuse_subsys1_Subsystem2(real_T rtu_In1,
rtB_reuse_subsys1_Subsystem2
 *localB)
{
    /* Gain: '<S2>/Gain' */
    localB->Gain_y = rtu_In1 * 3.0;
}

/* Output and update for atomic system: '<Root>/Subsystem3' */
void reuse_subsys1_Subsystem3(real_T rtu_In1, real_T *rtty_0)
{
    /* Gain: '<S3>/Gain' */
    (*rtty_0) = rtu_In1 * 3.0;
}

```

One way to make all the function signatures the same — and therefore assure code reuse — is to insert Signal Conversion blocks. Place one between the Inport and Subsystem1 and another between Subsystem3 and the Output of the referenced model.



The result is a single reusable function:

```

void reuse_subsys2_Subsystem1(real_T rtu_In1,
                             rtB_reuse_subsys2_Subsystem1 *localB)
{
    /* Gain: '<S1>/Gain' */
    localB->Gain_g = rtu_In1 * 3.0;
}

```

You can achieve the same result (reusable code) with only one Signal Conversion block. You can omit the Signal Conversion block connected to the Inport block if you select the **Pass scalar root inputs by value** check box at the bottom of the **Model Referencing** pane of the Configuration Parameters dialog box. When you do this, you still need to insert a Signal Conversion block before the Outport block.

Customizing the Library File Suffix, Including the File Type Extension

You can control the library file suffix, including the file type extension, that Real-Time Workshop uses to name generated model reference libraries by specifying the string for the suffix with the model configuration parameter `TargetLibSuffix`. The string must include a period (.). If you do not set this parameter,

On a...	Real-Time Workshop Names the Libraries...
Windows system	<code>model_rtwlib.lib</code>
UNIX system	<code>model_rtwlib.a</code>

Real-Time Workshop Model Referencing Limitations

The following Real-Time Workshop limitations apply to model referencing. In addition to these limitations, a model reference hierarchy used for code generation must satisfy:

- The Simulink requirements listed in:
 - “Configuration Requirements for All Referenced Model Simulation”
 - “Model Structure Requirements”
- The Simulink limitations listed in “Simulink Model Referencing Limitations”.
- The Real-Time Workshop requirements applicable to the code generation target, as listed in “Configuration Parameter Requirements” on page 4-30.

Customization Limitations

- Real-Time Workshop ignores custom code settings in the **Configuration Parameter** dialog box and custom code blocks when generating code for a referenced model.
- Some restrictions exist on grouped custom storage classes in referenced models. See “Custom Storage Class Limitations” for details.
- Referenced models do not support custom storage classes if the parent model has inline parameters off.
- This release does not include Stateflow target custom code in simulation targets generated for referenced models.
- Data type replacement is not supported for simulation target code generation for referenced models.
- Simulation targets do not include Stateflow target custom code.

Data Logging Limitations

- To Workspace blocks, Scope blocks, and all types of runtime display, such as the display of port values and signal values, are ignored when Real-Time Workshop generates code for a referenced model. The resulting code is the same as if the constructs did not exist.
- Code generated for referenced models cannot log data to MAT-files. If data logging is enabled for a referenced model, Real-Time Workshop disables the option before code generation and re-enables it afterwards.

Reusability Limitations

A model that has any of the following properties can be referenced at most once in a model reference hierarchy for which Real-Time Workshop generates code. If more than one instance exists, trying to generate code for the hierarchy causes an error.

- SL_REUSE_BLKER_ACCEL_CALL_IN_ENGINE
- SL_REUSE_BLKER_DEBUG_DISABLE_REUSE
- SL_REUSE_BLKER_FORCED_NONINLINE

- `SL_REUSE_BLKER_HAS_UNSUPP_SFCN`
- `SL_REUSE_BLKER_HAS_WIDE_FCN_CALL`
- `SL_REUSE_BLKER_MARKED_FUNCTION`
- `SL_REUSE_BLKER_MDLREF_GLOBAL_DWORK`
- `SL_REUSE_BLKER_MDLREF_GLOBAL_SIGNAL`
- `SL_REUSE_BLKER_MDLREF_SINGLE_INSTANCE`
- `SL_REUSE_BLKER_STATE_PORT_CROSS_BOUNDARY`

S-Function Limitations

- If a referenced model contains an S-function that should be inlined using a Target Language Compiler file, the S-function must use the `ssSetOptions` macro to set the `SS_OPTION_USE_TLC_WITH_ACCELERATOR` option in its `mdlInitializeSizes` method. The simulation target will not inline the S-function unless this flag is set.
- Real-Time Workshop cannot generate code for a referenced model that includes noninlined S-functions in either the model itself or any subordinate referenced mode.
- A referenced model cannot use noninlined S-functions generated by Real-Time Workshop.
- The Real-Time Workshop S-function target does not support model referencing.

Simulink Tool Limitations

- Simulink tools that require access to a model's internal data or configuration (including the Model Coverage tool, the Report Generator, the Simulink Debugger, and the Simulink Profiler) have no effect on code generated by Real-Time Workshop for a referenced model, or on the execution of that code. Specifications made and actions taken by such tools are ignored and effectively do not exist.

Subsystem Limitations

- If a subsystem contains Model blocks, you cannot build a subsystem module by right-clicking the subsystem (or by using **Tools > Real-Time Workshop > Build subsystem**) unless the model is configured to use an ERT target.
- If you generate code for an atomic subsystem as a reusable function, inputs or outputs that connect the subsystem to a referenced model can affect code reuse, as described in “Reusable Code and Referenced Models” on page 4-41.

Target Limitations

- Real-Time Workshop `grt_malloc` targets do not support model reference.
- The Real-Time Workshop S-function target does not support model referencing.

Other Limitations

- Errors or unexpected behavior can occur if a Model block is part of a cycle, the Model block is a direct feedthrough block, and an algebraic loop results. See “Model Blocks and Direct Feedthrough” for details.
- The **External mode** option is not supported. If it is enabled, it is ignored during code generation.

Sharing Utility Functions

In this section...

- “Introduction” on page 4-49
- “Controlling Shared Utility Generation” on page 4-49
- “rtwtypes.h and Shared Utilities” on page 4-50
- “Incremental Shared Utility Generation and Compilation” on page 4-51
- “Shared Utility Checksum” on page 4-51
- “Shared Fixed-Point Utilities” on page 4-53

Introduction

Blocks in a model can require common functionality to implement their algorithm. In many cases, it is most efficient to modularize this functionality into standalone support or helper functions, rather than inlining the code for the functionality for each block instance.

Typically, functions that can have multiple callers are packaged into a library. Traditionally, such functions are defined statically, that is, the function source code exists in a file before you use Real-Time Workshop to generate code for your model. This is the case, for example, with the Real-Time Workshop directory `libsrc`, which contains many statically defined functions.

In other cases, several model- and block-specific properties can affect which functions are needed and their behavior. Additionally, these properties can affect type definitions (for example, `typedef`) in shared utility header files. Since there are many possible combinations of properties that determine unique behavior, it is not practical to statically define all possible function files before code generation. Instead, you can use the Real-Time Workshop shared utility mechanism, which generates any needed support functions during code generation process.

Controlling Shared Utility Generation

You control the shared utility generation mechanism with the **Utility function generation** option on the **Real-Time Workshop > Interface**

pane of the Configuration Parameters dialog box. By default, the option is set to Auto. For this setting, if the model being built does not include any Model blocks, Real-Time Workshop places any code required for fixed-point and other utilities in one of the following:

- The `model.c` or `model.cpp` file
- In a separate file in the Real-Time Workshop build directory (for example, `vdp_grt_rtw`)

Thus, the code is specific to the model.

If a model does contain Model blocks, Real-Time Workshop creates and uses a shared utilities directory within `slprj`. Model reference builds require the use of shared utilities. The naming convention for shared utility directories is `slprj/target/_sharedutils`, where `target` is `sim` for simulations with Model blocks or the name of the system target file for Real-Time Workshop target builds. Some examples follow:

```
slprj/sim/_sharedutils      % directory used with simulation
slprj/grt/_sharedutils      % directory used with grt.tlc STF
slprj/ert/_sharedutils      % directory used with ert.tlc STF
slprj/mytarget/_sharedutils % directory used with mytarget.tlc STF
```

To force a model build to use the `slprj` directory for shared utility generation, even when the current model contains no Model blocks, set the **Utility function generation** option to `Shared location`. This forces Real-Time Workshop to place utilities under the `slprj` directory rather than in the normal Real-Time Workshop build directory. This setting is useful when you are manually combining code from several models, as it prevents symbol collisions between the models.

rtwtypes.h and Shared Utilities

The generated header file `rtwtypes.h` provides necessary defines, enumerations, and so on. The location of this file is controlled by whether the build process is using the shared utilities directory. Typically, Real-Time Workshop places `rtwtypes.h` in the standard build directory, `model_target_rtw`. However, if a shared directory is required, Real-Time Workshop places `rtwtypes.h` in `slprj/target/_sharedutils`.

Incremental Shared Utility Generation and Compilation

As explained in “Controlling Shared Utility Generation” on page 4-49, you can specify that C source files, which contain function definitions, and header files, which contain macro definitions, be generated in a shared utilities directory. For the purpose of this discussion, the term functions means functions and macros.

A shared function can be used by blocks within the same model and by blocks in different models when using model reference or when building multiple standalone models from the same start build directory. However, Real-Time Workshop generates the code for a given function only once for the block that first triggers code generation. As Real-Time Workshop determines the need to generate function code for subsequent blocks, it performs a file existence check. If the file exists, the function is not regenerated. Thus, the shared utility function mechanism requires that a given function and file name represent the same functional behavior regardless of which block or model generates the function. To satisfy this requirement:

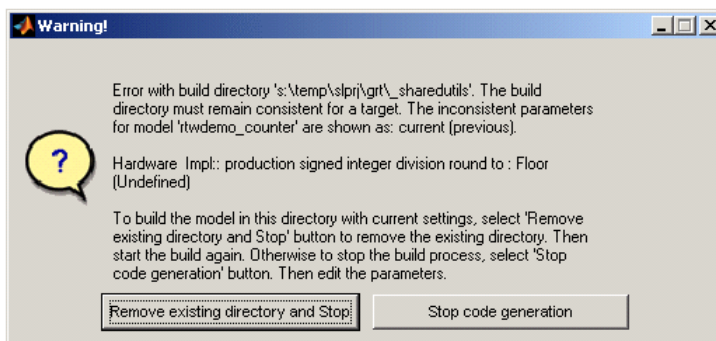
- Model properties that affect function behavior are included in a shared utility checksum or affect the function and file name.
- Block properties that affect the function behavior also affect the function and file name.

During compilation, makefile rules for the shared utilities directory are configured to compile only new C files, and incrementally archive the object file into the shared utility library, `rtwshared.lib` or `rtwshared.a`. Thus, incremental compilation is also done.

Shared Utility Checksum

As explained in “Incremental Shared Utility Generation and Compilation” on page 4-51, Real-Time Workshop uses the shared utilities directory when you explicitly configure a model to use the shared location or the model contains Model blocks. During the code generation process, if relative to the current directory, the configuration file `slprj/target/_sharedutils/checksummap.mat` exists, Real-Time Workshop reads that file and ensures that the current model being built has identical settings for the required model properties. If mismatches occur between the

properties defined in `checksummap.mat` and the current model properties, a Warning dialog appears.



The following table lists properties that must match for the shared utility checksum.

Category	Properties
Hardware Implementation configuration properties	<code>get_param(bdroot, 'TargetShiftRightIntArith')</code> <code>get_param(bdroot, 'TargetEndianness')</code> <code>get_param(bdroot, 'ProdEndianness')</code> <code>get_param(bdroot, 'TargetBitPerChar')</code> <code>get_param(bdroot, 'TargetBitPerShort')</code> <code>get_param(bdroot, 'TargetBitPerInt')</code> <code>get_param(bdroot, 'TargetBitPerLong')</code> <code>get_param(bdroot, 'ProdHWWordLengths')</code> <code>get_param(bdroot, 'TargetWordSize')</code> <code>get_param(bdroot, 'ProdWordSize')</code> <code>get_param(bdroot, 'TargetHWDeviceType')</code> <code>get_param(bdroot, 'ProdHWDeviceType')</code> <code>get_param(bdroot, 'TargetIntDivRoundTo')</code> <code>get_param(bdroot, 'ProdIntDivRoundTo')</code>
Additional configuration properties	<code>get_param(bdroot, 'TargetLibSuffix')</code> <code>get_param(bdroot, 'TargetLang')</code> <code>get_param(bdroot, 'TemplateMakefile')</code>

Category	Properties
ERT target properties	get_param(bdroot, 'PurelyIntegerCode') get_param(bdroot, 'SupportNonInlinedSFcns')
Platform property	Return value of the computer command

Shared Fixed-Point Utilities

An important set of generated functions that are placed in the shared utility directory are the fixed-point support functions. Based on model and block properties, there are many possible versions of fixed-point utilities functions that make it impractical to provide a complete set as static files. Generating only the required fixed-point utility functions during the code generation process is an efficient alternative.

The shared utility checksum mechanism ensures that several critical properties are identical for all models that use the shared utilities. For the fixed-point functions, there are additional properties that affect function behavior. These properties are coded into the functions and file names to ensure requirements are maintained. The additional properties include

Category	Function/Property
Block properties	<ul style="list-style-type: none"> • Fixed-point operation being performed by the block • Fixed-point data type and scaling (Slope, Bias) of function inputs and outputs • Overflow handling mode (Saturation, Wrap) • Rounding Mode (Floor, Ceil, Zero)
Model properties	get_param(bdroot, 'NoFixptDivByZeroProtection')

The naming convention for the fixed-point utilities is based on the properties as follows:

```
operation + [zero protection] + output data type + output bits +
[input1 data] + input1 bits + [input2 data type + input2 bits] +
[shift direction] + [saturate mode] + [round mode]
```

Below are examples of generated fixed-point utility files, the function or macro names in the file are identical to the file name without the extension.

```

FIX2FIX_U12_U16.c
FIX2FIX_S9_S9_SR99.c
ACCUM_POS_S30_S30.h
MUL_S30_S30_S16.h
div_nzp_s16s32_floor.c
div_s32_sat_floor.c

```

For these examples, the respective fields correspond as follows:

Operation	FIX2FIX	FIX2FIX	ACCUM_POS	MUL	div	div
Zero protection	NULL	NULL	NULL	NULL	_nzp	NULL
Output data type	_U	_S	_S	_S	_s	_s
Output bits	12	9	30	30	16	32
Input data type	_U	_S	_S	_S [and _S]	s	NULL
Input bits	16	9	30	30 [and 16]	32	NULL
Shift direction	NULL	SR99	NULL	NULL	NULL	NULL
Saturate mode	NULL	NULL	NULL	NULL	NULL	_sat
Round mode	NULL	NULL	NULL	NULL	_floor	_floor

Note For the ACCUM_POS example, the output variable is also used as one of the input variables. Therefore, only the output and second input is contained in the file and macro name. For the second div example, both inputs and the output have identical data type and bits. Therefore, only the output is included in the file and function name.

Supporting Shared Utility Directories in the Build Process

The shared utility directories (`slprj/target/_sharedutils`) typically store generated utility code that is common to a top-level model and the models it references. You can also force the build process to use a shared utilities directory for a standalone model. See “Sharing Utility Functions” on page 4-49 for details.

If you want your target to support compilation of code generated in the shared utilities directory, several updates to your template makefile (TMF) are required. Support for the shared utilities directory is a necessary, but not sufficient, condition for supporting model reference builds. See “Supporting Model Referencing” to learn about additional updates that are needed for supporting model reference builds.

The exact syntax of the changes can vary due to differences in the make utility and compiler/archive tools used by your target. The examples below are based on the GNU make utility. You can find the following updated TMF examples for GNU and Microsoft Visual C make utilities in the GRT and ERT target directories:

- GRT: `matlabroot/rtw/c/grt/`
 - `grt_lcc.tmf`
 - `grt_vc.tmf`
 - `grt_unix.tmf`
- ERT: `matlabroot/rtw/c/ert/`
 - `ert_lcc.tmf`
 - `ert_vc.tmf`
 - `ert_unix.tmf`

Use the GRT or ERT examples as a guide to the location, within the TMF, of the changes and additions described below.

Note The ERT-based TMFs contain extra code to handle generation of ERT S-functions and model reference simulation targets. Your target does not need to handle these cases.

Modifying Template Makefiles to Support Shared Utilities

Make the following changes to your TMF to support the shared utilities directory:

- 1 Add the following make variables and tokens to be expanded when the makefile is generated:

```
SHARED_SRC      = |>SHARED_SRC<|
SHARED_SRC_DIR  = |>SHARED_SRC_DIR<|
SHARED_BIN_DIR  = |>SHARED_BIN_DIR<|
SHARED_LIB      = |>SHARED_LIB<|
```

SHARED_SRC specifies the shared utilities directory location and the source files in it. A typical expansion in a makefile is

```
SHARED_SRC      = ../slprj/ert/_sharedutils/*.c
```

SHARED_LIB specifies the library file built from the shared source files, as in the following expansion.

```
SHARED_LIB      = ../slprj/ert/_sharedutils/rtwshared.lib
```

SHARED_SRC_DIR and SHARED_BIN_DIR allow specification of separate directories for shared source files and the library compiled from the source files. In the current release, all TMFs use the same path, as in the following expansions.

```
SHARED_SRC_DIR  = ../slprj/ert/_sharedutils
SHARED_BIN_DIR  = ../slprj/ert/_sharedutils
```

- 2 Set the SHARED_INCLUDES variable according to whether shared utilities are in use. Then append it to the overall INCLUDES variable.


```

SHARED_INCLUDES =
ifneq ($(SHARED_SRC_DIR),)
SHARED_INCLUDES = -I$(SHARED_SRC_DIR)
endif

```

```

INCLUDES = -I. $(MATLAB_INCLUDES) $(ADD_INCLUDES) \
$(USER_INCLUDES) $(SHARED_INCLUDES)

```

- 3** Update the SHARED_SRC variable to list all shared files explicitly.

```

SHARED_SRC := $(wildcard $(SHARED_SRC))

```

- 4** Create a SHARED_OBJS variable based on SHARED_SRC.

```

SHARED_OBJS = $(addsuffix .o, $(basename $(SHARED_SRC)))

```

- 5** Create an OPTS (options) variable for compilation of shared utilities.

```

SHARED_OUTPUT_OPTS = -o $@

```

- 6** Provide a rule to compile the shared utility source files.

```

$(SHARED_OBJS) : $(SHARED_BIN_DIR)/%.o : $(SHARED_SRC_DIR)/%.c
$(CC) -c $(CFLAGS) $(SHARED_OUTPUT_OPTS) $<

```

- 7** Provide a rule to create a library of the shared utilities. The following example is UNIX based.

```

$(SHARED_LIB) : $(SHARED_OBJS)
@echo "### Creating $@"
ar r $@ $(SHARED_OBJS)
@echo "### Created $@"

```

- 8** Add SHARED_LIB to the rule that creates the final executable.

```

$(PROGRAM) : $(OBJS) $(LIBS) $(SHARED_LIB)
$(LD) $(LDFLAGS) -o $@ $(LINK_OBJS) $(LIBS) $(SHARED_LIB) \
$(SYSLIBS)
@echo "### Created executable: $(MODEL)"

```

- 9 Remove any explicit reference to `rt_nonfinite.c` or `rt_nonfinite.cpp` from your TMF. For example, change

```
ADD_SRCS = $(RTWLOG) rt_nonfinite.c
```

to

```
ADD_SRCS = $(RTWLOG)
```

Working with Data Structures

Parameter Storage, Interfacing, and Tuning (p. 5-2)	Explains how to generate storage declarations for communicating model parameters to and from user-written code
Signal Storage, Optimization, and Interfacing (p. 5-31)	Explains how signal storage optimizations work, and how to generate storage declarations for communicating model signals to and from user-written code
Parameter Tuning and Signal Monitoring (p. 5-45)	Explains how to tune parameters and monitor signals
Simulink Data Objects and Code Generation (p. 5-46)	Explains how to represent and store signals and parameters in Simulink data objects, and how Real-Time Workshop generates code from these objects
Block State Storage and Interfacing (p. 5-72)	Explains how to generate storage declarations for communicating discrete block states to and from user-written code
Storage Classes for Data Store Memory Blocks (p. 5-82)	Explains how to control data structures that define and initialize named shared memory regions, used by the Data Store Read and Data Store Write blocks

Parameter Storage, Interfacing, and Tuning

In this section...

- “Introduction” on page 5-2
- “Nontunable Parameter Storage” on page 5-3
- “Tunable Parameter Storage” on page 5-5
- “Tunable Parameter Storage Classes” on page 5-7
- “Using the Model Parameter Configuration Dialog Box” on page 5-10
- “Tunable Expressions” on page 5-14
- “Linear Block Parameter Tunability” on page 5-18
- “Parameter Configuration Quick Reference Diagram” on page 5-19
- “Generated Code for Parameter Data Types” on page 5-20
- “Tunable Workspace Parameter Data Type Considerations” on page 5-26
- “Parameter Tuning by Using MATLAB Commands” on page 5-28

Introduction

This section discusses how Real-Time Workshop generates parameter storage declarations, and how you can generate the storage declarations you need to interface block parameters to your code.

If you are using S-functions in your model and intend to tune their run-time parameters in the generated code, see “Tuning Runtime Parameters” in the Simulink documentation. Note that

- Parameters must be numeric, logical, or character arrays.
- Parameters may not be sparse.
- Parameter arrays must not be greater than 2 dimensions.

For guidance on implementing a parameter tuning interface using a C-API, see “C-API for Interfacing with Signals and Parameters” on page 17-2.

Simulink external mode offers a way to monitor signals and modify parameter values while generated model code executes. However, external mode might not be appropriate for your application in some cases. The S-function target does not support external mode, for example. For other targets, you might want your existing code to access parameters and signals of a model directly, rather than using the external mode communications mechanism. For information on external mode, see Chapter 6, “External Mode”.

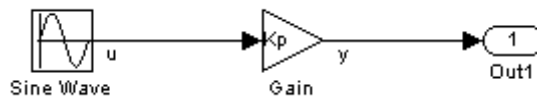
Nontunable Parameter Storage

By default, block parameters are not tunable in the generated code. When **Inline Parameters** is off (the default), Real-Time Workshop has control of parameter storage declarations and the symbolic naming of parameters in the generated code.

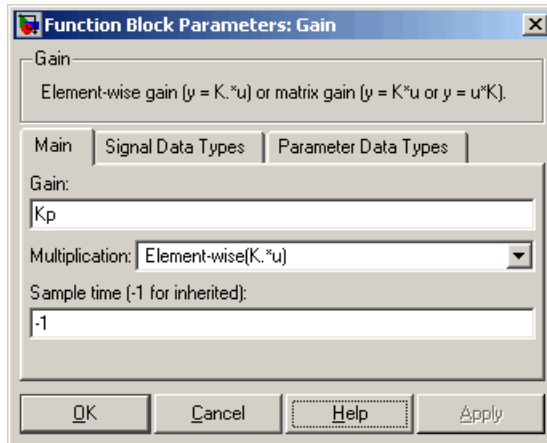
Nontunable parameters are stored as fields within *model_P* (formerly *rtP*), a model-specific global parameter data structure. Real-Time Workshop initializes each field of *model_P* to the value of the corresponding block parameter at code generation time.

When the **Inline parameters** option is on, block parameters are evaluated at code generation time, and their values appear as constants in the generated code, if possible (in certain circumstances, parameters cannot be inlined, and are then included in a constant parameter or model parameter structure.)

As an example of nontunable parameter storage, consider the following model.



The workspace variable *Kp* sets the gain of the Gain1 block.



Assume that K_p is nontunable and has a value of 5.0. The next table shows the variable declarations and the code generated for K_p in the noninlined and inlined cases.

Notice that the generated code does not preserve the symbolic name K_p . The noninlined code represents the gain of the Gain1 block as `model_P.Gain1_Gain`. When K_p is noninlined, the parameter is tunable.

Inline Parameters	Generated Variable Declaration and Code
Off	<pre> struct Parameters_non_tunable_sin { real_T SineWave_Amp; real_T SineWave_Bias; real_T SineWave_Freq; real_T SineWave_Phase; real_T Gain_Gain; }; . . . Parameters_non_tunable_sin non_tunable_sin_P = { 1.0 , /* SineWave_Amp : '<Root>/Sine Wave' */ 0.0 , /* SineWave_Bias : '<Root>/Sine Wave' */ 1.0 , /* SineWave_Freq : '<Root>/Sine Wave' */ 0.0 , /* SineWave_Phase : '<Root>/Sine Wave' */ 5.0 /* Gain_Gain : '<Root>/Gain' */ }; . . . non_tunable_sin_Y.Out1 = rtb_u * non_tunable_sin_P.Gain_Gain; </pre>
On	<pre> non_tunable_sin_Y.Out1 = rtb_u * 5.0; </pre>

Tunable Parameter Storage

A *tunable* parameter is a block parameter whose value can be changed at run-time. A tunable parameter is inherently noninlined. Consequently, when **Inlined parameters** is off, all parameters are members of *model_P*, and thus are tunable. A *tunable expression* is an expression that contains one or more tunable parameters.

When you declare a parameter tunable, you control whether or not the parameter is stored within `model_P`. You also control the symbolic name of the parameter in the generated code.

When you declare a parameter tunable, you specify

- The *storage class* of the parameter.

In Real-Time Workshop, the storage class property of a parameter specifies how Real-Time Workshop declares the parameter in generated code.

The term “storage class,” as used in Real-Time Workshop, is not synonymous with the term *storage class specifier*, as used in the C language.

- A *storage type qualifier*, such as `const` or `volatile`. This is simply a string that is included in the variable declaration, without error checking.
- (Implicitly) the symbolic name of the variable or field in which the parameter is stored. Real-Time Workshop derives variable and field names from the names of tunable parameters.

Real-Time Workshop generates a variable or struct storage declaration for each tunable parameter. Your choice of storage class controls whether the parameter is declared as a member of `model_P` or as a separate global variable.

You can use the generated storage declaration to make the variable visible to external legacy code. You can also make variables declared in your code visible to the generated code. You are responsible for properly linking your code to generated code modules.

You can use tunable parameters or expressions in your root model and in masked or unmasked subsystems, subject to certain restrictions. (See “Tunable Expressions” on page 5-14.)

Overriding Inlined Parameters for Tuning

When the **Inline parameters** option is selected, you can use the Model Parameter Configuration dialog box to remove individual parameters from inlining and declare them to be tunable. This allows you to improve overall efficiency by inlining most parameters, while at the same time retaining the flexibility of run-time tuning for selected parameters. Another way you can

achieve the same result is by using Simulink data objects; see “Simulink Data Objects and Code Generation” on page 5-46 for specific details.

The mechanics of declaring tunable parameters are discussed in “Using the Model Parameter Configuration Dialog Box” on page 5-10.

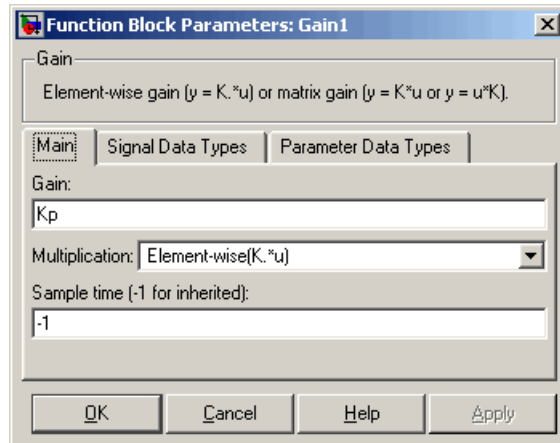
Tunable Parameter Storage Classes

Real-Time Workshop defines four storage classes for tunable parameters. You must declare a tunable parameter to have one of the following storage classes:

- **SimulinkGlobal (Auto):** SimulinkGlobal (Auto) is the default storage class. Real-Time Workshop stores the parameter as a member of *model_P*. Each member of *model_P* is initialized to the value of the corresponding workspace variable at code generation time.
- **ExportedGlobal:** The generated code instantiates and initializes the parameter and *model.h* exports it as a global variable. An exported global variable is independent of the *model_P* data structure. Each exported global variable is initialized to the value of the corresponding workspace variable at code generation time.
- **ImportedExtern:** *model_private.h* declares the parameter as an extern variable. Your code must supply the proper variable definition and initializer.
- **ImportedExternPointer:** *model_private.h* declares the variable as an extern pointer. Your code must supply the proper pointer variable definition and initializer, if any.

The generated code for *model.h* includes *model_private.h* to make the extern declarations available to subsystem files.

As an example of how the storage class declaration affects the code generated for a parameter, consider the next figure.



The workspace variable `Kp` sets the gain of the `Gain1` block. Assume that the value of `Kp` is 3.14. The following table shows the variable declarations and the code generated for the gain block when `Kp` is declared as a tunable parameter. An example is shown for each storage class.

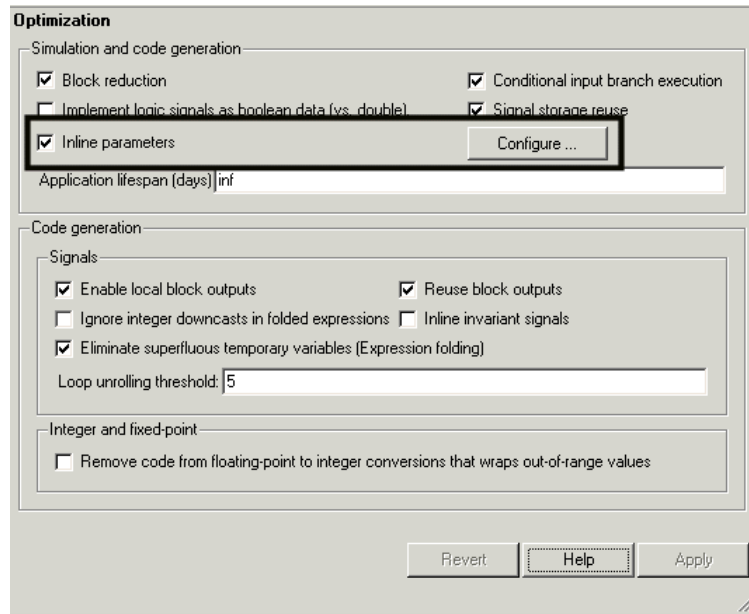
Note Real-Time Workshop uses column-major ordering for two-dimensional signal and parameter data. When interfacing your hand-written code to such signals or parameters by using `ExportedGlobal`, `ImportedExtern`, or `ImportedExternPointer` declarations, make sure that your code observes this ordering convention.

The symbolic name `Kp` is preserved in the variable and field names in the generated code.

Storage Class	Generated Variable Declaration and Code
SimulinkGlobal (Auto)	<pre> typedef struct _Parameters_tunable_sin Parameters_tunable_sin; struct _Parameters_tunable_sin { real_T Kp; }; Parameters_tunable_sin tunable_sin_P = { 3.14 }; . . tunable_sin_Y.Out1 = rtb_u * tunable_sin_P.Kp; </pre>
ExportedGlobal	<pre> real_T Kp = 3.14; . . tunable_sin_Y.Out1 = rtb_u * Kp; </pre>
ImportedExtern	<pre> extern real_T Kp; . . tunable_sin_Y.Out1 = rtb_u * Kp; </pre>
ImportedExtern Pointer	<pre> extern real_T *Kp; . . tunable_sin_Y.Out1 = rtb_u * (*Kp); </pre>

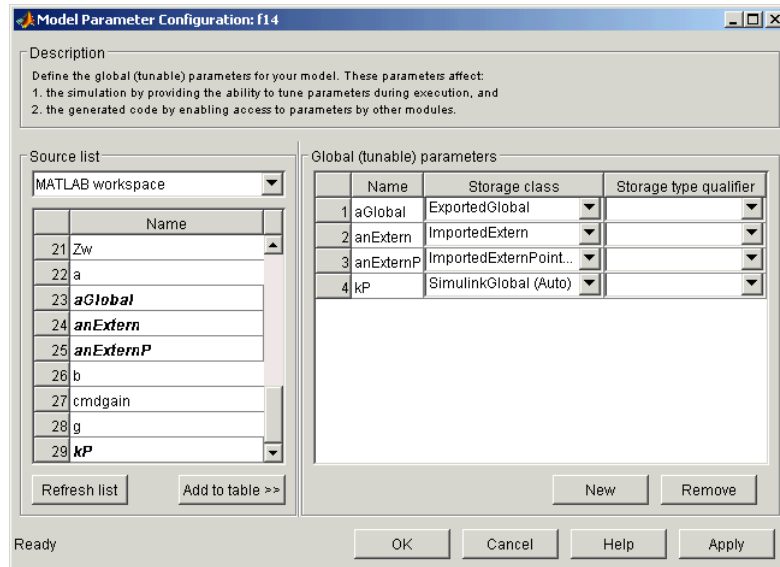
Using the Model Parameter Configuration Dialog Box

The Model Parameter Configuration dialog box is available only when the **Inline parameters** option on the **Optimization** pane is selected. Selecting this option activates the **Configure** button, as shown in the next figure.



Clicking the **Configure** button opens the Model Parameter Configuration dialog box.

Note The Model Parameter Configuration dialog box cannot tune parameters within referenced models. See “Parameterizing Model References” for tuning techniques that work with referenced models.



The Model Parameter Configuration Dialog Box

The Model Parameter Configuration dialog box lets you select base workspace variables and declare them to be tunable parameters in the current model. The dialog box is divided into two panels:

- The **Source list** panel displays a list of workspace variables and lets you add them to the tunable parameters list.
- The **Global (tunable) parameters** panel displays and maintains a list of tunable parameters associated with the model.

To declare tunable parameters, you select one or more variables from the **Source list**, add them to the **Global (tunable) parameters** list, and set their storage class and other attributes.

Source List Panel

The **Source list** panel displays a menu and a scrolling table of numerical workspace variables.

The menu lets you choose the source of the variables to be displayed in the list. There are two choices: MATLAB workspace (lists all variables in the

MATLAB workspace that have numeric values), and Referenced workspace variables (lists only those variables referenced by the model). The source list displays names of variables defined in the MATLAB base workspace.

Selecting one or more variables from the source list enables the **Add to table** button. Clicking **Add to table** adds selected variables to the tunable parameters list in the **Global (tunable) parameters** panel. This action is all that is necessary to declare tunable parameters. However, if a block parameter which is not tunable is set to the name that appears on this list, a warning results during simulation and also during code generation.

In the **Source list**, the names of variables added to the tunable parameters list are displayed in bold type (see the preceding figure).

The **Refresh list** button updates the table of variables to reflect the current state of the workspace. If you define or remove variables in the workspace while the Model Parameter Configuration dialog box is open, click the **Refresh list** button when you return to the dialog box. The new variables are added to the source list.

Global (Tunable) Parameters Panel

The **Global (tunable) parameters** panel displays a scrolling table of variables that have been declared tunable in the current model and lets you specify their attributes. The **Global (tunable) parameters** panel also lets you remove entries from the list or create new tunable parameters.

You select individual variables and change their attributes directly in the table. The attributes are

- **Storage class** of the parameter in the generated code. Select one of
 - SimulinkGlobal (Auto)
 - ExportedGlobal
 - ImportedExtern
 - ImportedExternPointer

See “Tunable Parameter Storage Classes” on page 5-7 for definitions.

- **Storage type qualifier** of the variable in the generated code. For variables with any storage class *except* SimulinkGlobal (Auto), you can add a qualifier (such as `const` or `volatile`) to the generated storage declaration. To do so, you can select a predefined qualifier from the list or add additional qualifiers to the list. The code generator does not check the storage type qualifier for validity. The code generator includes the qualifier string in the generated code without syntax checking.
- **Name** of the parameter. This field is used only when creating a new tunable variable.

Use the **New** button to create a new tunable variable entry in the **Global (tunable) parameters** list. Enter the name and attributes of the variable and click **Apply**. The new variable does not need to be in use when you do this. At a later time, you can add references to any such variable in the model.

If the name you enter matches the name of an existing workspace variable in the **Source list**, that variable is declared tunable, and is displayed in italics in the **Source list**.

Use the **Remove** button to delete selected variables from the **Global (tunable) parameters** list. All such removed variables will be inlined if **Inlined parameters** is on.

Note If you edit the name of an existing variable in the list, you actually create a new tunable variable with the new name. The previous variable is removed from the list and loses its tunability (that is, it is inlined).

Declaring Tunable Variables

To declare an existing variable tunable

- 1 Open the Model Parameter Configuration dialog box.
- 2 In the **Source list** panel, click the desired variable in the list to select it.
- 3 Click the **Add to table** button. The variable then appears in the table of tunable variables in the **Global (tunable) parameters** panel.

- 4** Click the variable in the **Global (tunable) parameters** panel.
- 5** Select the desired storage class from the **Storage class** menu.
- 6** Optionally, select (or enter) a storage type qualifier, such as `const` or `volatile` that you want the variable to have.
- 7** Click **Apply**, or click **OK** to apply changes and close the dialog box.

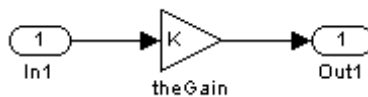
Tunable Expressions

Real-Time Workshop supports the use of tunable variables in expressions. An expression that contains one or more tunable parameters is called a *tunable expression*.

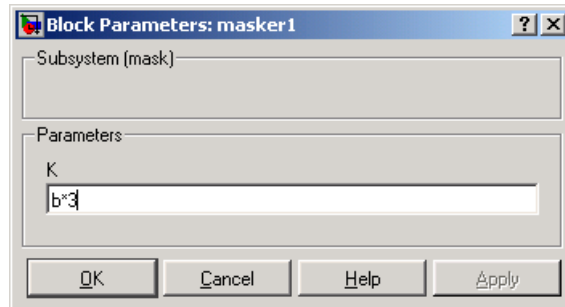
Tunable Expressions in Masked Subsystems

Tunable expressions are allowed in masked subsystems. You can use tunable parameter names or tunable expressions in a masked subsystem dialog box. When referenced in lower-level subsystems, such parameters remain tunable.

As an example, consider the masked subsystem in the next figure. The masked variable `k` sets the gain parameter of `theGain`.



Suppose that the base workspace variable `b` is declared tunable with `SimulinkGlobal (Auto)` storage class. The next figure shows the tunable expression `b*3` in the subsystem's mask dialog box.



Tunable Expression in Subsystem Mask Dialog Box

Real-Time Workshop produces the following output computation for theGain. The variable *b* is represented as a member of the global parameters structure, *model_P*. (For clarity in showing the individual Gain block computation, **Expression folding** was turned off in this example.)

```
/* Gain: '<S1>/theGain' */
   rtb_theGain_C = rtb_SineWave_n * ((subsys_mask_P.b * 3.0));

/* Output: '<Root>/Out1' */
   subsys_mask_Y.Out1 = rtb_theGain_C;
```

As this example shows, for GRT targets, the parameter structure is mangled to create the structure identifier *model_P* (subject to the identifier length constraint). This is done to avoid namespace clashes in combining code from multiple models using model reference. ERT-based targets provide ways to customize identifier names.

When **Expression folding** is turned on, the above code condenses to

```
/* Output: '<Root>/Out1' incorporates:
 * Gain: '<S1>/theGain'
 */
   subsys_mask_Y.Out1 = rtb_SineWave_n * ((subsys_mask_P.b * 3.0));
```

Expressions that include variables that were declared or modified in mask initialization code are *not* tunable.

As an example, consider the subsystem above, modified as follows:

- The mask initialization code is

```
t = 3 * k;
```

- The parameter k of the myGain block is 4 + t.
- Workspace variable b = 2. The expression b * 3 is plugged into the mask dialog box as in the preceding figure.

Since the mask initialization code can run only once, k is evaluated at code generation time as

```
4 + (3 * (2 * 3) )
```

Real-Time Workshop inlines the result. Therefore, despite the fact that b was declared tunable, the code generator produces the following output computation for theGain. (For clarity in showing the individual Gain block computation, **Expression folding** was off in this example.)

```
/* Gain Block: <S1>/theGain */
rtb_temp0 *= (22.0);
```

Tunable Expression Limitations

Currently, there are certain limitations on the use of tunable variables in expressions. When an unsupported expression is encountered during code generation a warning is issued and the equivalent numeric value is generated in the code. The limitations on tunable expressions are

- Complex expressions are not supported, except where the expression is simply the name of a complex variable.
- The use of certain operators or functions in expressions containing tunable operands is restricted. Restrictions are applied to four categories of operators or functions, classified in the following table:

Category	Supported Operators or Functions
1	+ - .* ./ < > <= >= == ~= &
2	* /

Category	Supported Operators or Functions
3	abs, acos, asin, atan, atan2, boolean, ceil, cos, cosh, exp, floor, log, log10, sign, sin, sinh, sqrt, tan, tanh,
4	single, int8, int16, int32, uint8, uint16, uint32
5	: .^ ^ [] {} . \ .\ ' .' ; ,

The rules applying to each category are as follows:

- Category 1 is unrestricted. These operators can be used in tunable expressions with any combination of scalar or vector operands.
- Category 2 operators can be used in tunable expressions where at least one operand is a scalar. That is, scalar/scalar and scalar/matrix operand combinations are supported, but not matrix/matrix.
- Category 3 lists all functions that support tunable arguments. Tunable arguments passed to these functions retain their tunability. Tunable arguments passed to any other functions lose their tunability.
- Category 4 lists the casting functions that do not support tunable arguments. Tunable arguments passed to these functions lose their tunability.

Note Real-Time Workshop casts values using MATLAB typecasting rules. The MATLAB typecasting rules are different from C code typecasting rules. For example, in MATLAB, `int8(3.7)` returns the result 4, while in C code `int8(3.7)` returns the result 3. See “Data Type Conversion” in the MATLAB reference documentation for more information on MATLAB typecasting.

- Category 5 operators are not supported.

Note The “dot” (structure membership) operator is not supported. This means that expressions that include a structure member are not tunable.

- Expressions that include variables that were declared or modified in mask initialization code are *not* tunable.
- The Fcn block does not support tunable expressions in code generation.
- Model workspace parameters can take on only the Auto storage class, and thus are not tunable. See “Parameterizing Model References” for tuning techniques that work with referenced models.
- Non-double expressions are not supported.
- Blocks that access parameters only by address support the use of tunable parameters, if the parameter expression is a simple variable reference. When an operation such as a data type conversion or a math operation is applied, Real-Time Workshop creates a nontrivial expression that cannot be accessed by address, resulting in an error during the build process.

Linear Block Parameter Tunability

The following blocks have a `Realization` parameter that affects the tunability of their parameters:

- Transfer Fcn
- State-Space
- Discrete Transfer Fcn
- Discrete State-Space
- Discrete Filter

The `Realization` parameter must be set by using the MATLAB `set_param` function, as in the following example.

```
set_param(gcf, 'Realization', 'auto')
```

The following values are defined for the `Realization` parameter:

- `general`: The block’s parameters are preserved in the generated code, permitting parameters to be tuned.
- `sparse`: The block’s parameters are represented in the code by transformed values that increase the computational efficiency. Because of the transformation, the block’s parameters are no longer tunable.

- auto: This setting is the default. A general realization is used if one or more of the block's parameters are tunable. Otherwise sparse is used.

Note To tune the parameter values of a block of one of the above types without restriction during an external mode simulation, you must set Realization to general.

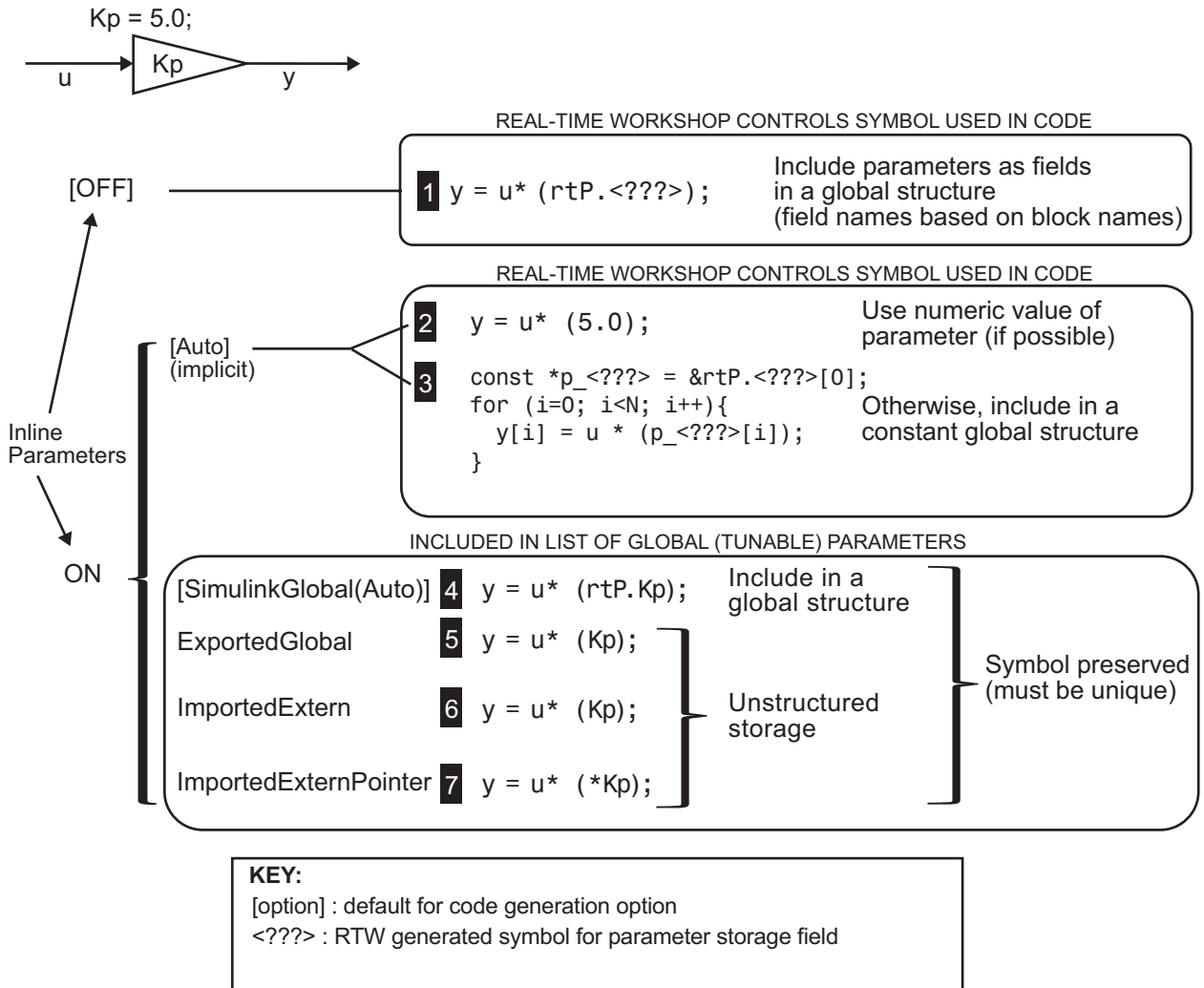
Code Reuse for Subsystems with Mask Parameters

Real-Time Workshop can generate reusable (reentrant) code for a model containing identical atomic subsystems. Selecting the Reusable function option for **Real-Time Workshop system code** enables such code reuse, and causes a single function with arguments to be generated that is called when any of the identical atomic subsystem executes. See “Reusable Function Option” on page 4-12 for details and restrictions on the use of this option.

Mask parameters become arguments to reusable functions. However, for reuse to occur, each instance of a reusable subsystem must declare the same set of mask parameters. If, for example subsystem A has mask parameters b and K, and subsystem B has mask parameters c and K, then code reuse is not possible, and Real-Time Workshop will generate separate functions for A and B.

Parameter Configuration Quick Reference Diagram

The next figure shows the code generation and storage class options that control the representation of parameters in generated code.

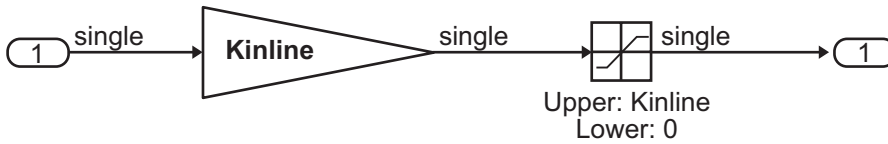


Generated Code for Parameter Data Types

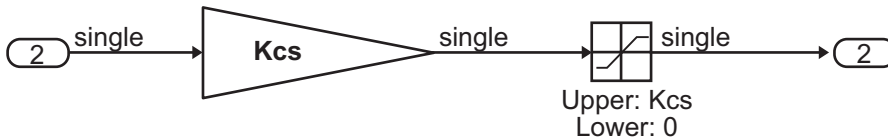
For an example of the code generated from Simulink parameters with different data types, run the demo model `rtwdemo_paramdt`. This demo model shows options that are available for controlling the data type of tunable parameters in the generated code. The model's subsystem includes several

instances of Gain blocks feeding Saturation blocks. Each pair of blocks uses a workspace variable of a particular data type, as shown in the next figure.

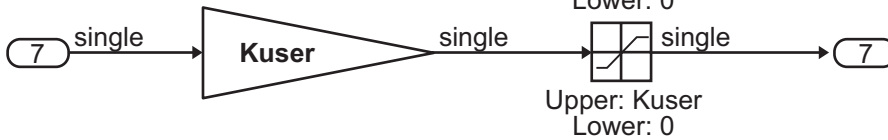
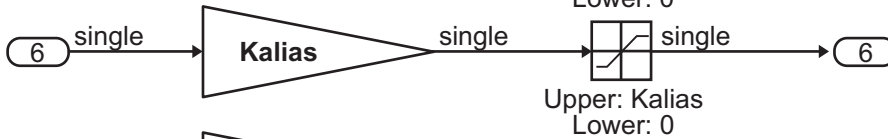
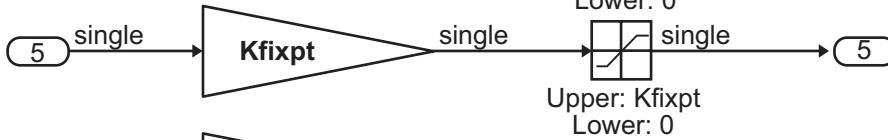
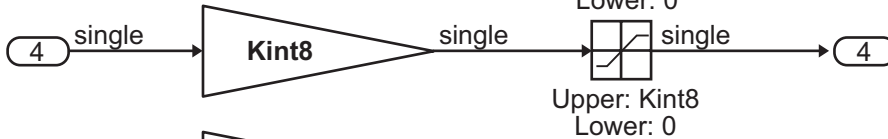
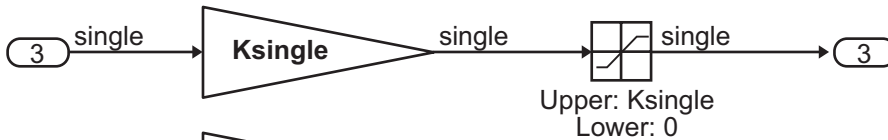
Inlined parameters (InLineParameters ON + Auto storage class)
 ==> numeric value inlined



Double-precision (context-sensitive) parameters
 ==> tunable parameter inherits data type from run-time parameter



Tunable parameters with explicit data type specification
 ==> parameter is cast to run-time parameter data type in generated code



Simulink initializes the parameters in the demo model by executing the script `rtwdemo_paramdt_data.m`. You can view the initialization script and inspect the workspace variables in Model Explorer by double-clicking the appropriate yellow boxes in the demo model.

In the demo model, note that the **Inline parameters** option on the **Optimization** pane of the **Configuration Parameters** dialog box is selected. The **Model Parameter Configuration** dialog box reveals that all base workspace variables (with the exception of `Kinline`) have their **Storage class** property set to `ExportedGlobal`. Consequently, `Kinline` is a nontunable parameter while the remaining variables are tunable parameters.

To generate code for the demo model, double-click the blue boxes. The following table shows both the MATLAB code used to initialize parameters and the code generated for each parameter in the `rtwdemo_paramdt` model.

Parameter & MATLAB Code	Generated Variable Declaration and Code
<p>Kinline</p> <pre>Kinline = 2;</pre>	<pre>rtb_Gain1 = rtwdemo_paramdt_U.In1 * 2.0F; . . rtwdemo_paramdt_Y.Out1 = rt_SATURATE(rtb_Gain1, 0.0F, 2.0F);</pre>
<p>Kcs</p> <pre>Kcs = 3;</pre>	<pre>real32_T Kcs = 3.0F; . . rtb_Gain1 = rtwdemo_paramdt_U.In2 * Kcs; . . rtwdemo_paramdt_Y.Out2 = rt_SATURATE(rtb_Gain1, 0.0F, Kcs);</pre>

Parameter & MATLAB Code	Generated Variable Declaration and Code
<p>Ksingle</p> <pre>Ksingle = single(4);</pre>	<pre>real32_T Ksingle = 4.0F; . . rtb_Gain1 = rtwdemo_paramdt_U.In3 * Ksingle; . . rtwdemo_paramdt_Y.Out3 = rt_SATURATE(rtb_Gain1, 0.0F, Ksingle);</pre>
<p>Kint8</p> <pre>Kint8 = int8(5);</pre>	<pre>int8_T Kint8 = 5; . . rtb_Gain1 = rtwdemo_paramdt_U.In4 * ((real32_T)(Kint8)); . . rtwdemo_paramdt_Y.Out4 = rt_SATURATE(rtb_Gain1, 0.0F, ((real32_T)(Kint8)));</pre>
<p>Kfixpt</p> <pre>Kfixpt = Simulink.Parameter; Kfixpt.Value = 6; Kfixpt.DataType = ... 'fixdt(true, 16, 2^-5, 0)'; Kfixpt.RTWInfo.StorageClass = ... 'ExportedGlobal';</pre>	<pre>int16_T Kfixpt = 192; . . rtb_Gain1 = rtwdemo_paramdt_U.In5 * (((real32_T)ldexp((real_T)Kfixpt, -5))); . . rtwdemo_paramdt_Y.Out5 = rt_SATURATE(rtb_Gain1, 0.0F, (((real32_T)ldexp((real_T)Kfixpt, -5))));</pre>

Parameter & MATLAB Code	Generated Variable Declaration and Code
<p>Kalias</p> <pre>aliasType = ... Simulink.AliasType('single'); Kalias = Simulink.Parameter; Kalias.Value = 7; Kalias.DataType = 'aliasType'; Kalias.RTWInfo.StorageClass = ... 'ExportedGlobal';</pre>	<pre>typedef real32_T aliasType; . . aliasType Kalias = 7.0F; . . rtb_Gain1 = rtwdemo_paramdt_U.In6 * Kalias; . . rtwdemo_paramdt_Y.Out6 = rt_SATURATE(rtb_Gain1, 0.0F, Kalias);</pre>
<p>Kuser</p> <pre>userType = Simulink.NumericType; userType.DataTypeMode = ... 'Fixed-point: slope and bias scaling'; userType.Slope = 2^-3; userType.isAlias = true; Kuser = Simulink.Parameter; Kuser.Value = 8; Kuser.DataType = 'userType'; Kuser.RTWInfo.StorageClass = ... 'ExportedGlobal';</pre>	<pre>typedef int16_T userType; . . userType Kuser = 64; . . rtb_Gain1 = rtwdemo_paramdt_U.In7 * (((real32_T)1dexp((real_T)Kuser, -3))); . . rtwdemo_paramdt_Y.Out7 = rt_SATURATE(rtb_Gain1, 0.0F, (((real32_T)1dexp((real_T)Kuser, -3))));</pre>

The salient features of the code generated for this demo model are as follows:

- Real-Time Workshop inlines nontunable parameters, for example, `Kinline`. However, Real-Time Workshop does not inline tunable parameters, such as `Kcs`, `Ksingle`, and `Kint8`.
- Simulink treats tunable parameters of data type `double` in a context-sensitive manner, such that the parameter inherits its data type from the context in which the block uses it. For example, `Kcs` inherits a single data type from the Gain block's input signal.
- If a parameter's data type matches that of the block's run-time parameter, the block can use the tunable parameter without any transformation.

Consequently, Real-Time Workshop need not cast the parameter from one data type to another, as illustrated by `Ksingle` and `Kalias`. However, if a parameter's data type does not match that of the block's run-time parameter, the block cannot readily compute its output. In this case, Real-Time Workshop casts parameters to the appropriate data type. For example, `Kint8`, `Kfixpt`, and `Kuser` require casts to a single data type for compatibility with the input signals to the Gain and Saturation blocks.

- If you are using an ERT target and a parameter specifies a data type alias, for example, created by an instance of the `Simulink.AliasType` class, its variable definition in the generated code uses the alias data type. For example, Real-Time Workshop declares `Kalias` and `Kuser` to be of data types `aliasType` and `userType`, respectively.
- If a parameter specifies a fixed-point data type, Real-Time Workshop initializes its value in the generated code to the value of Q computed from the expression $V = SQ + B$ (see the Simulink Fixed Point documentation for more information about fixed-point semantics and notation), where
 - V is a real-world value
 - Q is an integer that encodes V
 - S is the slope
 - B is the bias

For example, `Kfixpt` has a real-world value of 6, slope of 2^{-5} , and bias of 0. Consequently, Real-Time Workshop declares the value of `Kfixpt` to be 192.

Tunable Workspace Parameter Data Type Considerations

If you are using tunable workspace parameters, you need to be aware of potential issues regarding data types. A workspace parameter is tunable when the following conditions exist:

- You select the **Inline parameters** option on the **Optimization pane** of the Configuration Parameters dialog box
- The parameter has a storage class other than `Auto`

When generating code for tunable workspace parameters, Real-Time Workshop checks and compares the data types used for a particular parameter in the workspace and in Block Parameter dialog boxes.

If...	Real-Time Workshop...
The data types match	Uses that data type for the parameter in the generated code.
You do not explicitly specify a data type other than double in the workspace	<p>Uses the data type specified by the block in the generated code. If multiple blocks share a parameter, they must all specify the same data type. If the data type varies between blocks, Real-Time Workshop generates an error similar to the following:</p> <pre data-bbox="743 725 1233 939">Variable 'K' is used in incompatible ways in the dialog fields of the following: cs_params/Gain, cs_params/Gain1. The variable'value is being used both directly and after a transformation. Only one of these usages is permitted for any given variable.</pre>
You explicitly specify a data type other than double in the workspace	Uses the data type from the workspace for the parameter. The block typecasts the parameter to the block specific data type before using it.

Guidelines for Specifying Data Types

The following table provides guidelines on specifying data types for tunable workspace parameters.

If You Want to...	Then Specify Data Types in...
Minimize memory usage (int8 instead of single)	The workspace explicitly
Avoid typecasting	Blocks only

If You Want to...	Then Specify Data Types in...
Interface to legacy or custom code	The workspace explicitly
Use the same parameter for multiple blocks that specify different data types	The workspace explicitly

Real-Time Workshop enforces limitations on the use of data types other than `double` in the workspace, as explained in “Limitations on Specifying Data Types in the Workspace Explicitly” on page 5-28.

Limitations on Specifying Data Types in the Workspace Explicitly

When you explicitly specify a data type other than `double` in the workspace, blocks typecast the parameter to the appropriate data type. This is an issue for blocks that use pointer access for their parameters. Blocks cannot use pointer access if they need to typecast the parameter before using it (because of a data type mismatch). Another case in which this occurs is for workspace variables with bias or fractional slope. Two possible solutions to these problems are

- Remove the explicit data type specification in the workspace for parameters used in such blocks.
- Modify the block so that it uses the parameter with the same data type as specified in the workspace. For example, the Lookup Table block uses the data types of its input signal to determine the data type that it uses to access the X-breakpoint parameter. You can prevent the block from typecasting the run-time parameter by converting the input signal to the data type used for X-breakpoints in the workspace. (Similarly, the output signal is used to determine the data types used to access the lookup table’s Y data.)

Parameter Tuning by Using MATLAB Commands

When parameters are MATLAB workspace variables, the Model Parameter Configuration dialog box is the recommended way to see or set the attributes of tunable parameters. In addition to that dialog box, you can also use MATLAB `get_param` and `set_param` commands.

Note You can also use `Simulink.Parameter` objects for tunable parameters. See “Configuring Parameter Objects for Code Generation” on page 5-47 for details.

The following commands return the tunable parameters and/or their attributes:

- `get_param(gcs, 'TunableVars')`
- `get_param(gcs, 'TunableVarsStorageClass')`
- `get_param(gcs, 'TunableVarsTypeQualifier')`

The following commands declare tunable parameters or set their attributes:

- `set_param(gcs, 'TunableVars', str)`

The argument `str` (string) is a comma-separated list of variable names.

- `set_param(gcs, 'TunableVarsStorageClass', str)`

The argument `str` (string) is a comma-separated list of storage class settings.

The valid storage class settings are

- `Auto`
 - `ExportedGlobal`
 - `ImportedExtern`
 - `ImportedExternPointer`
- `set_param(gcs, 'TunableVarsTypeQualifier', str)`

The argument `str` (string) is a comma-separated list of storage type qualifiers.

The following example declares the variable `k1` to be tunable, with storage class `ExportedGlobal` and type qualifier `const`. The number of variables and number of specified storage class settings must match. If you specify multiple variables and storage class settings, separate them with a comma.

```
set_param(gcs, 'TunableVars', 'k1')
set_param(gcs, 'TunableVarsStorageClass', 'ExportedGlobal')
set_param(gcs, 'TunableVarsTypeQualifier', 'const')
```

Other configuration parameters you can get and set are listed in “Configuration Parameters” in the Real-Time Workshop Reference.

Signal Storage, Optimization, and Interfacing

In this section...

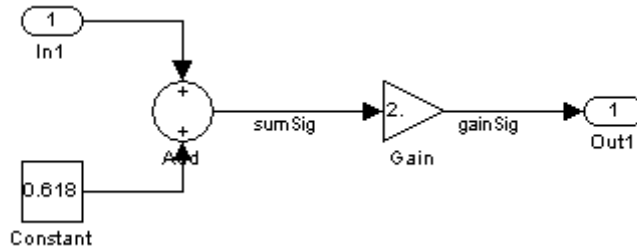
- “Introduction” on page 5-31
- “Signal Storage Concepts” on page 5-32
- “Signals with Auto Storage Class” on page 5-34
- “Declaring Test Points” on page 5-39
- “Interfacing Signals to External Code” on page 5-40
- “Symbolic Naming Conventions for Signals in Generated Code” on page 5-42
- “Summary of Signal Storage Class Options” on page 5-43

Introduction

Real-Time Workshop offers a number of options that let you control how signals in your model are stored and represented in the generated code. This section discusses how you can use these options to

- Control whether signal storage is declared in global memory space or locally in functions (that is, in stack variables).
- Control the allocation of stack space when using local storage.
- Ensure that particular signals are stored in unique memory locations by declaring them as *test points*.
- Reduce memory usage by instructing Real-Time Workshop to store signals in reusable buffers.
- Control whether or not signals declared in generated code are interfaceable (visible) to externally written code. You can also specify that signals are to be stored in locations declared by externally written code.
- Preserve the symbolic names of signals in generated code by using signal labels.

The discussion in the following sections refers to code generated from `signal_examp`, the model shown in the next figure.



Signal_examp Model

Signal Storage Concepts

This section discusses structures and concepts you must understand to choose the best signal storage options for your application:

- The global block I/O data structure *model_B*
- The concept of signal *storage classes* as used in Real-Time Workshop

The Global Block I/O Structure

By default, Real-Time Workshop attempts to optimize memory usage by sharing signal memory and using local variables.

However, there are a number of circumstances in which it is desirable or necessary to place signals in global memory. For example,

- You might want a signal to be stored in a structure that is visible to externally written code.
- The number and/or size of signals in your model might exceed the stack space available for local variables.

In such cases, it is possible to override the default behavior and store selected (or all) signals in a model-specific *global block I/O data structure*. The global block I/O structure is called *model_B* (in earlier versions this was called *rtB*).

The following code shows how *model_B* is defined and declared in code generated (with signal storage optimizations off) from the *signal_examp* model shown in the figure *Signal_examp Model* on page 5-32.

```

(in model.h)
/* Block signals (auto storage) */
typedef struct _BlockIO_signal_examp {
    real_T sumSig;           /* '<Root>/Add' */
    real_T gainSig;        /* '<Root>/Gain' */
} BlockIO_signal_examp;
. . .
(in model.c)
/* Block signals (auto storage) */
BlockIO_signal_examp signal_examp_B;

```

Field names for signals stored in *model_B* are generated according to the rules described in “Symbolic Naming Conventions for Signals in Generated Code” on page 5-42.

Signals Storage Classes

In Real-Time Workshop, the *storage class* property of a signal specifies how Real-Time Workshop declares and stores the signal. In some cases this specification is qualified by more options.

In the context of Real-Time Workshop, the term “storage class” is not synonymous with the term *storage class specifier*, as used in the C language.

Default Storage Class. Auto is the default storage class. Auto is the appropriate storage class for signals that you do not need to interface to external code. Signals with Auto storage class can be stored in local and/or shared variables or in a global data structure. The form of storage depends on the **Signal storage reuse**, **Reuse block outputs**, and **Enable local block outputs** options, and on available stack space. See “Signals with Auto Storage Class” on page 5-34 for a full description of code generation options for signals with Auto storage class.

Explicitly Assigned Storage Classes. Signals with storage classes other than Auto are stored either as members of *model_B*, or in unstructured global variables, independent of *model_B*. These storage classes are appropriate for signals that you want to monitor and/or interface to external code.

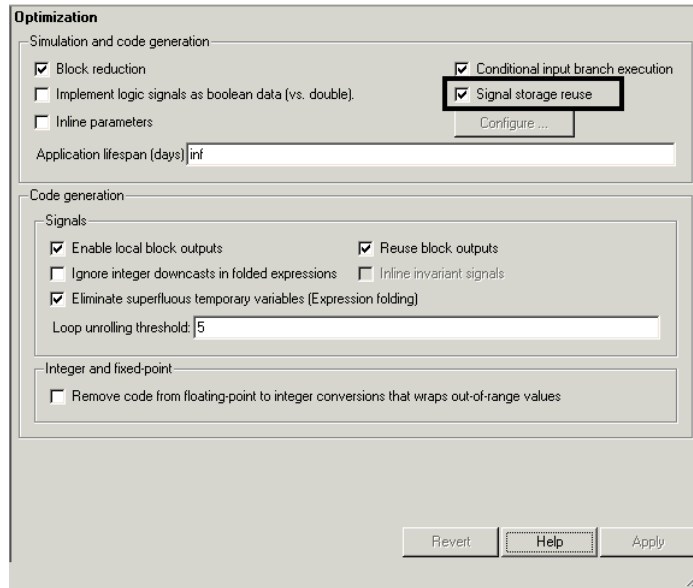
The **Signal storage reuse** and **Local block outputs** optimizations do not apply to signals with storage classes other than Auto.

Use the Signal Properties dialog box to assign these storage classes to signals:

- `SimulinkGlobal(Test Point)`: Test points are stored as fields of the `model_B` structure that are not shared or reused by any other signal. See “Declaring Test Points” on page 5-39 for more information.
- `ExportedGlobal`: The signal is stored in a global variable, independent of the `model_B` data structure. `model.h` exports the variable. Signals with `ExportedGlobal` storage class must have unique signal names. See “Interfacing Signals to External Code” on page 5-40 for more information.
- `ImportedExtern`: `model_private.h` declares the signal as an extern variable. Your code must supply the proper variable definition. Signals with `ImportedExtern` storage class must have unique signal names. See “Interfacing Signals to External Code” on page 5-40 for more information.
- `ImportedExternPointer`: `model_private.h` declares the signal as an extern pointer. Your code must define a valid pointer variable. Signals with `ImportedExtern` storage class must have unique signal names. See “Interfacing Signals to External Code” on page 5-40 for more information.

Signals with Auto Storage Class

Options are available for signals with Auto storage class — **Signal storage reuse** and **Reuse block outputs**. Use these options to control signal memory reuse and choose local or global (`model_B`) storage for signals. The **Signal storage reuse** option is on the **Optimization** pane of the Configuration Parameters dialog box, as shown in the next figure.



When **Signal storage reuse** is on, the **Enable local block outputs** and **Reuse block outputs** options in the Code Generation section of the dialog box become visible, and are selected by default.

These options interact. When the **Signal storage reuse** option is on,

- The **Reuse block outputs** option is enabled. By default, **Reuse block outputs** is on and signal memory is reused whenever possible.
- The **Enable Local block outputs** option is enabled. This lets you choose whether reusable signal variables are declared as local variables in functions or as members of `model_B`.

The following code examples illustrate the effects of the **Signal storage reuse**, **Reuse block outputs**, and **Enable local block outputs** options. The examples were generated from the `signal_examp` model (see figure `Signal_examp Model` on page 5-32).

The first example illustrates maximal signal storage optimization, with **Signal storage reuse**, **Reuse block outputs**, and **Enable local block**

outputs on (the default). The output signal from the Sum block reuses `rtb_sumSig`, a variable local to the `MdlOutputs` function.

```
/* Model output function */
static void signal_examp_output(int_T tid)
{
    /* local block i/o variables */
    real_T rtb_sumSig;

    /* Sum: '<Root>/Add' incorporates:
     * Constant: '<Root>/Constant'
     * Inport: '<Root>/In1'
     */
    rtb_sumSig = signal_examp_U.In1 + signal_examp_P.Constant_Value;

    /* Gain: '<Root>/Gain' */
    rtb_sumSig *= signal_examp_P.Gain_Gain;

    /* Outport: '<Root>/Out1' */
    signal_examp_Y.Out1 = rtb_sumSig;
    UNUSED_PARAMETER(tid);
}
```

If you are constrained by limited stack space, you can turn **Enable local block outputs** off and still benefit from memory reuse. The following example was generated with **Enable local block outputs** off and **Signal storage reuse** and **Reuse block outputs** on. The output signals from the Sum and Gain blocks use global structure `signal_examp_B` rather than declaring local variables and in both cases the signal name is `sumSig`.

```
/* Model output function */
static void signal_examp_output(int_T tid)
{
    /* Sum: '<Root>/Add' incorporates:
     * Constant: '<Root>/Constant'
     * Inport: '<Root>/In1'
     */
    signal_examp_B.sumSig = signal_examp_U.In1 +
        signal_examp_P.Constant_Value;
```

```

/* Gain: '<Root>/Gain' */
signal_examp_B.sumSig = signal_examp_B.sumSig *
    signal_examp_P.Gain_Gain;

/* Output: '<Root>/Out1' */
signal_examp_Y.Out1 = signal_examp_B.sumSig;
UNUSED_PARAMETER(tid);
}

```

When the **Signal storage reuse** option is off, **Reuse block outputs** and **Enable local block outputs** are disabled. This makes the block output signals global and unique, `signal_examp_B.sumSig` and `signal_examp_B.gainSig`, as shown in the following code.

```

/* Model output function */
static void signal_examp_output(int_T tid)
{
    /* Sum: '<Root>/Add' incorporates:
     * Constant: '<Root>/Constant'
     * Inport: '<Root>/In1'
     */
    signal_examp_B.sumSig = signal_examp_U.In1 +
        signal_examp_P.Constant_Value;

    /* Gain: '<Root>/Gain' */
    signal_examp_B.gainSig = signal_examp_B.sumSig *
        signal_examp_P.Gain_Gain;

    /* Output: '<Root>/Out1' */
    signal_examp_Y.Out1 = signal_examp_B.gainSig;
    UNUSED_PARAMETER(tid);
}

```

In large models, disabling **Signal storage reuse** can significantly increase RAM and ROM usage. Therefore, this approach is not recommended for code deployment; however it can be useful in rapid prototyping environments.

The following table summarizes the possible combinations of the **Signal storage reuse/ Reuse block outputs** and **Enable local block outputs** options.

	Signal storage reuse and Reuse block outputs ON	Signal storage reuse OFF (Reuse block outputs disabled)
Enable local block outputs ON	Reuse signals in local memory (fully optimized)	N/A
Enable local block outputs OFF	Reuse signals in <i>model_B</i> structure	Individual signal storage in <i>model_B</i> structure

Controlling Stack Space Allocation

When the **Local block outputs** option is on, the use of stack space by local block output variables is constrained by the following TLC variables:

- **MaxStackSize:** The maximum number of bytes Real-Time Workshop allocates for local variables declared by all block outputs in a model. **MaxStackSize** can be any positive integer. If the total size of local block output variables exceeds this maximum, Real-Time Workshop allocates the remaining block output variables in global, rather than local, memory. The default value for **MaxStackSize** is *Inf*, that is, unlimited stack size.

Note Local variables in the generated code from sources other than local block outputs and stack usage from sources such as function calls and context switching are not included in the **MaxStackSize** calculation. For overall executable stack usage metrics, you should do a target-specific measurement, such as using run-time (empirical) analysis or static (code path) analysis with object code.

- **MaxStackVariableSize:** The maximum number of bytes *n*, where *n* is greater than zero, Real-Time Workshop allocates for any local block output variable declared in the code. Real-Time Workshop allocates any variable with a size that exceeds **MaxStackVariableSize** in global, rather than local, memory. The default is 4096.

You may need to adjust the settings of these variables when working with models that contain large signals. When a variable exceeds `MaxStackVariableSize`, Real-Time Workshop places the variable in global memory space. Similarly, if the accumulated size of variables in local memory exceeds `MaxStackSize`, Real-Time Workshop places subsequent local variables in global memory space. Real-Time Workshop analyzes the accumulated size of local variables based on a worst-case scenario without taking into account that some local variables are released after functions return.

Consider the following options for your specific model:

- Is it important that you maximize potential for signal storage optimization? If so, set `MaxStackSize` appropriately to accommodate the size and number of signals in your model. This minimizes overflow into global memory space and maximizes use of local memory. Local variables offer more optimization potential through mechanisms such as expression folding and buffer reuse.
- Is the accumulated size of local variables exceeding the `MaxStackSize` setting? If so, consider setting `MaxStackVariableSize` to a value that forces large local variables into the global memory space and helps retain smaller local variables in local storage.

See “Setting Target Language Compiler Options” on page 2-79 for more information.

Declaring Test Points

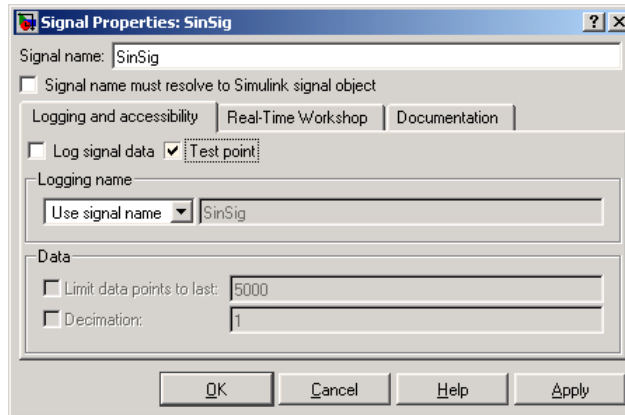
A *test point* is a signal that is stored in a unique location that is not shared or reused by any other signal. *Test-pointing* is the process of declaring a signal to be a test point.

You declare a signal to be a test point as follows:

- 1 Select the signal line by right-clicking it.
- 2 From the context menu that pops up, select **Signal properties**.

Alternatively, after selecting the line that carries the signal, choose **Signal Properties** from the **Edit** menu of your model. This also opens the Signal Properties dialog box.

- 3 On the **Logging and accessibility tab**, select the **Test point** option on the Signal properties dialog box, as shown in the next figure.



- 4 Click **OK** to dismiss the dialog box.

A stemmed-circle icon appears on the signal line to indicate the test point, as shown in the next figure.



Test points are stored as members of the *model_B* structure, even when the **Signal storage reuse** and **Local block outputs** option are selected. Test-pointing lets you override these options for individual signals. Therefore, you can test-point selected signals without losing the benefits of optimized storage for the other signals in your model.

For an example of storage declarations and code generated for a test point, see “Summary of Signal Storage Class Options” on page 5-43.

Interfacing Signals to External Code

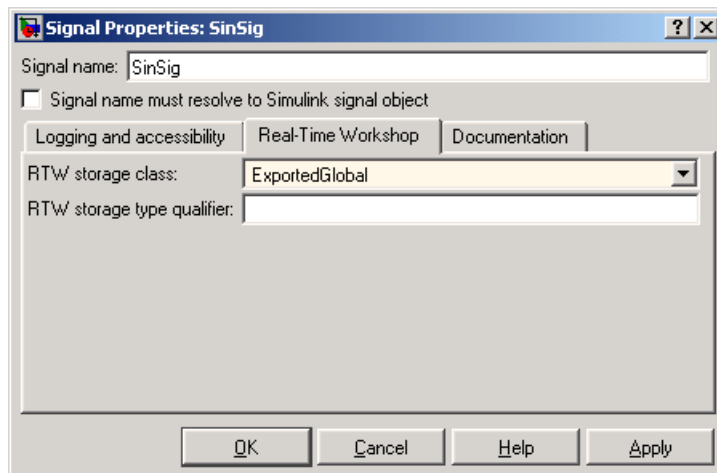
The Simulink Signal Properties dialog box lets you interface selected signals to externally written code. In this way, your hand-written code has access to

such signals for monitoring or other purposes. To interface a signal to external code, use the **Real-Time Workshop** tab of the Signal Properties dialog box to assign one of the following storage classes to the signal:

- ExportedGlobal
- ImportedExtern
- ImportedExternPointer

Set the storage class as follows:

- 1** In your Simulink block diagram, select the line that carries the signal. Then select **Signal Properties** from the **Edit** menu of your model. This opens the Signal Properties dialog box. Alternatively, right-click the line that carries the signal, and select **Signal properties** from the menu.
- 2** Select the **Real-Time Workshop** tab of the Signal Properties dialog box.
- 3** Select the desired storage class (Auto, ExportedGlobal, ImportedExtern, or ImportedExternPointer) from the **RTW storage class** menu. The next figure shows ExportedGlobal selected.



- 4** *Optional:* For storage classes other than Auto, you can enter a storage type qualifier such as `const` or `volatile` in the **RTW storage type qualifier**

field. Real-Time Workshop does not check this string for errors; whatever you enter is included in the variable declaration.

5 Click Apply.

Note You can also interface test points and other signals that are stored as members of *model_B* to your code. To do this, your code must know the address of the *model_B* structure where the data is stored, and other information. This information is not automatically exported. Real-Time Workshop provides C/C++ and Target Language Compiler APIs that give your code access to *model_B* and other data structures. See “C-API for Interfacing with Signals and Parameters” on page 17-2 for more information.

Symbolic Naming Conventions for Signals in Generated Code

When signals have a storage class other than Auto, Real-Time Workshop preserves symbolic information about the signals or their originating blocks in the generated code.

For labeled signals, field names in *model_B* derive from the signal names. In the following example, the field names *model_B.sumSig* and *model_B.gainSig* are derived from the corresponding labeled signals in the *signal_examp* model (shown in figure *Signal_examp Model* on page 5-32).

```
/* Block signals (auto storage) */
typedef struct _BlockIO_signal_examp {
    real_T sumSig;                /* '<Root>/Add' */
    real_T gainSig;              /* '<Root>/Gain' */
} BlockIO_signal_examp;
```

When the optimization **Signal Storage Reuse** is off, *sumSig* is not part of *model_B*, and a local variable is used for it instead. For unlabeled signals, *model_B* field names are derived from the name of the source block or subsystem.

The components of a generated signal label are

- The root model name, followed by
- The name of the generating signal object, followed by
- A unique *name mangling* string (if required)

The number of characters that a signal label can have is limited by the **Maximum identifier length** parameter specified on the **Symbols** pane of the Configuration Parameters dialog box. See “Configuring Generated Identifiers” on page 2-57 for more detail.

When a signal has Auto storage class, Real-Time Workshop controls generation of variable or field names without regard to signal labels.

Summary of Signal Storage Class Options

The next table shows, for each signal storage class option, the variable declaration and the code generated for Sum (sumSig) and Gain (gainSig) block outputs of the model shown in figure Signal_exam Model on page 5-32.

Storage Class	Declaration	Code
Auto (with signal storage reuse optimizations on)	In <i>model.c</i> or <i>model.cpp</i> real_T rtb_sumSig;	<pre>rtb_sumSig = signal_exam_U.In1 + signal_exam_P.Constant_Value; rtb_sumSig *= signal_exam_P.Gain_Gain; signal_exam_Y.Out1 = rtb_sumSig;</pre>

Storage Class	Declaration	Code
Test point (for sumSig only)	<p>In <i>model.h</i></p> <pre>typedef struct _BlockIO_signal_examp { real_T sumSig; } BlockIO_signal_examp;</pre> <p>In <i>model.c</i> or <i>model.cpp</i></p> <pre>BlockIO_signal_examp signal_examp_B; real_T rtb_gainSig;</pre>	<pre>signal_examp_B.sumSig = signal_examp_U.In1 + signal_examp_P.Constant_Value; rtb_gainSig = signal_examp_B.sumSig * signal_examp_P.Gain_Gain; signal_examp_Y.Out1 = rtb_gainSig;</pre>
Exported Global (for sumSig only)	<p>In <i>model.c.cpp.h</i></p> <pre>extern real_T sumSig;</pre> <p>In <i>model</i></p> <pre>real_T sumSig; real_T rtb_gainSig;</pre>	<pre>sumSig = signal_examp_U.In1 + signal_examp_P.Constant_Value; rtb_gainSig = sumSig * signal_examp_P.Gain_Gain; signal_examp_Y.Out1 = rtb_gainSig;</pre>
Imported Extern	<p>In <i>model_private.h</i></p> <pre>extern real_T sumSig;</pre> <p>In <i>model.c</i> or <i>model.cpp</i></p> <pre>real_T rtb_gainSig;</pre>	<pre>sumSig = signal_examp_U.In1 + signal_examp_P.Constant_Value; rtb_gainSig = sumSig * signal_examp_P.Gain_Gain; signal_examp_Y.Out1 = rtb_gainSig;</pre>
Imported Extern Pointer	<p>In <i>model_private.h</i></p> <pre>extern real_T *sumSig;</pre> <p>In <i>model.c</i> or <i>model.cpp</i></p> <pre>real_T rtb_gainSig;</pre>	<pre>(*sumSig) = signal_examp_U.In1 + signal_examp_P.Constant_Value; rtb_gainSig = (*sumSig) * signal_examp_P.Gain_Gain; signal_examp_Y.Out1 = rtb_gainSig;</pre>

Parameter Tuning and Signal Monitoring

In this section...

“Introduction” on page 5-45

“Using the C-API to Tune Parameters and Monitor Signals” on page 5-45

“Using the Target Language Compiler API to Tune Parameters and Monitor Signals” on page 5-45

Introduction

This section describes how to tune parameters and monitor signals in Real-Time Workshop.

Using the C-API to Tune Parameters and Monitor Signals

Real-Time Workshop includes a C application program interface (API) for tuning parameters and monitoring signals independent of external mode. See “C-API for Interfacing with Signals and Parameters” on page 17-2 for information.

Using the Target Language Compiler API to Tune Parameters and Monitor Signals

Real-Time Workshop includes support for development of a Target Language Compiler API for tuning parameters and monitoring signals independent of external mode. See “Target Language Compiler API for Signals and Parameters” on page 17-21 for information.

Simulink Data Objects and Code Generation

In this section...

“Introduction” on page 5-46

“Parameter Objects” on page 5-47

“Parameter Object Configuration Quick Reference Diagram” on page 5-54

“Signal Objects” on page 5-55

“Using Signal Objects to Initialize Signals and Discrete States” on page 5-60

“Resolving Conflicts in Configuration of Parameter and Signal Objects”
on page 5-69

“Customizing Code for Parameter and Signal Objects” on page 5-71

“Using Objects to Export ASAP2 Files” on page 5-71

Introduction

Before using Simulink data objects with Real-Time Workshop, read the following:

- The discussion of Simulink data objects in the Simulink documentation
- “Parameter Storage, Interfacing, and Tuning” on page 5-2
- “Signal Storage, Optimization, and Interfacing” on page 5-31

Within the class hierarchy of Simulink data objects, Simulink provides two classes that are designed as base classes for signal and parameter storage:

- `Simulink.Parameter`: Objects that are instances of the `Simulink.Parameter` class or any class derived from `Simulink.Parameter` are called *parameter objects*.
- `Simulink.Signal`: Objects that are instances of the `Simulink.Signal` class or any class derived from `Simulink.Signal` are called *signal objects*.

The `RTWInfo` properties of parameter and signal objects are used by Real-Time Workshop during code generation. These properties let you assign storage

classes to the objects, thereby controlling how the generated code stores and represents signals and parameters.

Real-Time Workshop also writes information about the properties of parameter and signal objects to the `model.rtw` file. This information, formatted as Object records, is accessible to Target Language Compiler programs. For general information on Object records, see the Target Language Compiler documentation.

The general procedure for using Simulink data objects in code generation is as follows:

- 1 Define a subclass of one of the built-in `Simulink.Data` classes.
 - For parameters, define a subclass of `Simulink.Parameter`.
 - For signals, define a subclass of `Simulink.Signal`.
- 2 Instantiate parameter or signal objects from your subclass and set their properties appropriately, from the command line or using Model Explorer.
- 3 Use the objects as parameters or signals within your model.
- 4 Generate code and build your target executable.

The following sections describe the relationship between Simulink data objects and code generation in Real-Time Workshop.

Parameter Objects

This section discusses how to use parameter objects in code generation.

Configuring Parameter Objects for Code Generation

In configuring parameter objects for code generation, you use the following code generation and parameter object properties:

- The **Inline parameters** option (see “Parameter Storage, Interfacing, and Tuning” on page 5-2).
- Parameter object properties:

- **Value.** The numeric value of the object, used as an initial (or inlined) parameter value in generated code.
- **DataType.** The data type of the object. This can be any Simulink numeric data type, including a fixed-point, user-defined, or alias data type.
- **RTWInfo.StorageClass.** Controls the generated storage declaration and code for the parameter object.

Other parameter object properties (such as user-defined properties of classes derived from `Simulink.Parameter`) do not affect code generation.

Note If **Inline parameters** is off (the default), the `RTWInfo.StorageClass` parameter object property is ignored in code generation.

Effect of Storage Classes on Code Generation for Parameter Objects

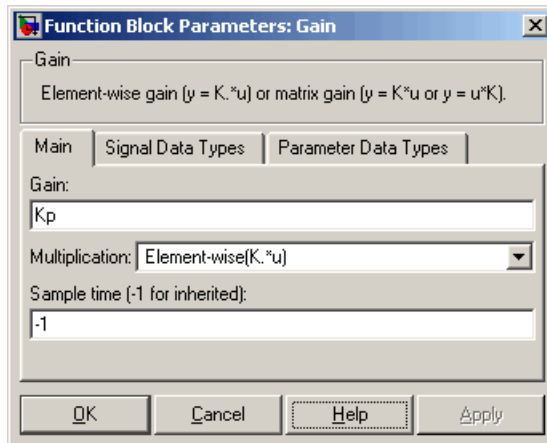
Real-Time Workshop generates code and storage declarations based on the `RTWInfo.StorageClass` property of the parameter object. The logic is as follows:

- If the storage class is 'Auto' (the default), the parameter object is inlined (if possible), using the `Value` property.
- For storage classes other than 'Auto', the parameter object is handled as a tunable parameter.
 - A global storage declaration is generated. You can use the generated storage declaration to make the variable visible to your hand-written code. You can also make variables declared in your hand-written code visible to the generated code.
 - The symbolic name of the parameter object is generally preserved in the generated code.

See the table in “Controlling Parameter Object Code Generation By Using Model Explorer” on page 5-50 for examples of code generated for possible settings of `RTWInfo.StorageClass`.

Controlling Parameter Object Code Generation with Typed Commands

In this section, the Gain block computations of the model shown in the next figure are used as an example of how Real-Time Workshop generates code for a parameter object.



Model Using Parameter Object Kp As Block Parameter

In this model, Kp sets the gain of the Gain block.

To configure a parameter object such as Kp for code generation,

- 1 Instantiate a Simulink.Parameter object called Kp. In this example, the parameter object is an instance of the example class SimulinkDemos.Parameter, which is provided with Simulink.

```
Kp = Simulink.Parameter
Kp =
Simulink.Parameter
    RTWInfo: [1x1 Simulink.ParamRTWInfo]
    Description: ''
    DocUnits: ''
    Min: -Inf
    Max: Inf
    Value: 5
    DataType: 'auto'
```

```
Complexity: 'real'  
Dimensions: '[1x1]'
```

Make sure that the name of the parameter object matches the desired block parameter in your model. This ensures that Simulink can associate the parameter name with the correct object. In the preceding model, the Gain block parameter Kp resolves to the parameter object Kp.

- 2 Set the object properties you need. You can do this by using the Model Explorer, or you can assign properties by using MATLAB commands, as follows:

- To specify the Value property, type

```
Kp.Value = 5.0;
```

- To specify the storage class of for the parameter, set the RTWInfo.StorageClass property, for example:

```
Kp.RTWInfo.StorageClass = 'ExportedGlobal';
```

The RTWInfo parameters are now

```
Kp.RTWInfo  
Simulink.ParamRTWInfo  
    StorageClass: 'ExportedGlobal'  
    Alias: ''  
    CustomStorageClass: 'Default'  
    CustomAttributes: [1x1  
    SimulinkCSC.AttribClass_Simulink_Default]
```

Controlling Parameter Object Code Generation By Using Model Explorer

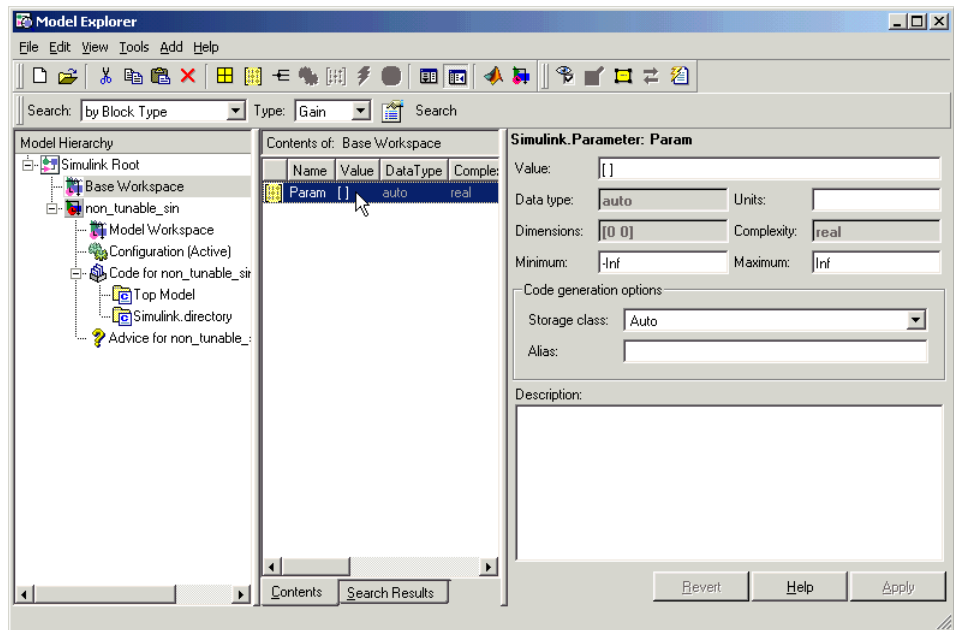
If you prefer, you can create and modify attributes of parameter objects using Model Explorer. This lets you see all attributes of a parameter in a dialog box, and alleviates the need to remember and type field names. Do the following to instantiate Kp and set its attributes from Model Explorer:

- 1 Choose **Model Explorer** from the View menu.

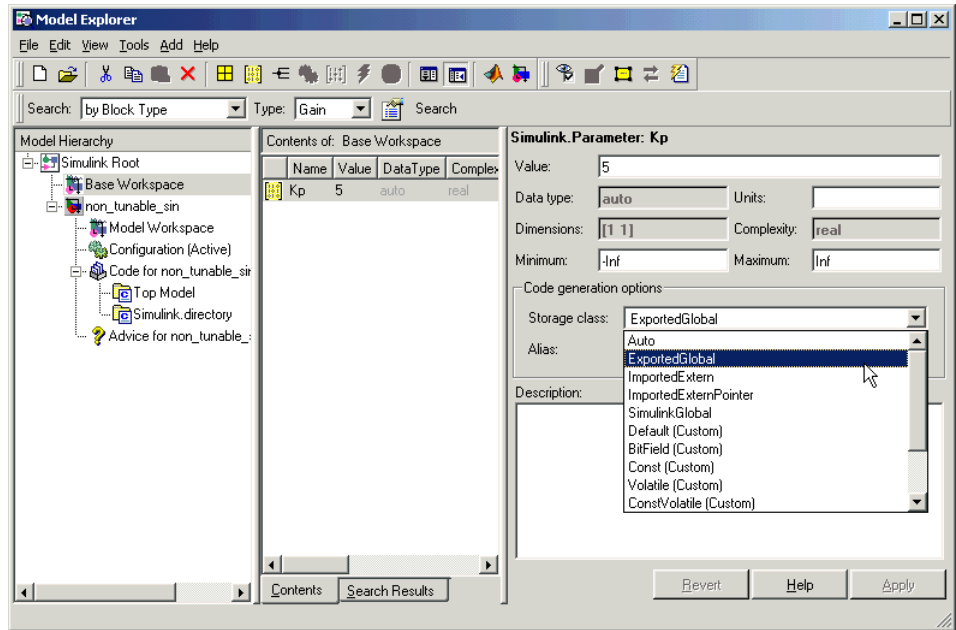
Model Explorer opens or activates if it already was open.

- 2 Select Base Workspace in the **Model Hierarchy** pane.
- 3 Select **Simulink Parameter** from the **Add** menu (or type **Ctrl+R**)

A new parameter named Param appears in the **Contents** pane.



- 4 To set `Kp.Name` in Model Explorer, click the word `Param` in the **Name** column to select it, and rename it by typing `Kp` followed by **Return** in place of `Param`.
- 5 To set `Kp.Value` in Model Explorer, select the **Value** field at the top of the **Dialog** pane and type `5.0`, then click the **Apply** button.
- 6 To set the `Kp.RTWInfo.StorageClass` in Model Explorer, click the **Storage class** menu and select `ExportedGlobal`, as shown in the next figure.



7 Click Apply.

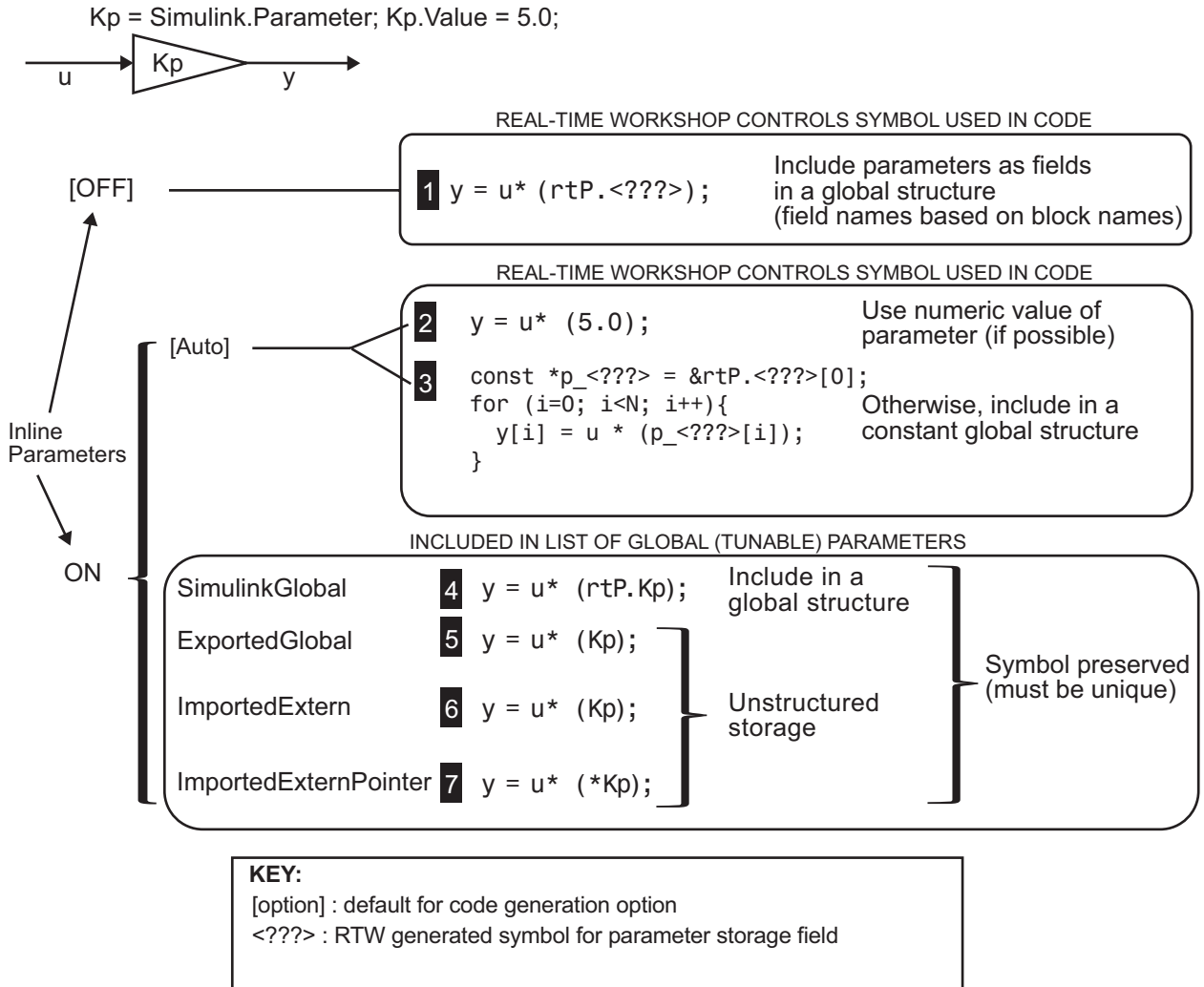
The following table shows the variable declarations for Kp and the code generated for the Gain block in the model shown in the preceding model, with **Inline parameters** on and **expression folding** on (which includes the gain computation in the output computation). An example is shown for each possible setting of RTWInfo.StorageClass. Global structures include the model name (symbolized as *model_* or *_model*).

StorageClass Property	Generated Variable Declaration and Code
Auto	<pre>model_Y.Out1 = rtb_u * 5.0;</pre>

StorageClass Property	Generated Variable Declaration and Code
Simulink Global	<pre> struct _Parameters_model { real_T Kp; } . . Parameters_model model_P = { 5.0 }; . . model_Y.Out1 = rtb_u * model_P.Kp; </pre>
Exported Global	<pre> extern real_T Kp; . . real_T Kp = 5.0; . . model_Y.Out1 = rtb_u * Kp; </pre>
Imported Extern	<pre> extern real_T Kp; . . model_Y.Out1 = rtb_u * Kp; </pre>
Imported Extern Pointer	<pre> extern real_T *Kp; . . model_Y.Out1 = rtb_u * (*Kp); </pre>

Parameter Object Configuration Quick Reference Diagram

The next figure shows the code generation and storage class options that control the representation of parameter objects in generated code.



Signal Objects

This section discusses how to use signal objects in code generation. Signal objects can be used to represent both signal and state data, and behave similarly to parameter objects, described in “Parameter Objects” on page 5-47.

Configuring Signal Objects for Code Generation

In configuring signal objects for code generation, you use the following code generation options and signal object properties:

- The **Signal storage reuse** code generation option (see “Signal Storage, Optimization, and Interfacing” on page 5-31).
- The **Enable local block outputs** code generation option (see “Signal Storage, Optimization, and Interfacing” on page 5-31).
- The `RTWInfo.StorageClass` signal object property: The storage classes defined for signal objects, and their effect on code generation, are the same for model signals and signal objects (see “Signals Storage Classes” on page 5-33).

Other signal object properties (such as user-defined properties of classes derived from `Simulink.Signal`) do not affect code generation.

Effect of Storage Classes on Code Generation for Signal Objects

The way in which Real-Time Workshop uses storage classes to determine how signals are stored is the same with and without signal objects. However, if a signal’s label resolves to a signal object, the object’s `RTWInfo.StorageClass` property is used in place of the port configuration of the signal.

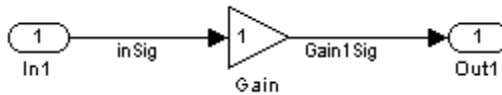
The default storage class is `Auto`. If the storage type is `Auto`, Real-Time Workshop follows the **Signal storage reuse**, **Buffer reuse**, and **Local block outputs** code generation options to determine whether signal objects are stored in reusable and/or local variables. Make sure that these options are set correctly for your application.

To generate a test point or signal storage declaration that can interface externally, use an explicit `RTWInfo.StorageClass` assignment. For example, setting the storage class to `SimulinkGlobal`, as in the following command, is equivalent to declaring a signal as a test point.

```
SinSig.RTWInfo.StorageClass = 'SimulinkGlobal';
```

Controlling Signal Object Code Generation By Using Typed Commands

The discussion and code examples in this section refers to the model shown in the next figure.



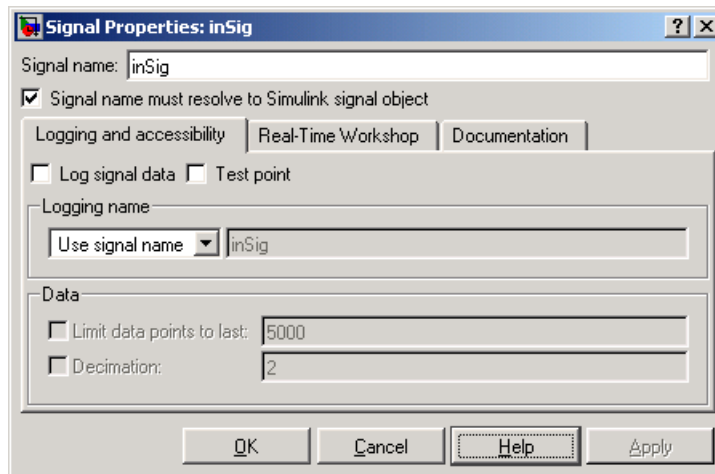
To configure a signal object, you must first create it and associate it with a labeled signal in your model. To do this,

- 1 Define a subclass of `Simulink.Signal`. In this example, the signal object is an instance of the class `Simulink.Signal`, which is provided with `Simulink`.
- 2 Instantiate a signal object from your subclass. The following example instantiates `inSig`, a signal object of class `Simulink.Signal`.

```
inSig = Simulink.Signal
inSig =
Simulink.Signal
    RTWInfo: [1x1 Simulink.SignalRTWInfo]
    Description: ''
    DocUnits: ''
    Min: -Inf
    Max: Inf
    DataType: 'auto'
    Dimensions: -1
    Complexity: 'auto'
    SampleTime: -1
    SamplingMode: 'auto'
```

Make sure that the name of the signal object matches the label of the desired signal in your model. This ensures that Simulink can resolve the signal label to the correct object. For example, in the model shown in the above figure, the signal label `inSig` would resolve to the signal object `inSig`.

- 3** You can require signals in a model to resolve to Simulink.Signal objects. To do this for the signal `inSig`, in the model window right-click the signal line labeled `inSig` and choose **Signal Properties** from the context menu. A Signal Properties dialog appears.



- 4** In the Signal Properties dialog box that appears, select the check box labelled **Signal name must resolve to Simulink signal object**, and click **OK** or **Apply**.
- 5** Set the object properties as required. You can do this by using the Simulink Data Explorer. Alternatively, you can assign properties by using MATLAB commands. For example, assign the signal object's storage class by setting the `RTWInfo.StorageClass` property as follows.

```
inSig.RTWInfo.StorageClass = 'ExportedGlobal';
```

Controlling Signal Object Code Generation By Using Model Explorer

If you prefer, you can create signal objects and modify their attributes using Model Explorer. This lets you see and set attributes of a signal in a dialog box pane, and alleviates the need to remember and type field names. Do the following to instantiate `inSig` and set its attributes from Model Explorer:

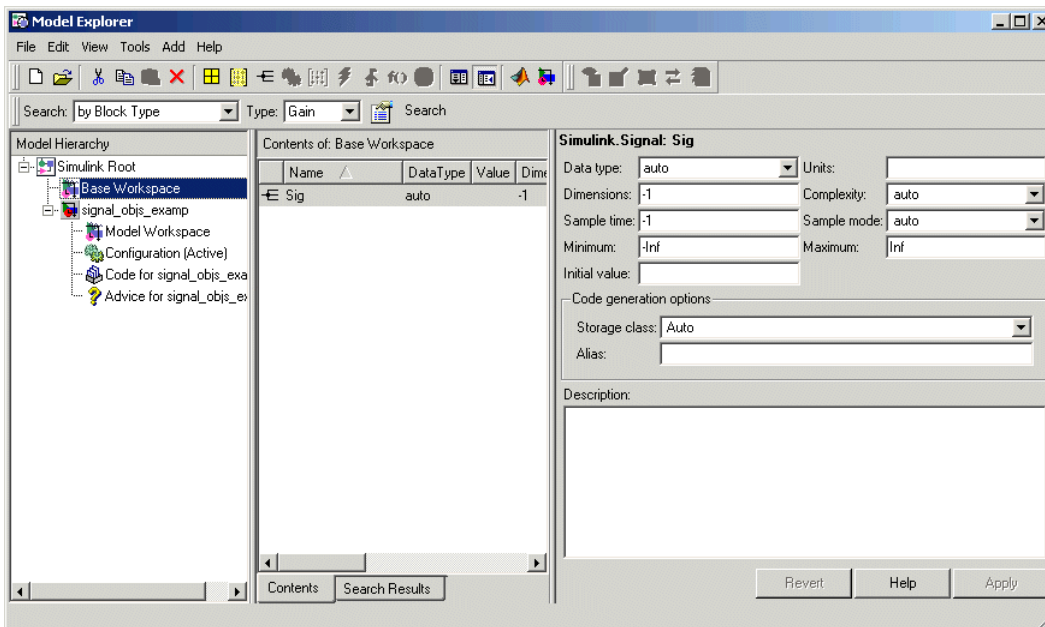
1 Choose **Model Explorer** from the View menu.

Model Explorer opens or activates if it already was open.

2 Select Base Workspace in the **Model Hierarchy** pane.

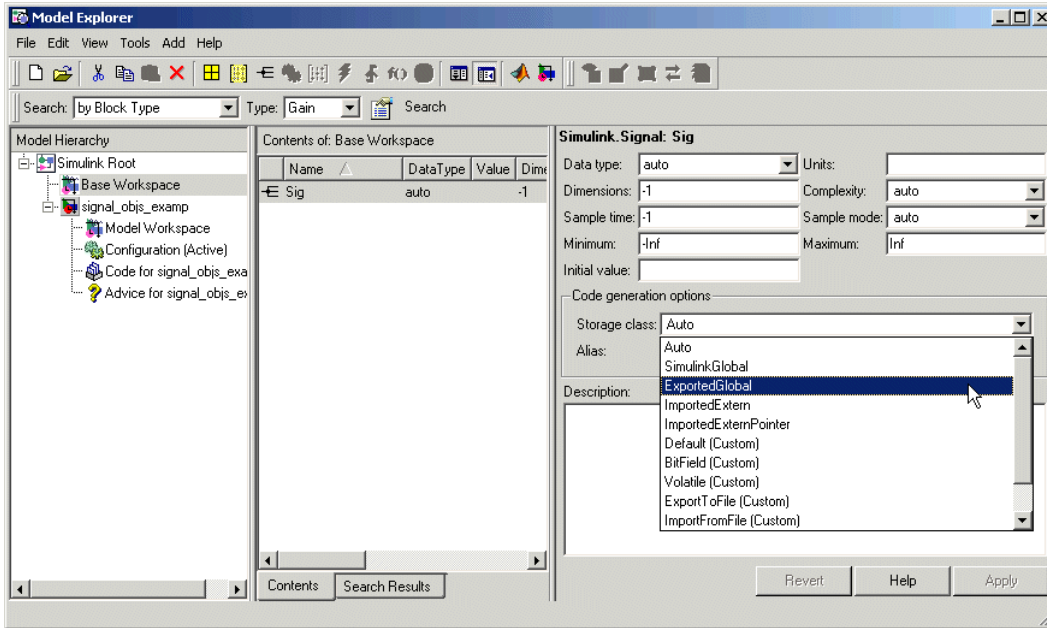
3 Select **Simulink Signal** from the **Add** menu (or type **Ctrl+S**)

A new signal named Sig appears in the **Contents** pane.



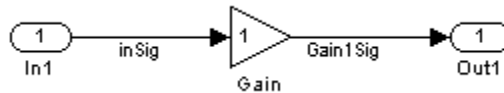
4 To set the signal name in Model Explorer, click the word Sig in the **Name** column to select it, and rename it by typing `inSig` followed by **Return** in place of Sig.

5 To set the `inSig.RTWInfo.StorageClass` in Model Explorer, click the **Storage class** menu and select `ExportedGlobal`, as shown in the next figure.



6 Click Apply.

The following table shows, for each setting of RTWInfo.StorageClass, the variable declaration and the code generated for the inport signal (inSig) of the current model:



Storage Class	Declaration	Code
Auto (with storage optimizations on)	In <i>model.h</i> <pre>typedef struct _ExternalInputs_signal_objs_examp_tag { real_T inSig; } ExternalInputs_signal_objs_examp;</pre>	<pre>rtb_Gain1Sig = signal_objs_examp_U.inSig * signal_objs_examp_P.Gain_Gain;</pre>
Simulink Global	In <i>model.h</i> <pre>typedef struct _ExternalInputs_signal_objs_examp_tag { real_T inSig; } ExternalInputs_signal_objs_examp;</pre>	<pre>rtb_Gain1Sig = signal_objs_examp_U.inSig * signal_objs_examp_P.Gain_Gain;</pre>
Exported Global	In <i>model.c</i> or <i>model.cpp</i> <pre>real_T inSig;</pre> In <i>model.h</i> <pre>extern real_T inSig;</pre>	<pre>rtb_Gain1Sig = inSig * signal_objs_examp_P.Gain_Gain;</pre>
Imported Extern	In <i>model_private.h</i> <pre>extern real_T inSig;</pre>	<pre>rtb_Gain1Sig = inSig * signal_objs_examp_P.Gain_Gain;</pre>
Imported Extern Pointer	In <i>model_private.h</i> <pre>extern real_T *inSig;</pre>	<pre>rtb_Gain1Sig = (*inSig) * signal_objs_examp_P.Gain_Gain;</pre>

Using Signal Objects to Initialize Signals and Discrete States

You can use Simulink signal objects to initialize signals and discrete states with user-defined values for simulation and code generation. Data initialization increases application reliability and is a requirement of safety

critical applications. Initializing signals for both simulation and code generation can expedite transitions between phases of Model-Based Design.

For details on simulation behavior, see “Initialization Behavior Summary for Signal Objects” in the Simulink documentation.

Specifying an Initial Value for a Signal Object

You can use signal objects that have a storage class other than 'auto' or 'SimulinkGlobal' to initialize

- Discrete states with an initial condition parameter
- Any signals in a model except bus signals and signals with constant sample time

The initial value is the signal or state value before a simulation takes its first time step.

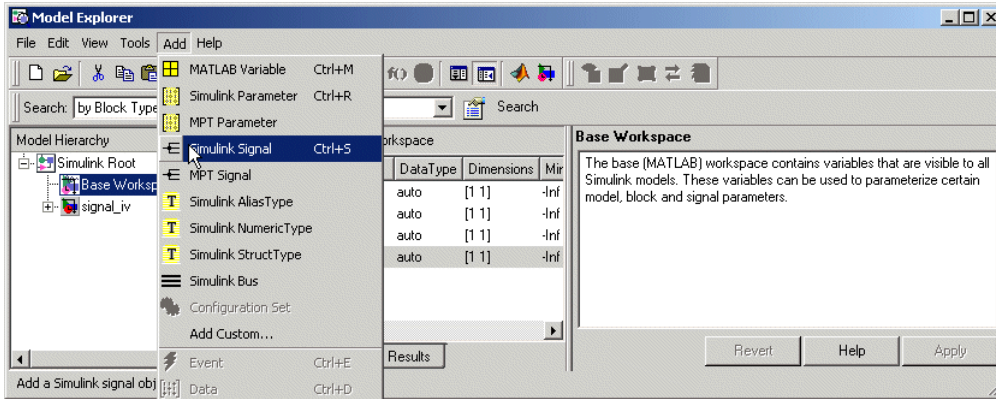
Note Initial value settings for signal objects that represent the following signals and states override the corresponding block parameter initial values if undefined (specified as []):

- Output signals of conditionally executed subsystems and Merge blocks
 - Block states
-

To specify an initial value, use the Model Explorer or MATLAB commands to do the following:

- 1 Create the signal object.

Model Explorer



MATLAB Command

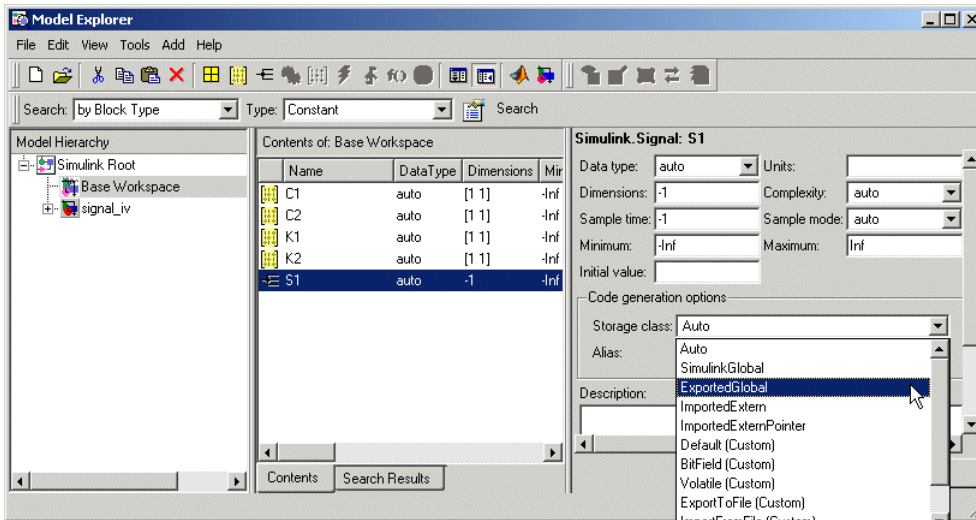
```
S1=Simulink.Signal;
```

The name of the signal object must be the same as the name of the signal that the object is initializing. Although not required, consider setting the **Signal name must resolve to Simulink signal object** option in the Signal Properties dialog box. This setting ensures consistency between signal objects in the MATLAB workspace and the signals that appear in your model.

Consider using the Data Object Wizard to create signal objects. The Data Object Wizard searches a model for signals for which signal objects do not exist. You can then selectively create signal objects for multiple signals listed in the search results with a single operation. For more information about the Data Object Wizard, see “Data Object Wizard” in the Simulink documentation.

- 2 Set the signal object's storage class to a value other than 'auto' or 'SimulinkGlobal'.

Model Explorer



MATLAB Command

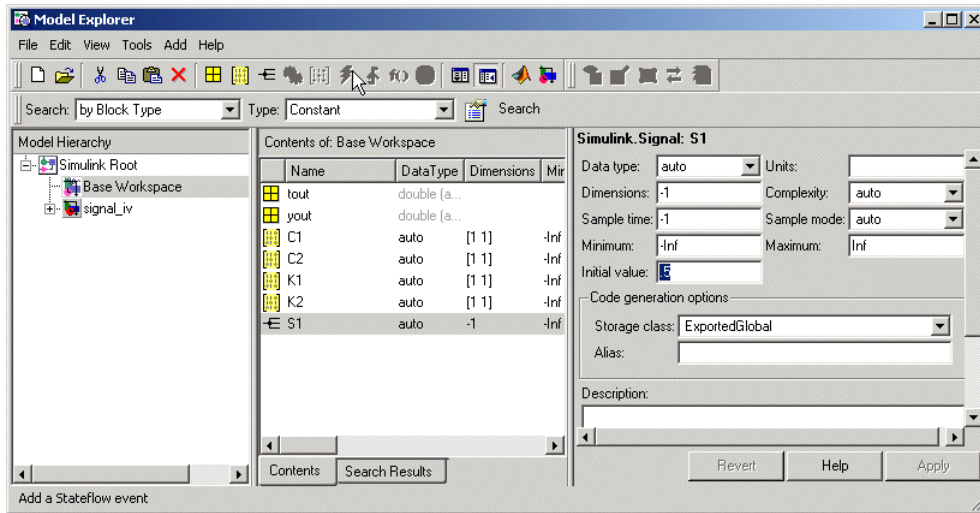
```
S1.RTWInfo.StorageClass='ExportedGlobal';
```

- Set the initial value. You can specify any MATLAB string expression that evaluates to a double numeric scalar value or array.

	Model Explorer	MATLAB Command
Valid	1.5 [1 2 3] 1+0.5	foo = 1.5; s1.InitialValue = 'foo';
Invalid	uint(1)	foo = '1.5'; s1.InitialValue = 'foo';

If necessary, Simulink converts the initial value to ensure type, complexity, and dimension consistency with the corresponding block parameter value. If you specify an invalid value or expression, an error message appears when you update the model.

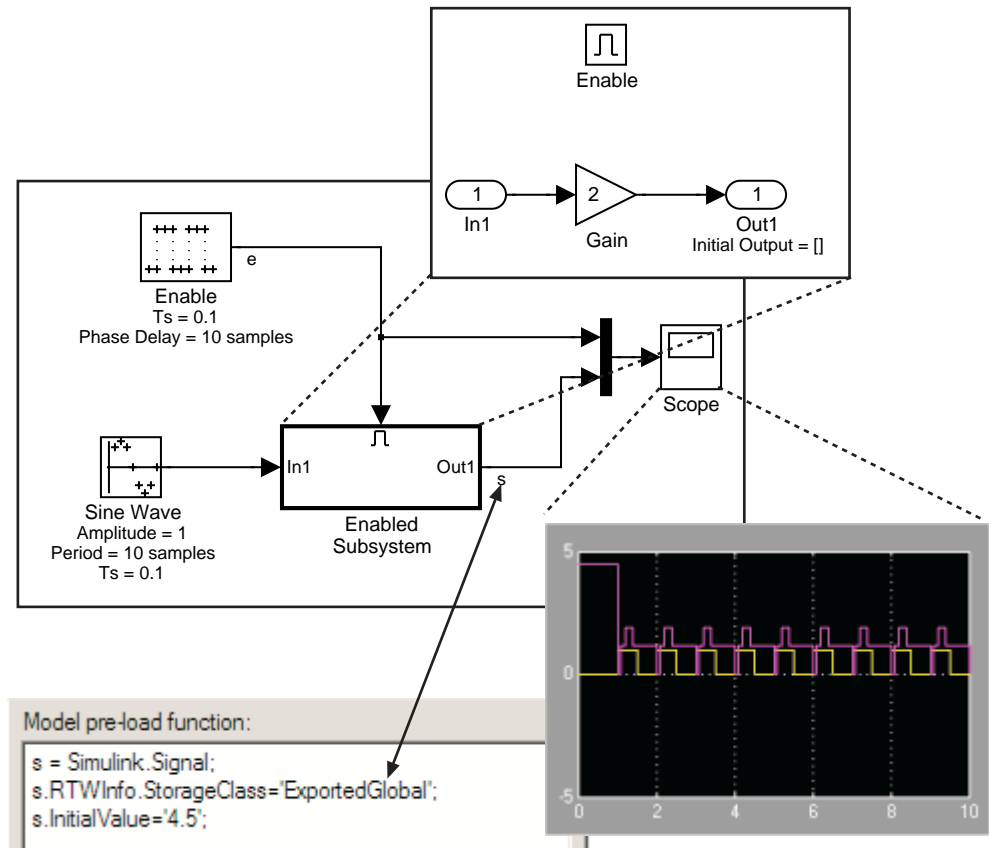
Model Explorer



MATLAB Command

```
S1.InitialValue='0.5'
```

The following example shows a signal object specifying the initial output of an enabled subsystem.



Signal s is initialized to 4.5. Note that to avoid a consistency error, the initial value of the enabled subsystem's Output block must be $[]$ or 4.5.

Signal Object Initialization in Generated Code

The initialization behavior for code generation is the same as that for model simulation with the following exceptions:

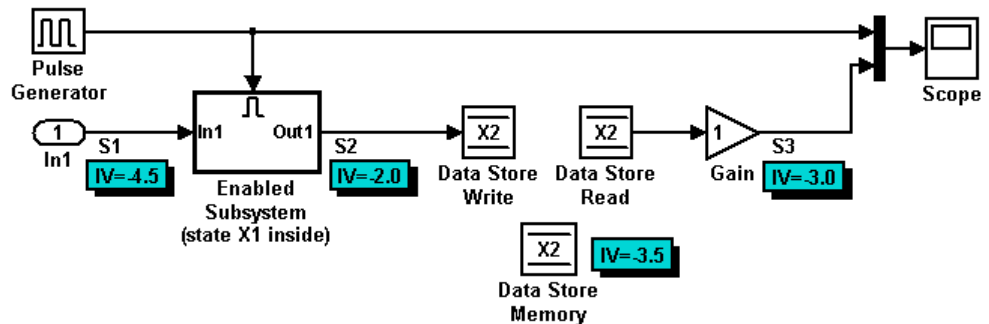
- Use of the **Data Import/Export** pane of the Configuration Parameters dialog box to load input values from the model's base workspace applies to RSim target executables only. GRT and ERT targets cannot gain access to input values in the base workspace.

- The initial value for a block output signal or root level input or output signal can be overwritten by an external (calling) program.
- Setting the initial value for persistent signals is relevant if the value is used or viewed by an external application.

For details on initialization behavior for different types of signals and discrete states, see “Initialization Behavior Summary for Signal Objects” in the Simulink documentation.

When you initialize Simulink signal objects in a model during code generation, the corresponding initialization statements are placed in *model.c* or *model.cpp* in the model’s initialize code.

For example, consider the demo model *rtwdemo_sigobj_iv*.



If you create and initialize signal objects in the base workspace, Real-Time Workshop places initialization code for the signals in the file *rtwdemo_sigobj_iv.c* under the *rtwdemo_sigobj_iv_initialize* function, as shown below.

```

/* Model initialize function */

void rtwdemo_sigobj_iv_initialize(boolean_T firstTime)
{
    .
    .
    .
}

```

```

/* exported global signals */
S3 = -3.0;

S2 = -2.0;
    .
    .
    .
/* exported global states */
X1 = 0.0;
X2 = 0.0;

/* external inputs */
S1 = -4.5;
    .
    .
    .

```

The following code shows the initialization code for the enabled subsystem's Unit Delay block state X1 and output signal S2.

```

void Md1Start(void) {
    .
    .
    .
/* InitializeConditions for UnitDelay: '<S2>/Unit Delay' */
X1 = aa1;

/* Start for enable system: '<Root>/Enabled Subsystem (state X1 inside)' */

/* virtual outports code */

/* (Virtual) Output Block: '<S2>/Out1' */

S2 = aa2;

}

```

Also note that for an enabled subsystem, such as the one shown in the preceding model, the initial value is also used as a reset value if the subsystem's Output block parameter **Output when disabled** is set

to reset. The following code from `rtwdemo_sigobj_iv.c` shows the assignment statement for S3 as it appears in the model output function `rtwdeni_sigobj_iv_output`.

```
/* Model output function */

static void rtwdemo_sigobj_iv_output(void)
{
    .
    .
    .
    /* Disable for enable system: '<Root>/Enabled Subsystem (state X1 inside)' */

    /* (Virtual) Output Block: '<S2>/Out1' */

    S2 = aa2;
```

Tunable Initial Values

If you specify a tunable parameter in the initial value for a signal object, the parameter expression is preserved in the initialization code in `model.c`.

For example, if you configure parameter `df` to be tunable for model `signal_iv` and you initialize the signal object for discrete state X1 with the expression `df*2`, the following initialization code appears for signal object X1 in `signal_iv.c`.

```
void MdlInitialize(void) {

    /* InitializeConditions for UnitDelay: '<Root>/Unit Delay X1=2' */
    X1 = (tunable_param_P.df * 2.0);
}
```

For more information about the treatment of tunable parameters in generated code, see “Parameter Storage, Interfacing, and Tuning” on page 5-2.

Resolving Conflicts in Configuration of Parameter and Signal Objects

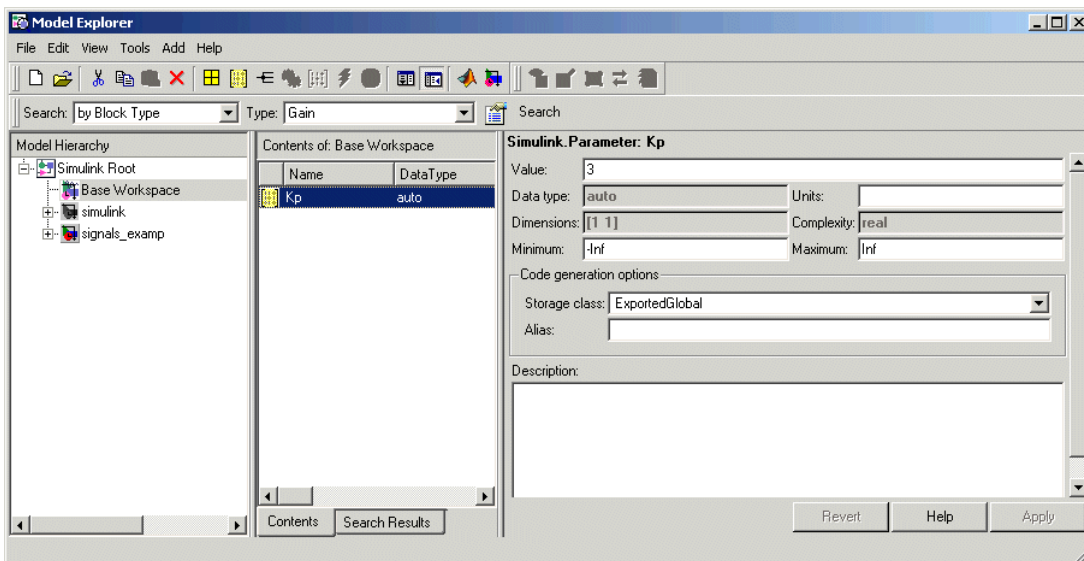
This section describes how to avoid and resolve certain conflicts that can arise when using parameter and signal objects.

Parameters

As explained in “Simulink Data Objects and Code Generation” on page 5-46 and “Using the Model Parameter Configuration Dialog Box” on page 5-10, two methods are available for controlling the tunability of parameters. You can

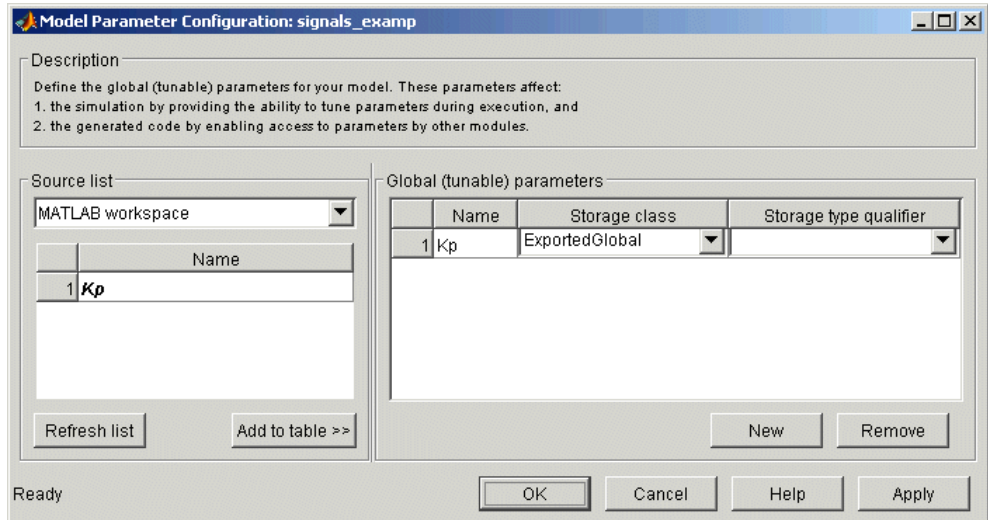
- Define them as `Simulink.Parameter` objects in the MATLAB workspace
- Use the Model Parameter Configuration dialog box

The next figures show how you can use each of these methods to control the tunability of parameter `Kp`. The first figure shows `Kp` defined as `Simulink.Parameter` in the Model Explorer. You control the tunability of `Kp` by specifying the parameter’s storage class.



Parameter Object `Kp` with Auto Storage Class in Model Explorer

The next figure shows how you can use the Model Parameter Configuration dialog box to specify a storage class for numeric variables in the MATLAB workspace.

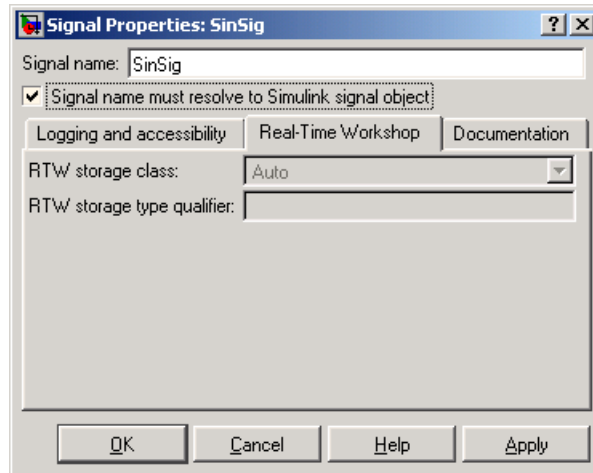


Parameter Kp Defined with SimulinkGlobal Storage Class

Note The MathWorks recommends that you not use both methods for controlling the tunability of a given parameter. If you use both methods and the storage class settings for the parameter do not match, an error results.

Signals and Block States

If a signal is defined in the Signal Properties dialog box and a signal object of the same name is defined by using the command line or in Model Explorer, the potential exists for ambiguity when Simulink attempts to resolve the symbol representing the signal name. One way to resolve the ambiguity is to specify that a signal must resolve to a Simulink data object. To do this, select the **Signal name must resolve to Simulink signal object** option in the Signal Properties dialog box. When you do this, you no longer can specify the **RTW storage class** property in the **Real-Time Workshop** pane of the Signal Properties dialog box, as the next figure shows.



As the preceding figure shows, the **RTW storage class** menu is disabled because it is up to the SinSig Simulink.Signal object to specify its own storage class.

The signal and signal objects SinSig both have SimulinkGlobal storage class. Therefore, no conflict arises, and SinSig resolves to the signal object SinSig.

Note The rules for compatibility between block states/signal objects are identical to those given for signals/signal objects.

Customizing Code for Parameter and Signal Objects

You can influence the treatment of parameter and signal objects in generated code by using TLC to access fields in object records in *model.rtw* files. For details on doing this, see the Target Language Compiler documentation.

Using Objects to Export ASAP2 Files

Real-Time Workshop provides an interface for exporting ASAP2 files, which you customize. For details, see Appendix B, “Generating ASAP2 Files”.

Block State Storage and Interfacing

In this section...
“Introduction” on page 5-72
“Block State Storage” on page 5-72
“Block State Storage Classes” on page 5-73
“Using the State Properties Dialog Box to Interface States to External Code” on page 5-74
“Symbolic Names for Block States” on page 5-76
“Block States and Simulink Signal Objects” on page 5-79
“Summary of State Storage Class Options” on page 5-80

Introduction

For certain block types, Real-Time Workshop lets you control how block states in your model are stored and represented in the generated code. Using the **State properties** tab of a block dialog box, you can

- Control whether or not states declared in generated code are interfaceable (visible) to externally written code. You can also specify that states are to be stored in locations declared by externally written code.
- Assign symbolic names to block states in generated code.

Block State Storage

The discussion of block state storage in this section applies to the following block types:

- Discrete Filter
- Discrete State-Space
- Discrete-Time Integrator
- Discrete Transfer Function
- Discrete Zero-Pole

- Memory
- Unit Delay

These block types require persistent memory to store values representing the state of the block between consecutive time intervals. By default, such values are stored in a *data type work vector*. This vector is usually referred to as the DWork vector. It is represented in generated code as *model_DWork*, a global data structure. For more information on the DWork vector, see the Target Language Compiler documentation.

If you want to interface a block state to your hand-written code, you can specify that the state is to be stored in a location other than the DWork vector. You do this by assigning a storage class to the block state.

You can also define a symbolic name, to be used in code generation, for a block state.

Block State Storage Classes

The storage class property of a block state specifies how Real-Time Workshop declares and stores the state in a variable. Storage class options for block states are similar to those for signals. The available storage classes are

- Auto
- ExportedGlobal
- ImportedExtern
- ImportedExternPointer

Default Storage Class

Auto is the default storage class. Auto is the appropriate storage class for states that you do not need to interface to external code. States with Auto storage class are stored as members of the Dwork vector.

You can assign a symbolic name to states with Auto storage class. If you do not supply a name, Real-Time Workshop generates one, as described in “Symbolic Names for Block States” on page 5-76.

Explicitly Assigned Storage Classes

Block states with storage classes other than Auto are stored in unstructured global variables, independent of the Dwork vector. These storage classes are appropriate for states that you want to interface to external code. The following storage classes are available for states:

- **ExportedGlobal:** The state is stored in a global variable. *model.h* exports the variable. States with ExportedGlobal storage class must have unique names.
- **ImportedExtern:** *model_private.h* declares the state as an extern variable. Your code must supply the proper variable definition. States with ImportedExtern storage class must have unique names.
- **ImportedExternPointer:** *model_private.h* declares the state as an extern pointer. Your code must supply the proper pointer variable definition. States with ImportedExternPointer storage class must have unique names.

The table in “Summary of Signal Storage Class Options” on page 5-43 gives examples of variable declarations and the code generated for block states with each type of storage class.

Note Assign a symbolic name to states to specify a storage class other than auto. If you do not supply a name for auto states, Real-Time Workshop generates one, as described in “Symbolic Names for Block States” on page 5-76.

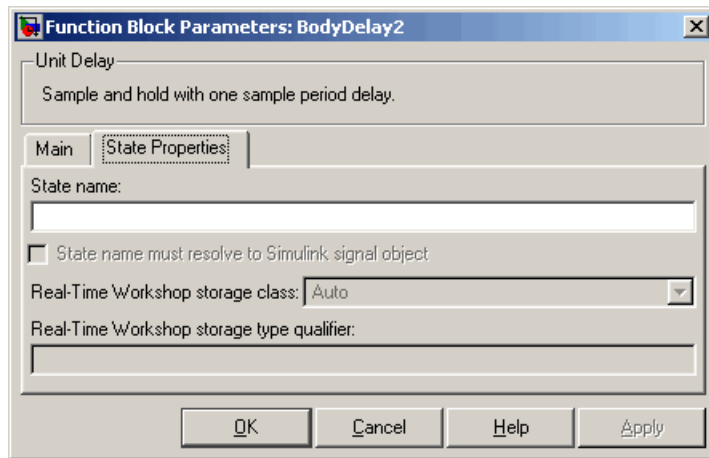
The next section explains how to use the State Properties dialog box to assign storage classes to block states.

Using the State Properties Dialog Box to Interface States to External Code

The **State Properties** tab of the relevant blocks’ parameter dialog boxes lets you interface a block’s state to external code by assigning the state a storage class other than Auto (that is, ExportedGlobal, ImportedExtern, or ImportedExternPointer).

Set the storage class as follows:

- 1 In your block diagram, double-click the desired block. This opens the block dialog box containing two or more tabs, one of which is **State properties**. Alternatively, you can right-click the block and select **Block properties** from the context menu.
- 2 Click the **State Properties** tab. The State Properties dialog appears.



- 3 Enter a name for the variable to be used to store block state in the **State name** field.

The **State name** field turns yellow to indicate that you changed it.

- 4 Click **Apply** to register the variable name.

The first two fields beneath the **State name**, **State name must resolve to Simulink signal object** and **RTW storage class**, become enabled.

- 5 If the state is to be stored in a Simulink signal object in the base or model workspace, select **State name must resolve to Simulink signal object**.

If you choose this option, you cannot declare a storage class for the state in the block, and the fields below becomes disabled.

- 6** Select the desired storage class (ExportedGlobal, ImportedExtern, or ImportedExternPointer) from the **RTW storage class** menu.
- 7** *Optional:* For storage classes other than Auto, you can enter a storage type qualifier such as `const` or `volatile` in the **RTW storage type qualifier** field. Real-Time Workshop does not check this string for errors; whatever you enter is included in the variable declaration.
- 8** Click **OK** or **Apply** and close the dialog box.

Symbolic Names for Block States

To determine the variable or field name generated for a block's state, you can either

- Use a default name generated by Real-Time Workshop
- Define a symbolic name by using the **State Name** field of the State Properties dialog box

Default Block State Naming Convention

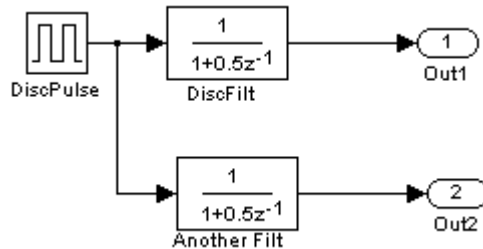
If you do not define a symbolic name for a block state, Real-Time Workshop uses the following default naming convention:

`BlockType#_DSTATE`

where

- `BlockType` is the name of the block type (for example, `Discrete_Filter`).
- `#` is a unique ID number (`#`) assigned by Real-Time Workshop if multiple instances of the same block type appear in the model. The ID number is appended to `BlockType`.
- `_DSTATE` is a string that is always appended to the block type and ID number.

For example, consider the model shown in the next figure.



Model with Two Discrete Filter Block States

Examine the code generated for the states of the two Discrete Filter blocks. Assume that:

- Neither block's state has a user-defined name.
- The upper Discrete Filter block has Auto storage class (and is therefore stored in the DWork vector).
- The lower Discrete Filter block has ExportedGlobal storage class.

The states of the two Discrete Filter blocks are stored in DWork vectors, initialized as shown in the code below:

```

/* data type work */
disc_filt_states_M->Work.dwork = ((void *)
&disc_filt_states_DWork);
(void)memset((char_T *) &disc_filt_states_DWork, 0,
sizeof(D_Work_disc_filt_states));
{
    int_T i;
    real_T *dwork_ptr = (real_T *)
&disc_filt_states_DWork.DiscFilt_DSTATE;

    for (i = 0; i < 2; i++) {
        dwork_ptr[i] = 0.0;
    }
}

```

User-Defined Block State Names

Using the State Properties dialog box, you can define your own symbolic name for a block state. To do this,

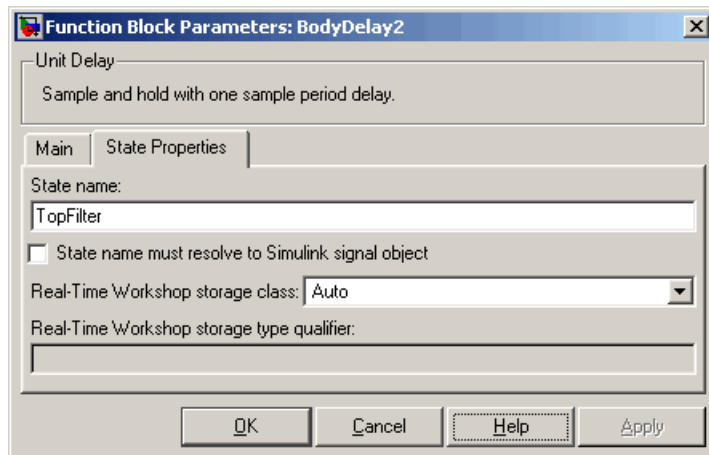
- 1 In your block diagram, double-click the desired block. This opens the block dialog box, containing two or more tabs, one of which is **State properties**.

Alternatively, you can right-click the block and select **Block properties** from the context menu.

- 2 Click the **State properties** tab.

- 3 Enter the symbolic name in the **State name** field of the State Properties dialog box. For example, enter the state name `Top_filter`.

- 4 Click **Apply**. The dialog box now looks like this:



- 5 Click **OK** or **Cancel** to dismiss the block dialog box.

The following state initialization code was generated from the example model shown in figure , under the following conditions:

- The upper Discrete Filter block has the state name `Top_filter`, and `Auto` storage class (and is therefore stored in the `DWork` vector).

- The lower Discrete Filter block has the state name `Lower_filter`, and storage class `ExportedGlobal`.

`Top_filter` is placed in the `Dwork` vector.

```
/* data type work */
disc_filt_states_M->Work.dwork = ((void *)
&disc_filt_states_DWork);
(void)memset((char_T *) &disc_filt_states_DWork, 0,
sizeof(D_Work_disc_filt_states));
disc_filt_states_DWork.Top_filter = 0.0;

/* exported global states */
Lower_filter = 0.0;
```

Block States and Simulink Signal Objects

If you are not familiar with Simulink data objects and signal objects, you should read “Simulink Data Objects and Code Generation” on page 5-46 before reading this section.

You can associate a block state with a signal object, and control code generation for the block state through the signal object. To do this,

- 1 Instantiate the desired signal object, and set its `RTWInfo.StorageClass` property as you require.
- 2 Open the State Properties dialog box for the block whose state you want to associate with the signal object.
- 3 Enter the name of the signal object in the **State name** field.
- 4 Select **State name must resolve to Simulink signal object**.

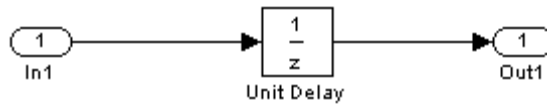
Simulink disables the **RTW storage class** and **RTW storage type qualifier** options in the State Properties dialog box, because the signal object specifies these settings.

- 5 Click **Apply** and close the dialog box.

Note When a block state is associated with a signal object, the mapping between the block state and the signal object must be one to one. If two or more identically named entities, such as a block state and a signal, map to the same signal object, the name conflict is flagged as an error at code generation time.

Summary of State Storage Class Options

Here is a simple model, `unit_delay.mdl`, which contains a Unit Delay block:



The following table shows, for each state storage class option, the variable declaration and initialization code generated for a Unit Delay block state. The block state has the user-defined state name `udx`.

Storage Class	Declaration	Initialization Code
Auto	In <i>model.h</i> <pre>typedef struct D_Work_unit_delay_tag { real_T udx; } D_Work_unit_delay;</pre>	<pre>unit_delay_DWork.udx = 0.0;</pre>
Exported Global	In <i>model.c</i> or <i>model.cpp</i> <pre>real_T udx;</pre> In <i>model.h</i> <pre>extern real_T udx;</pre>	<pre>udx = 0.0;</pre>

Storage Class	Declaration	Initialization Code
Imported Extern	In <i>model_private.h</i> extern real_T udx;	In <i>model.c</i> or <i>model.cpp</i> udx = unit_delay_P.UnitDelay_X0;
Imported Extern Pointer	In <i>model_private.h</i> extern real_T *udx;	In <i>model.c</i> or <i>model.cpp</i> (*udx) = unit_delay_P.UnitDelay_X0;

Storage Classes for Data Store Memory Blocks

You can control how Data Store Memory blocks in your model are stored and represented in the generated code by assigning storage classes and type qualifiers. You do this in almost exactly the same way you assign storage classes and type qualifiers for block states.

Data Store Memory blocks, like block states, have Auto storage class by default, and their memory is stored within the DWork vector. The symbolic name of the storage location is based on the block name.

You can generate code from multiple Data Store Memory blocks that have the same name, subject to the following restriction: *at most one* of the identically named blocks can have a storage class other than Auto. An error is reported if this condition is not met. For blocks with Auto storage class, Real-Time Workshop generates a unique symbolic name for each block (if necessary) to avoid name clashes. For blocks with storage classes other than Auto, Real-Time Workshop simply uses the block name to generate the symbol.

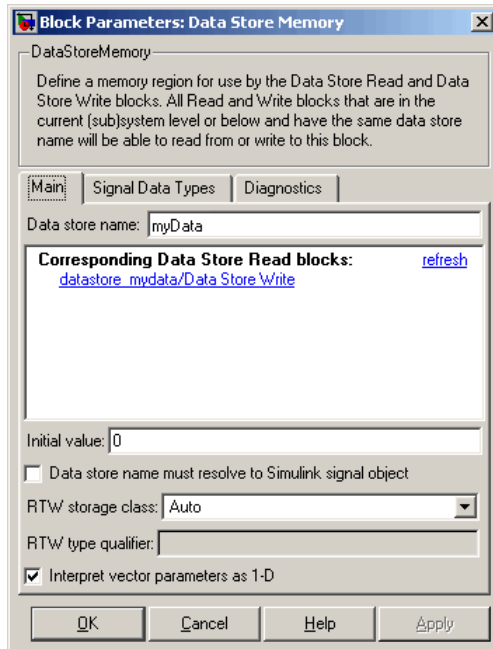
If the storage class of a Data Store Memory block is ExportedGlobal, Real-Time Workshop changes the name of any Inport that has the same name as the block. The name of the Inport in generated code is the original name suffixed with an underscore and a random lowercase letter. Real-Time Workshop makes this change to avoid reusing identifiers in ExportedGlobal data.

To control the storage declaration for a Data Store Memory block, use the **RTW storage class** and **RTW storage type qualifier** fields of the Data Store Memory block parameters dialog box.

In the following block diagram, a Data Store Write block writes to memory declared by the Data Store Memory block myData.



Data Store Memory blocks are nonvirtual because code is generated for their initialization in .c and .cpp files and their declarations in header files. The next figure shows the Data Store Memory Block Parameters dialog box, which specifies the blocks that can write to and read from the Data Store Memory block.



The following table shows code generated for the Data Store Memory block in this model, depending on the setting of **RTW storage class**. The table gives the variable declarations and MdlOutputs code generated for the myData block.

Storage Class	Declaration	Code
Auto	<p>In <i>model.h</i></p> <pre>typedef struct D_Work_tag { real_T myData; } D_Work;</pre> <p>In <i>model.c</i> or <i>model.cpp</i></p> <pre>/* Block states (auto storage) */ D_Work model_DWork;</pre>	<pre>model_DWork.myData = rtb_SineWave;</pre>
ExportedGlobal	<p>In <i>model.c</i> or <i>model.c</i></p> <pre>/* Exported block states */ real_T myData;</pre> <p>In <i>model.h</i></p> <pre>extern real_T myData;</pre>	<pre>myData = rtb_SineWave;</pre>
ImportedExtern	<p>In <i>model_private.h</i></p> <pre>extern real_T myData;</pre>	<pre>myData = rtb_SineWave;</pre>
ImportedExternPointer	<p>In <i>model_private.h</i></p> <pre>extern real_T *myData;</pre>	<pre>(*myData) = rtb_SineWave;</pre>

Data Store Memory and Simulink Signal Objects

If you are not familiar with Simulink data objects and signal objects, you should read “Simulink Data Objects and Code Generation” on page 5-46 before reading this section.

You can associate a Data Store Memory block with a signal object, and control code generation for the block through the signal object. To do this,

- 1** Instantiate the desired signal object, and set its `RTWInfo.StorageClass` property as you require.
- 2** Open the block parameters dialog box for the Data Store Memory block whose state you want to associate with the signal object. Enter the name of the signal object in the **Data store name** field.
- 3** Select the **Data Store name must resolve to Simulink signal object** option. Make sure that the storage class and type qualifier settings of the block parameters dialog box are not set; you will be unable to close the dialog box until you specify auto storage class. See “Resolving Conflicts in Configuration of Parameter and Signal Objects” on page 5-69.
- 4** Click **Apply** and close the dialog box.

Note When a Data Store Memory block is associated with a signal object, the mapping between the **Data store name** and the signal object name must be one to one. If two or more identically named entities map to the same signal object, the name conflict is flagged as an error at code generation time.

External Mode

In external mode, Real-Time Workshop establishes a communications link between a model running in Simulink and code executing on a target system. More details on external mode are provided elsewhere in this documentation: “Creating an External Mode Communication Channel” on page 17-23 contains advanced information for those who want to implement their own external mode communications layer. You want to read it to gain increased insight into the architecture and code structure of external mode communications. In addition, Chapter 13, “Targeting Tornado for Real-Time Applications” discusses the use of external mode in the VxWorks Tornado environment.

Introduction (p. 6-2)	Summarizes external mode features and architecture
Using the External Mode User Interface (p. 6-3)	Describes all elements of the external mode user interface
External Mode Compatible Blocks and Subsystems (p. 6-25)	Discusses types of blocks that receive and view signals in external mode
External Mode Communications Overview (p. 6-28)	Summarizes the communications process between Simulink and a target program
Client/Server Implementations (p. 6-32)	Discusses features, bundled targets, and techniques for using external mode
Using External Mode Programmatically (p. 6-40)	Discusses parameters for using external mode from the MATLAB command line or programmatically in scripts
External Mode Limitations (p. 6-46)	Lists external mode limitations

Introduction

External mode allows two separate systems, a *host* and a *target*, to communicate. The host is the computer where MATLAB and Simulink are executing. The target is the computer where the executable created by Real-Time Workshop runs.

The host (Simulink) transmits messages requesting the target to accept parameter changes or to upload signal data. The target responds by executing the request. External mode communication is based on a *client/server* architecture, in which Simulink is the client and the target is the server.

External mode lets you

- Modify, or *tune*, block parameters in real time. In external mode, whenever you change parameters in the block diagram, Simulink downloads them to the executing target program. This lets you tune your program's parameters without recompiling.
- View and log block outputs in many types of blocks and subsystems. You can monitor and/or store signal data from the executing target program, without writing special interface code. You can define the conditions under which data is uploaded from target to host. For example, data uploading could be triggered by a selected signal crossing zero in a positive direction. Alternatively, you can manually trigger data uploading.

External mode works by establishing a communication channel between Simulink and code generated by Real-Time Workshop. The channel's low-level *transport layer* handles the physical transmission of messages. Simulink and the generated model code are independent of this layer. The transport layer and the code directly interfacing to it are isolated in separate modules that format, transmit, and receive messages and data packets.

This design allows for different targets to use different transport layers. ERT, GRT, GRT malloc, and RSim targets support external mode host/target communication by using TCP/IP and RS-232 (serial) communication. xPC targets use a customized transport layer. The Tornado target supports TCP/IP only. Serial transport is implemented only for Windows 32-bit architectures. Real-Time Windows Target uses shared memory.

Using the External Mode User Interface

In this section...

“External Mode Interface Options” on page 6-3

“External Mode Related Menu and Toolbar Items” on page 6-6

“External Mode Control Panel” on page 6-11

“Target Interfacing” on page 6-13

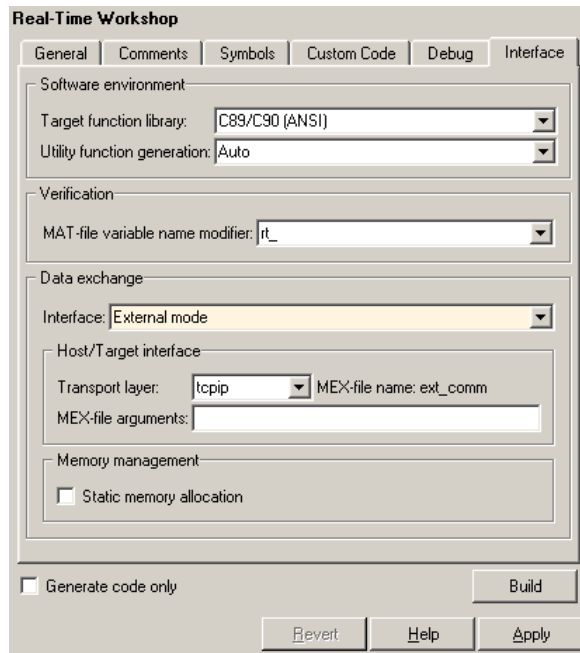
“External Signal Uploading and Triggering” on page 6-15

“Data Archiving” on page 6-20

“Parameter Downloading” on page 6-22

External Mode Interface Options

The ERT, GRT, GRT malloc, RSim, Real-Time Windows, and Tornado targets support external mode. All targets that support it feature a set of external mode options on their respective target tab of the Configuration Parameters dialog box. This tab is normally named **Interface**). The next figure is from the GRT target dialog box, and is discussed below.



Note xPC Target also uses external mode communications. External mode in xPC Target is always on, and has no interface options.

The **Data exchange** section at the bottom has the following elements:

- **Interface** menu: Selects which of three mutually exclusive data interfaces to include in the generated code. Options are
 - None
 - C-API
 - External mode
 - ASAP2

This chapter discusses only the External mode option. For information on other options, see “Configuring Model Interfaces” on page 2-63.

Once you select `External` mode from the `Interface` menu, the following options appear beneath:

- **Transport layer** menu: Identifies messaging protocol for host/target communications; choices are `tcpip` and `serial_win32`.

The default is `tcpip`. When you select a protocol, the MEX-file name that implements the protocol is shown to the right of the menu.

- **MEX-file arguments** text field: Optionally enter a list of arguments to be passed to the transport layer MEX-file for communicating with executing targets; these will vary according to the protocol you use.

For more information on the transport options, see “Target Interfacing” on page 6-13 and “Client/Server Implementations” on page 6-32. You can add other transport protocols yourself by following instructions given in “Creating an External Mode Communication Channel” on page 17-23.

- **Static memory allocation** check box: Controls how memory for external mode communication buffers in the target is allocated. When you select this option, the following one appears beneath it:
- **Static memory buffer size** text field: Number of bytes to preallocate for external mode communications buffers in the target when **Static memory allocation** is used.

Note Selecting `External` mode from the **Interface** menu does not cause Simulink to operate in external mode (see “External Mode Related Menu and Toolbar Items” on page 6-6, below). Its function is to instrument the code generated for the target to support external mode.

The **Static memory allocation** check box (for GRT and ERT targets) directs Real-Time Workshop to generate code for external mode that uses only static memory allocation (“malloc-free” code). When selected, it activates the **Static memory buffer size** edit field, in which you specify the size of the static memory buffer used by external mode. The default value is 1,000,000 bytes. Should you enter too small a value for your application, external mode issues an out-of-memory error when it tries to allocate more memory than you allowed. In such cases, increase the value in the **Static memory buffer size** field and regenerate the code.

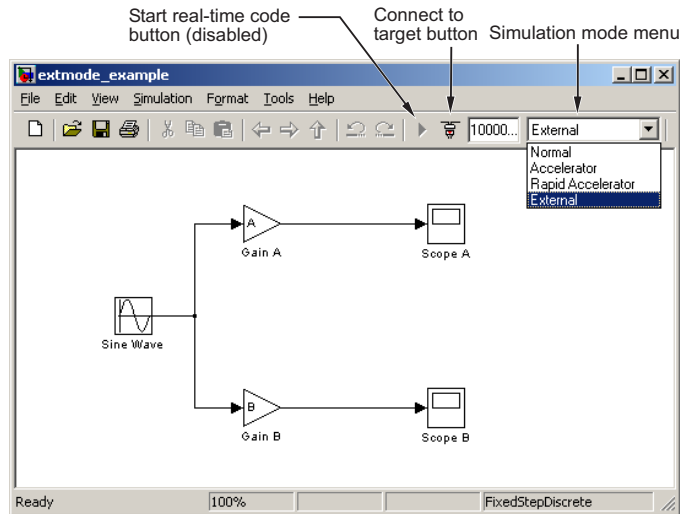
Notes

- To determine how much memory you need to allocate, enable verbose mode on the target (by including `OPTS="-DVERBOSE"` on the make command line). As it executes, external mode displays the amount of memory it tries to allocate and the amount of memory available to it each time it attempts an allocation. Should an allocation fail, this console log can be used to adjust the size entered in the **Static memory buffer size** field.
 - When you create an ERT target, external mode can generate pure integer code. Select this feature by clearing the **Support floating-point numbers** option on the **Interface** pane of the Configuration Parameters dialog box or Model Explorer. Clearing this option ensures that all code, including external mode support code, is free of doubles and floats. For more details, see “Configuring Model Interfaces” in the Real-Time Workshop Embedded Coder documentation.
-

External Mode Related Menu and Toolbar Items

To communicate with a target program, the model must be operating in external mode. To enable external mode, do either of the following:

- Select **External** from the **Simulation** menu.
- Select **External** from the simulation mode menu in the toolbar. The simulation mode menu is shown in the next figure.



Simulation Mode Menu Options and Target Connection Control (Host Disconnected from Target)

Once external mode is enabled, you can connect to and control the target program by doing any of the following:

- Select **Connect To Target** from the **Simulation** menu.
- Click the **Connect To Target** toolbar button, shown in the preceding figure.
- Use the **Ctrl+T** keyboard shortcut.

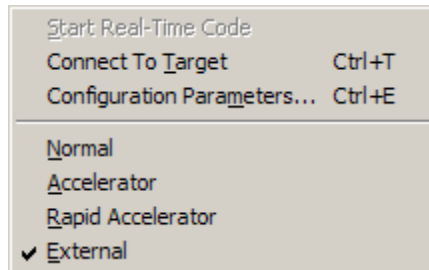
Note When external mode is selected in the model window, the **Ctrl+T** keyboard shortcut is remapped from a toggle for **Start** and **Stop** (simulation) to a toggle for **Connect To Target** and **Disconnect From Target**.

Selecting external mode in the model window controls execution only, and does *not* cause Real-Time Workshop to generate code for external mode. To do this, you must select External mode from the **Interface** menu on the **Interface** tab of the Configuration Parameters dialog box, as described in “External Mode Interface Options” on page 6-3.

Note You can enable external mode, and simultaneously connect to the target system, by using the External Mode Control Panel dialog box. See “External Mode Control Panel” on page 6-11.

Simulation Menu

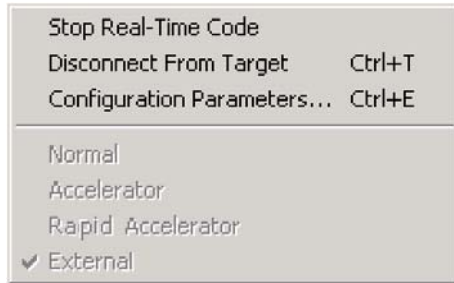
When Simulink is in external mode, the upper section of the **Simulation** menu contains external mode options. Initially, the Simulink model is disconnected from the target program, and the menu displays the options shown in the next figure.



Simulation Menu External Mode Options (Host Disconnected from Target)

The **Connect To Target** option (or its **Ctrl+T** keyboard shortcut) establishes communication with the target program. When a connection is established, the target program might be executing model code, or it might be awaiting a command from the host to start executing model code. You can also accomplish this by clicking the **Connect To Target** toolbar button, as shown in Simulation Mode Menu Options and Target Connection Control (Host Disconnected from Target) on page 6-7.

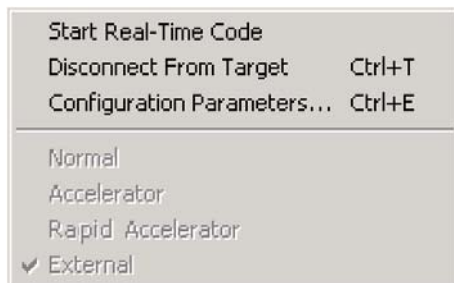
If the target program is executing model code, the **Simulation** menu contents change, as shown in the next figure.



Simulation Menu External Mode Options (Target Executing Model Code)

The **Disconnect From Target** option (or its **Ctrl+T** keyboard shortcut) disconnects Simulink from the target program, which continues to run. The **Stop Real-Time Code** option terminates execution of the target program and disconnects Simulink from the target system.

If the target program is in a wait state, the **Start Real-Time Code** option is enabled, as shown in the next figure. The **Start Real-Time Code** option instructs the target program to begin executing the model code.



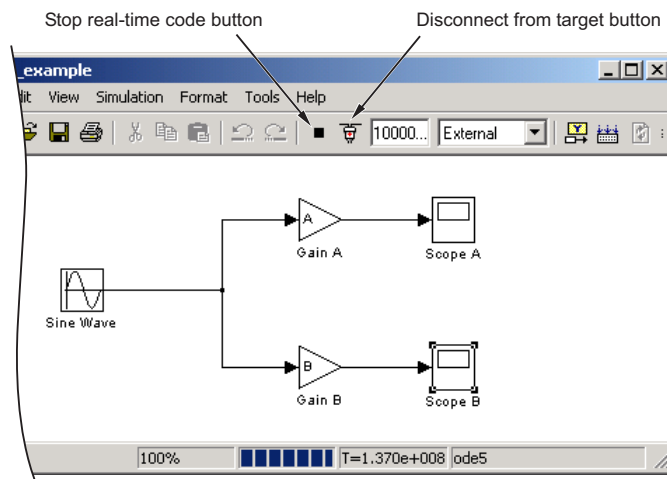
Simulation Menu External Mode Options (Target Awaiting Start Command)

Toolbar Controls

The Simulink toolbar controls, shown in Simulation Mode Menu Options and Target Connection Control (Host Disconnected from Target) on page 6-7, let you control the same external mode functions as the **Simulation** menu. Simulink displays external mode buttons to the left of the Simulation mode menu. Initially, the toolbar displays a **Connect To Target** button and a disabled **Start real-time code** button. Click the **Connect To Target** button to connect Simulink to the target program.

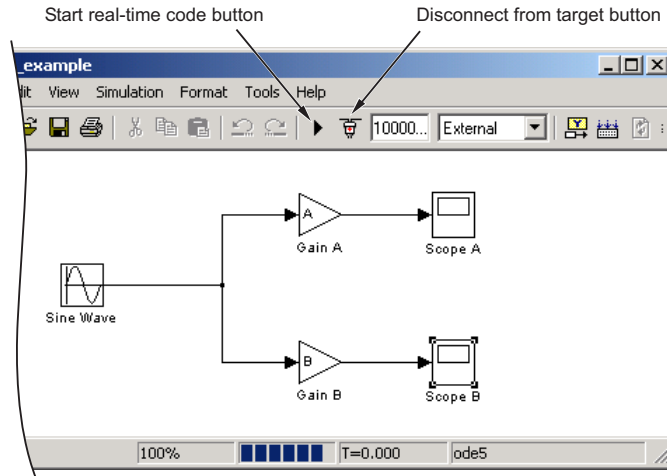
When a connection is established, the target program might be executing model code, or it might be awaiting a command from the host to start executing model code.

If the target program is executing model code, the toolbar displays a **Stop real-time code** button and a **Disconnect From Target** button (shown in External Mode Toolbar Controls (Target Executing Model Code) on page 6-10). Click the **Stop real-time code** button to command the target program to stop executing model code and disconnect Simulink from the target system. Click the **Disconnect From Target** button to disconnect Simulink from the target program while leaving the target program running.



External Mode Toolbar Controls (Target Executing Model Code)

If the target program is in a wait state, the toolbar displays a **Start real-time code** button and a **Disconnect From Target** button (shown in External Mode Toolbar Controls (Target in Wait State) on page 6-11). Click the **Start real-time code** button to instruct the target program to start executing model code. Click the **Disconnect From Target** button to disconnect Simulink from the target program.



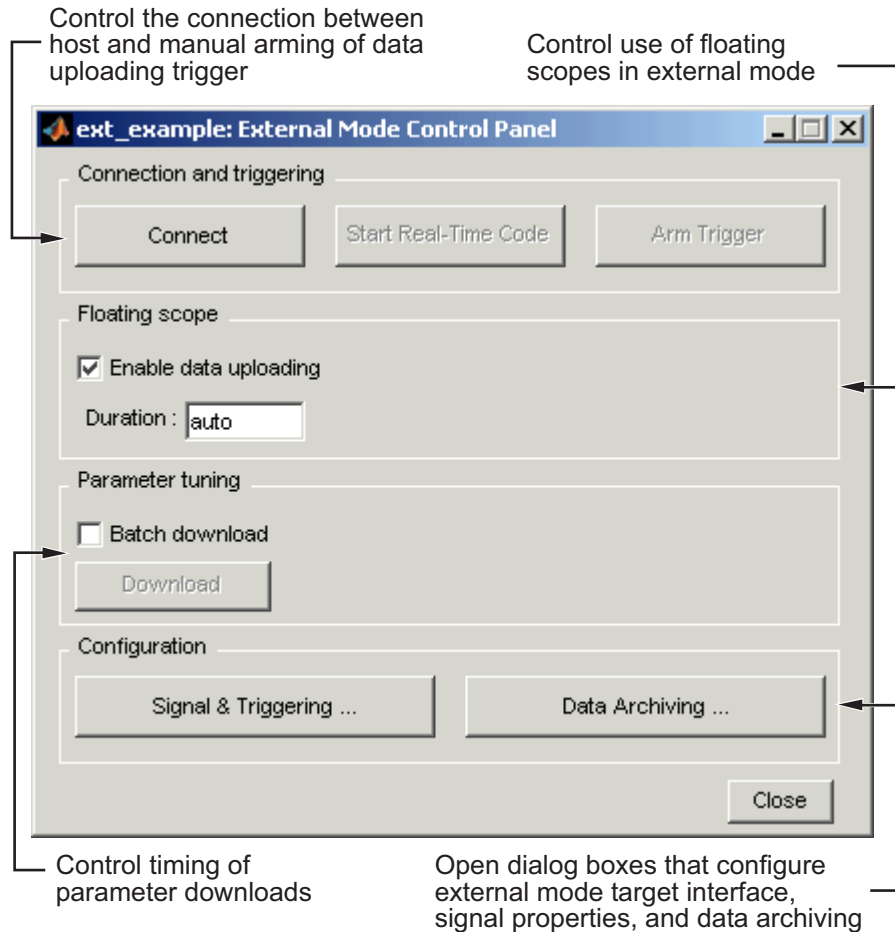
External Mode Toolbar Controls (Target in Wait State)

External Mode Control Panel

The External Mode Control Panel, illustrated in the next figure, provides centralized control of all external mode features, including

- Host/target connection, disconnection, and target program start/stop functions, and enabling of external mode
- Arming and disarming the data upload trigger
- External mode communications configuration
- Uploading data to Floating Scopes
- Timing of parameter downloads
- Selection of signals from the target program to be viewed and monitored on the host
- Configuration of data archiving features

Select **External Mode Control Panel** from the Simulink **Tools** menu to open the External Mode Control Panel dialog box.



The following sections describe the features supported by the External Mode Control Panel.

Connecting, Starting, and Stopping

The External Mode Control Panel performs the same connect/disconnect and start/stop functions found in the **Simulation** menu and the Simulink toolbar (see “External Mode Related Menu and Toolbar Items” on page 6-6).

The **Connect/Disconnect** button connects to or disconnects from the target program. The button text changes in accordance with the state of the connection.

If external mode is not enabled at the time the **Connect** button is clicked, the External Mode Control Panel enables external mode automatically.

The **Start/Stop real-time code** button commands the target to start or terminate model code execution. The button is disabled until a connection to the target is established. The button text changes in accordance with the state of the target program.

Floating Scope Options

The **Floating scope** pane of the External Mode Control Panel controls when and for how long data is uploaded to Floating Scope blocks. When used under external mode, Floating Scopes

- Do not appear in the signal and triggering GUI
- Support manual triggering only

The behavior of wired scopes is not restricted in these ways.

The **Floating scope** pane contains a check box and an edit field:

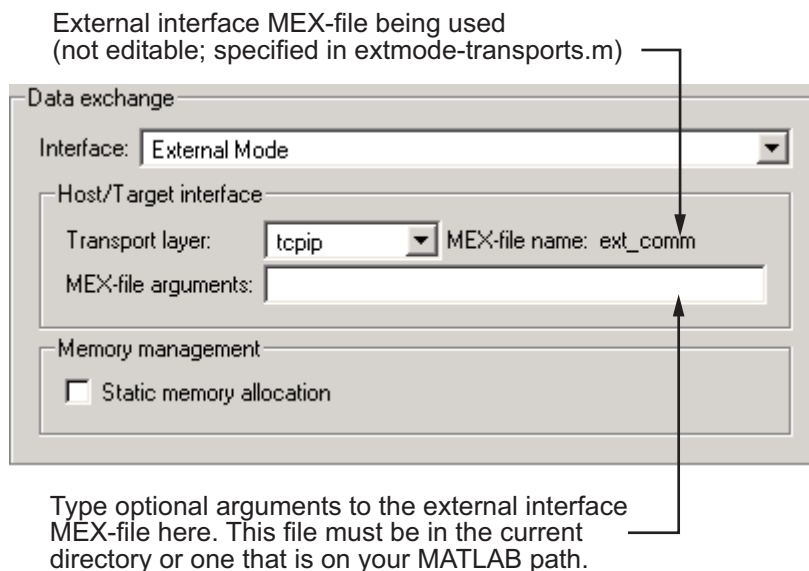
- **Enable data uploading** check box, which functions as an **Arm trigger** button for floating scopes. When the target is disconnected it controls whether or not to arm when connecting the floating scopes. When already connected it acts as a toggle button to arm/cancel the trigger.
- **Duration** edit field, which specifies the duration for floating scopes. By default, it is set to auto, which causes whatever value is specified in the signal and triggering GUI (which by default is 1000 seconds) to be used.

Target Interfacing

Real-Time Workshop lets you implement client and server transport for external mode using either TCP/IP or serial protocols. You can use the socket-based external mode implementation provided by Real-Time Workshop with the generated code, provided that your target system supports TCP/IP. Otherwise, use or customize the serial transport layer option provided.

A low-level *transport layer* handles physical transmission of messages. Both Simulink and the model code are independent of this layer. Both the transport layer and code directly interfacing to the transport layer are isolated in separate modules that format, transmit, and receive messages and data packets.

You specify the transport mechanism using the **Transport layer** menu in the **Host/Target interface** section of the **Interface** pane of the Configuration Parameters dialog box. This section appears in the next figure.



The **Host/Target interface** controls let you verify the name of a MEX-file that implements host/target communications, and specify calling argument values. This is known as the external interface MEX-file. The meaning of these arguments depends on the MEX-file implementation.

You cannot edit the name of the external interface MEX-file. The default is `ext_comm`, the TCP/IP-based external interface file provided for use with the GRT, GRT malloc, ERT, RSIM, and Tornado targets. If you select the `serial_win32` transport option, the MEX-file name `ext_serial_win32_com` is displayed in this location. Custom or third-party targets can use a different

external interface MEX-file. The interface MEX-file that appears in this field must be specified in the system target file.

The **MEX-file arguments** edit field lets you optionally specify arguments that are passed to the external mode interface MEX-file for communicating with executing targets.

For TCP/IP interfaces, `ext_comm` allows three optional arguments:

- Network name of your target (for example, 'myputer' or '148.27.151.12')
- Verbosity level (0 for no information or 1 for detailed information)
- TCP/IP server port number (an integer value between 256 and 65535, with a default of 17725)

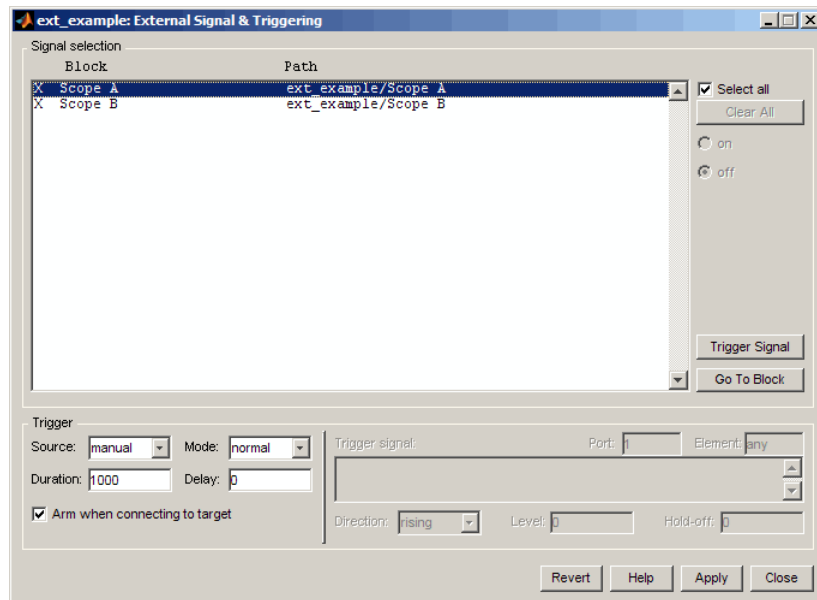
For serial transport, `ext_serial_win32_comm` allows three optional arguments:

- Verbosity level (0 for no information or 1 for detailed information)
- Serial port ID (for example, 1 for COM1, and so on)
- Baud rate (selected from the set 1200, 2400, 4800, 9600, 14400, 19200, 38400, 57600, 115200, with a default baud rate of 57600)

See “Client/Server Implementations” on page 6-32 for details on MEX-file transport architecture and arguments.

External Signal Uploading and Triggering

Clicking the **Signal & triggering** button of the External Mode Control Panel activates the External Signal & Triggering dialog box, as shown in the next figure.



The External Signal & Triggering dialog box displays a list of all blocks and subsystems in your model that support external mode signal uploading. See “External Mode Compatible Blocks and Subsystems” on page 6-25 for information on which types of blocks are external mode compatible.

The External Signal & Triggering dialog box lets you select the signals that are collected from the target system and viewed in external mode. It also lets you select a signal that triggers uploading of data when certain signal conditions are met, and define the triggering conditions.

Default Operation

The preceding figure shows the default settings of the External Signal & Triggering dialog box. The default operation of the External Signal & Triggering dialog box is designed to simplify monitoring the target program. If you use the default settings, you do not need to preconfigure signals and triggers. Simply start the target program and connect the Simulink model to it. All external mode compatible blocks will be selected and the trigger will be armed. Signal uploading begins immediately upon connection to the target program.

The default configuration is

- **Arm when connecting to target:** on
- **Trigger Mode:** normal
- **Trigger Source:** manual
- **Select all:** on

Signal Selection

All external mode compatible blocks in your model appear in the **Signal selection** list of the External Signal & Triggering dialog box. You use this list to select signals to be viewed. An X appears to the left of each selected block's name.

The **Select all** check box selects all signals. By default, **Select all** is on.

If **Select all** is off, you can select or deselect individual signals using the **on** and **off** radio buttons. To select a signal, click the desired list entry and click the **on** radio button. To deselect a signal, click the desired list entry and click the **off** radio button. Alternatively, you can double-click a signal in the list to toggle between selection and deselection.

The **Clear all** button deselects all signals.

Trigger Options

The **Trigger** panel located at the bottom left of the External Signal & Triggering dialog contains options that control when and how signal data is collected (uploaded) from the target system. These options are

- **Source:** manual or signal. Selecting manual directs external mode to start logging data when the **Arm trigger** button on the External Mode Control Panel is clicked.

Selecting signal tells external mode to start logging data when a selected trigger signal satisfies trigger conditions specified in the **Trigger signal** panel. When the trigger conditions are satisfied (that is, the signal crosses the trigger level in the specified direction) a *trigger event* occurs. If the

trigger is *armed*, external mode monitors for the occurrence of a trigger event. When a trigger event occurs, data logging begins.

- **Arm when connecting to target:** If this option is selected, external mode arms the trigger automatically when Simulink connects to the target. If the trigger source is manual, uploading begins immediately. If the trigger mode is signal, monitoring of the trigger signal begins immediately, and uploading begins upon the occurrence of a trigger event.

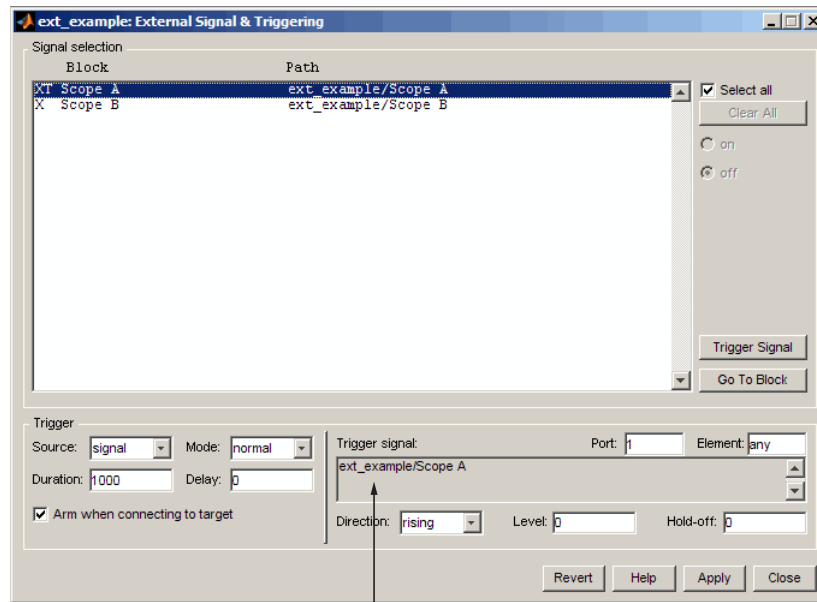
If **Arm when connecting to target** is not selected, you must manually arm the trigger by clicking the **Arm trigger** button in the External Mode Control Panel.

- **Duration:** The number of base rate steps for which external mode logs data after a trigger event. For example, if the fastest rate in the model is 1 second and a signal sampled at 1 Hz is being logged for a duration of 10 seconds, then external mode will collect 10 samples. If a signal sampled at 2 Hz is logged, 20 samples will be collected.
- **Mode:** normal or one-shot. In normal mode, external mode automatically rearms the trigger after each trigger event. In one-shot mode, external mode collects only one buffer of data each time you arm the trigger. See “Data Archiving” on page 6-20 for more details on the effect of the **Mode** setting.
- **Delay:** The delay represents the amount of time that elapses between a trigger occurrence and the start of data collection. The delay is expressed in base rate steps, and can be positive or negative. A negative delay corresponds to pretriggering. When the delay is negative, data from the time preceding the trigger is collected and uploaded.

Trigger Signal Selection

You can designate one signal as a trigger signal. To select a trigger signal, select signal from the **Trigger Source** menu. This activates the **Trigger signal** panel (see the next figure). Then, click the desired entry in the **Signal selection** list and click the **Trigger signal** button.

When a signal is selected as a trigger, a T appears to the left of the block’s name in the **Signal selection** list. In the next figure, the Scope A signal is the trigger. Scope B is also selected for viewing, as indicated by the X to the left of the block name.



Trigger signal panel

External Signal & Triggering Window with Trigger Selected

After selecting the trigger signal, you can define the trigger conditions and set the **Port** and **Element** fields in the **Trigger signal** panel.

Setting Trigger Conditions

Note The **Trigger signal** panel and the **Port** and **Element** fields of the External Signal & Triggering dialog box are enabled only when trigger **Source** is set to signal.

By default, any element of the first input port of the specified trigger block can cause the trigger to fire (that is, Port 1, any element). You can modify this behavior by adjusting the **Port** and **Element** fields located on the right side of the Trigger signal panel. The **Port** field accepts a number or the keyword last. The **Element** field accepts a number or the keywords any and last.

The **Trigger Signal** panel defines the conditions under which a trigger event will occur.

- **Level:** Specifies a threshold value. The trigger signal must cross this value in a designated direction to fire the trigger. By default, the level is 0.
- **Direction:** rising, falling, or either. This specifies the direction in which the signal must be traveling when it crosses the threshold value. The default is rising.
- **Hold-off:** Applies only to normal mode. Expressed in base rate steps, **Hold-off** is the time between the termination of one trigger event and the rearming of the trigger.

Data Archiving

Clicking the **Data Archiving** button of the External Mode Control Panel opens the External Data Archiving dialog box, which supports the following features:

Directory Notes

Use this option to add annotations that pertain to a collection of related data files in a directory. Clicking the **Edit directory note** button opens the MATLAB editor. Place comments that you want saved to a file in the specified directory in this window. By default, the comments are saved to the directory last written to by data archiving.

File Notes

Clicking **Edit file note** opens a file finder window that is, by default, set to the last file to which you have written. Selecting any MAT-file opens an edit window. Add or edit comments in this window that you want saved with your individual MAT-file.

Data Archiving

Clicking the **Enable Archiving** check box activates the automated data archiving features of external mode. To understand how the archiving features work, it is necessary to consider the handling of data when archiving is not enabled. There are two cases, one-shot and normal mode.

In one-shot mode, after a trigger event occurs, each selected block writes its data to the workspace just as it would at the end of a simulation. If another one-shot is triggered, the existing workspace data is overwritten.

In normal mode, external mode automatically rearms the trigger after each trigger event. Consequently, you can think of normal mode as a series of one-shots. Each one-shot in this series, except for the last, is referred to as an *intermediate result*. Since the trigger can fire at any time, writing intermediate results to the workspace generally results in unpredictable overwriting of the workspace variables. For this reason, the default behavior is to write only the results from the final one-shot to the workspace. The intermediate results are discarded. If you know that sufficient time exists between triggers for inspection of the intermediate results, then you can override the default behavior by checking the **Write intermediate results to workspace** check box. This option does not protect the workspace data from being overwritten by subsequent triggers.

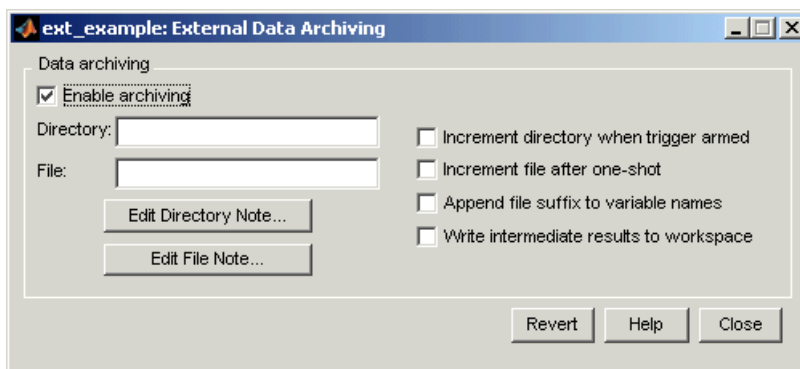
The options in the External Data Archiving dialog box support automatic writing of logging results, including intermediate results, to disk. Data archiving provides the following settings:

- **Directory:** Specifies the directory in which data is saved. External mode appends a suffix if you select **Increment directory when trigger armed**.
- **File:** Specifies the filename in which data is saved. External mode appends a suffix if you select **Increment file after one-shot**.
- **Increment directory when trigger armed:** External mode uses a different directory for writing log files each time that you click the **Arm trigger** button. The directories are named incrementally, for example, `dirname1`, `dirname2`, and so on.
- **Increment file after one-shot:** New data buffers are saved in incremental files: `filename1`, `filename2`, and so on. This happens automatically in normal mode.
- **Append file suffix to variable names:** Whenever external mode increments filenames, each file contains variables with identical names. Selecting **Append file suffix to variable name** results in each file containing unique variable names. For example, external mode will save a variable named `xdata` in incremental files (`file_1`, `file_2`, and so on) as `xdata_1`, `xdata_2`, and so on. This is useful if you want to load the

MAT-files into the workspace and compare variables in MATLAB. Without the unique names, each instance of xdata would overwrite the previous one in the MATLAB workspace.

- **Write intermediate results to workspace:** Select this option if you want Real-Time Workshop to write all intermediate results to the workspace.

The next figure shows the External Data Archiving dialog box with archiving enabled.



Unless you select **Enable archiving**, entries for the **Directory** and **File** fields are not accepted.

Parameter Downloading

The **Batch download** check box on the External Mode Control Panel enables or disables batch parameter changes.

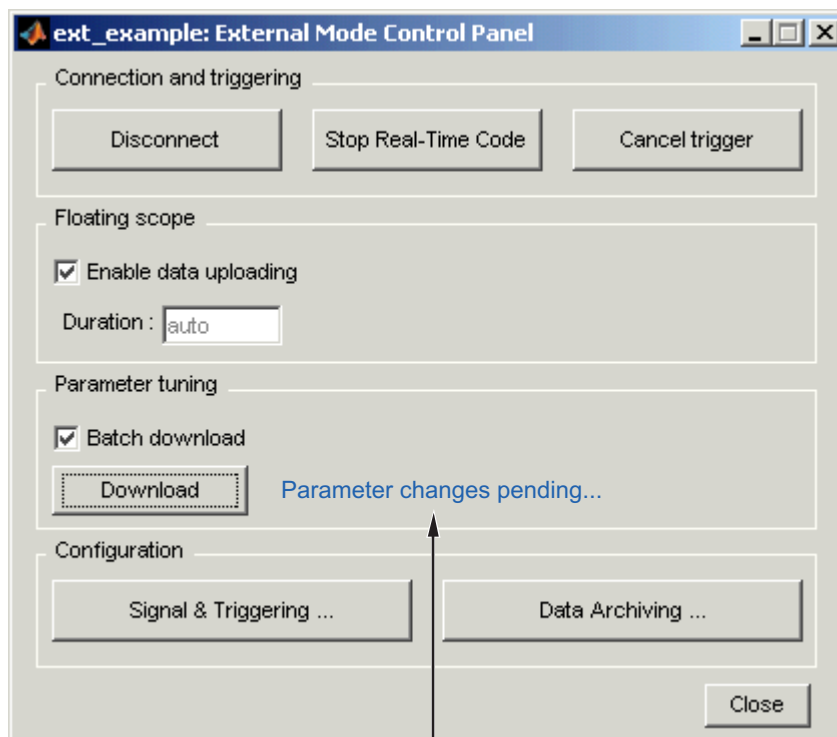
By default, batch download is not enabled. If batch download is not enabled, changes made directly to block parameters by using parameter dialog boxes are sent to the target when you click the **OK** or **Apply** button. Changes to MATLAB workspace variables are sent when an **Update diagram** is performed.

Note Opening a dialog box for a source block causes Simulink to pause. While Simulink is paused, you can edit the parameter values. You must close the dialog box to have the changes take effect and allow Simulink to continue.

If batch download is enabled, the Download button is enabled. Changes made to block parameters are stored locally until you click the Download button. When you click the Download button, the changes are sent in a single transmission.

When parameter changes have been made and are awaiting batch download, the External Mode Control Panel displays the message Parameter changes pending... to the right of the download button. (See the next figure.) This message disappears after Simulink receives notification from the target that the new parameters have been installed in the parameter vector of the target system.

The External Mode Control Panel with the batch download option activated appears in the next figure.



Parameter changes pending...
message appears if unsent
parameter value changes
are awaiting download

External Mode Control Panel in Batch Download Mode

External Mode Compatible Blocks and Subsystems

In this section...
“Compatible Blocks” on page 6-25
“Signal Viewing Subsystems” on page 6-25

Compatible Blocks

In external mode, you can use the following types of blocks to receive and view signals uploaded from the target program:

- Floating Scope, Scope, Spectrum Scope, and Vector Scope blocks
- Blocks in Gauges Blockset
- Display blocks
- To Workspace blocks
- User-written S-Function blocks

An external mode method is built into the S-function API. This method allows user-written blocks to support external mode. See `matlabroot/simulink/simstruc.h`.

- XY Graph blocks

In addition to these types of blocks, you can designate certain subsystems as Signal Viewing Subsystems and use them to receive and view signals uploaded from the target program. See “Signal Viewing Subsystems” on page 6-25 for more information.

External mode compatible blocks and subsystems are selected, and the trigger is armed, by using the External Signal & Triggering dialog box. By default, all such blocks in a model are selected, and a manual trigger is set to be armed when connected to the target program.

Signal Viewing Subsystems

A Signal Viewing Subsystem is an atomic subsystem that encapsulates processing and viewing of signals received from the target system. A Signal

Viewing Subsystem runs only on the host, generating no code in the target system. Signal Viewing Subsystems run in all simulation modes — normal, accelerated, and external.

Signal Viewing Subsystems are useful in situations where you want to process or condition signals before viewing or logging them, but you do not want to perform these tasks on the target system. By using a Signal Viewing Subsystem, you can generate smaller and more efficient code on the target system.

Like other external mode compatible blocks, Signal Viewing Subsystems are displayed in the External Signal & Triggering dialog box.

To declare a subsystem to be a Signal Viewing Subsystem,

- 1 Select the **Treat as atomic unit** option in the Block Parameters dialog box.

See “Nonvirtual Subsystem Code Generation” on page 4-2 for more information on atomic subsystems.

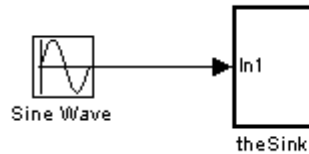
- 2 Use the following `set_param` command to turn the `SimViewingDevice` property on,

```
set_param('blockname', 'SimViewingDevice', 'on')
```

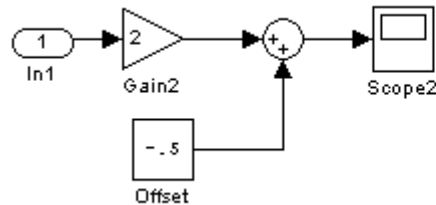
where 'blockname' is the name of the subsystem.

- 3 Make sure the subsystem meets the following requirements:
 - It must be a pure sink block. That is, it must contain no Output blocks or Data Store blocks. It can contain Goto blocks only if the corresponding From blocks are contained within the subsystem boundaries.
 - It must have no continuous states.

The following model, `sink_examp`, contains an atomic subsystem, `theSink`.



The subsystem `theSink`, shown in the next figure, applies a gain and an offset to its input signal and displays it on a Scope block.



If `theSink` is declared as a Signal Viewing Subsystem, the generated target program includes only the code for the Sine Wave block. If `theSink` is selected and armed in the External Signal & Triggering dialog box, the target program uploads the sine wave signal to `theSink` during simulation. You can then modify the parameters of the blocks within `theSink` and observe their effect upon the uploaded signal.

If `theSink` were not declared as a Signal Viewing Subsystem, its Gain, Constant, and Sum blocks would run as subsystem code on the target system. The Sine Wave signal would be uploaded to Simulink after being processed by these blocks, and viewed on `sink_examp/theSink/Scope2`. Processing demands on the target system would be increased by the additional signal processing, and by the downloading of changes in block parameters from the host.

External Mode Communications Overview

In this section...

“Introduction” on page 6-28

“The Download Mechanism” on page 6-28

“Inlined and Tunable Parameters” on page 6-30

Introduction

This section describes how Simulink and a target program communicate, and how and when they transmit parameter updates and signal data to each other.

Depending on the setting of the **Inline parameters** option when the target program is generated, there are differences in the way parameter updates are handled. “The Download Mechanism” on page 6-28 describes the operation of external mode communications with **Inline parameters** off. “Inlined and Tunable Parameters” on page 6-30 describes the operation of external mode with **Inline parameters** on.

The Download Mechanism

In external mode, Simulink does not simulate the system represented by the block diagram. By default, when external mode is enabled, Simulink downloads all parameters to the target system. After the initial download, Simulink remains in a waiting mode until you change parameters in the block diagram or until Simulink receives data from the target.

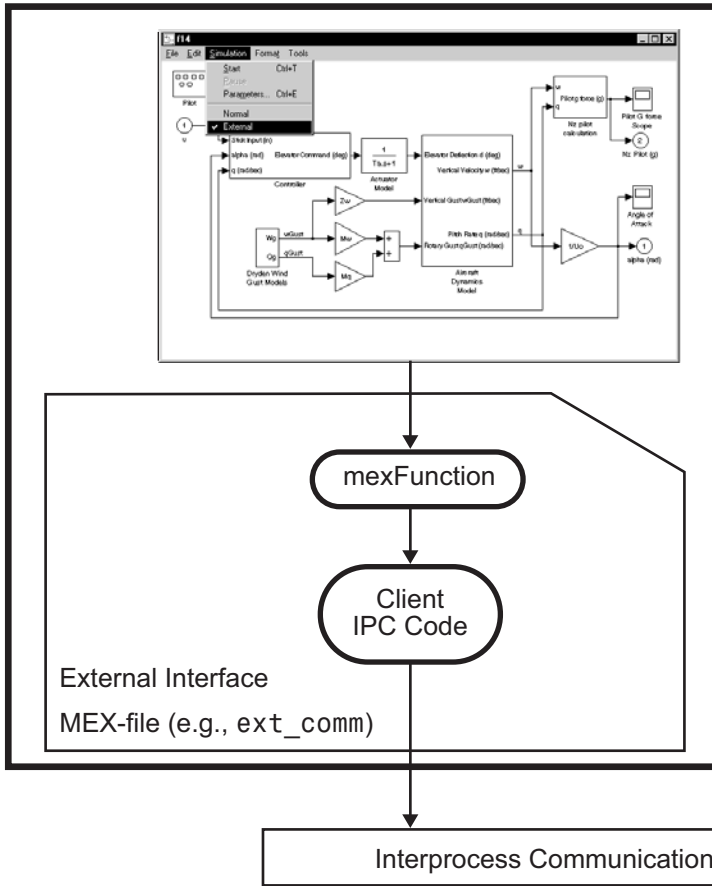
When you change a parameter in the block diagram, Simulink calls the external interface MEX-file, passing new parameter values (along with other information) as arguments. The external interface MEX-file contains code that implements one side of the interprocess communication (IPC) channel. This channel connects the Simulink process (where the MEX-file executes) to the process that is executing the external program. The MEX-file transfers the new parameter values by using this channel to the external program.

The other side of the communication channel is implemented within the external program. This side writes the new parameter values into the target’s parameter structure (*model_P*).

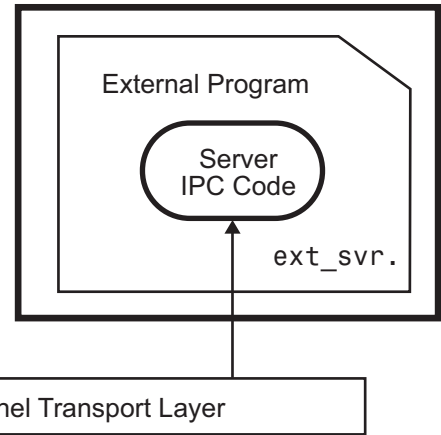
The Simulink side initiates the parameter download operation by sending a message containing parameter information to the external program. In the terminology of client/server computing, the Simulink side is the client and the external program is the server. The two processes can be remote, or they can be local. Where the client and server are remote, a protocol such as TCP/IP is used to transfer data. Where the client and server are local, a serial connection or shared memory can be used to transfer data.

The next figure shows this relationship. Simulink calls the external interface MEX-file whenever you change parameters in the block diagram. The MEX-file then downloads the parameters to the external program by using the communication channel.

Simulink Process



External Program Process



External Mode Architecture

Inlined and Tunable Parameters

By default, all parameters (except those listed in “External Mode Limitations” on page 6-46) in an external mode program are tunable; that is, you can change them by using the download mechanism described in this section.

If you select the **Inline parameters** option (on the **Optimization** pane of the Configuration Parameters dialog box), Real-Time Workshop embeds the numerical values of model parameters (constants), instead of symbolic

parameter names, in the generated code. Inlining parameters generates smaller and more efficient code. However, inlined parameters, because they effectively become constants, are not tunable.

Real-Time Workshop lets you improve overall efficiency by inlining most parameters, while at the same time retaining the flexibility of run-time tuning for selected parameters that are important to your application. When you inline parameters, you can use the Model Parameter Configuration dialog box to remove individual parameters from inlining and declare them to be tunable. In addition, the Model Parameter Configuration dialog box offers you options for controlling how parameters are represented in the generated code.

For more information on tunable parameters, see “Parameter Storage, Interfacing, and Tuning” on page 5-2.

Automatic Parameter Uploading on Host/Target Connection

Each time Simulink connects to a target program that was generated with **Inline parameters** on, the target program uploads the current value of its tunable parameters (if any) to the host. These values are assigned to the corresponding MATLAB workspace variables. This procedure ensures that the host and target are synchronized with respect to parameter values.

All workspace variables required by the model must be initialized at the time of host/target connection. Otherwise the uploading cannot proceed and an error results. Once the connection is made, these variables are updated to reflect the current parameter values on the target system.

Automatic parameter uploading takes place only if the target program was generated with **Inline parameters** on. “The Download Mechanism” on page 6-28 describes the operation of external mode communications with **Inline parameters** off.

Client/Server Implementations

In this section...
“Introduction” on page 6-32
“Using the TCP/IP Implementation” on page 6-32
“Using the Serial Implementation” on page 6-35
“Running the External Program” on page 6-37
“Implementing an External Mode Protocol Layer” on page 6-39

Introduction

Real-Time Workshop provides code to implement both the client and server side using either TCP/IP or serial protocols. You can use the socket-based external mode implementation provided by Real-Time Workshop with the generated code, provided that your target system supports TCP/IP. If not, use or customize the serial transport layer option provided.

A low-level *transport layer* handles physical transmission of messages. Both Simulink and the model code are independent of this layer. Both the transport layer and code directly interfacing to the transport layer are isolated in separate modules that format, transmit, and receive messages and data packets.

See “Target Interfacing” on page 6-13 for information on selecting a transport layer.

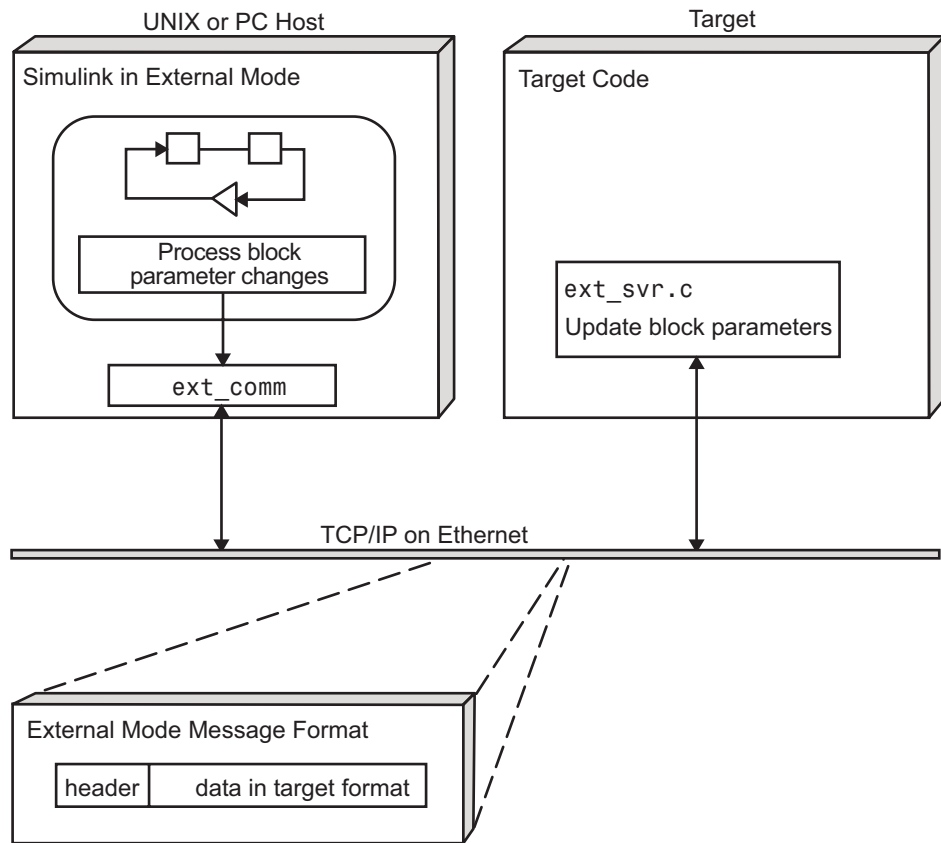
Using the TCP/IP Implementation

You can use TCP/IP-based client/server implementation of external mode with real-time programs on a UNIX or PC system. Chapter 13, “Targeting Tornado for Real-Time Applications” shows the use of external mode in the Tornado environment. For help in customizing external mode transport layers, see “Creating an External Mode Communication Channel” on page 17-23.

To use Simulink external mode over TCP/IP, you must

- Correctly specify the name of the external interface MEX-file in *matlabroot/toolbox/simulink/simulink/extmode_transports.m*. The name of the interface appears as uneditable text in the **Host/Target interface** section of the **Interface** pane of the Configuration Parameters dialog box. The TCP/IP default is `ext_comm`.
- Be sure that the template makefile is configured to link the proper source files for the TCP/IP server code and that it defines the necessary compiler flags when building the generated code.
- Build the external program.
- Run the external program.
- Set Simulink to external mode and connect to the target.

The next figure shows the structure of the TCP/IP-based implementation.



TCP/IP-Based Client/Server Implementation for External Mode

MEX-File Optional Arguments for TCP/IP Transport

In the External Target Interface dialog box, you can specify optional arguments that are passed to the external mode interface MEX-file for communicating with executing targets.

- Target network name: the network name of the computer running the external program. By default, this is the computer on which Simulink is running. The name can be
 - String delimited by single quotes, such as 'myPuter'
 - IP address delimited by single quotes, such as '148.27.151.12'

- **Verbosity level:** controls the level of detail of the information displayed during the data transfer. The value is either 0 or 1 and has the following meaning:
 - 0 — No information
 - 1 — Detailed information
- **TCP/IP server port number:** The default value is 17725. You can change the port number to a value between 256 and 65535 to avoid a port conflict if necessary.

The arguments are positional and must be specified in order. For example, if you want to specify the verbosity level (the second argument), then you must also specify the target network name (the first argument). Arguments can be delimited by whitespace or commas. For example:

```
'148.27.151.12' 1 30000
```

You can specify command-line options to the external program when you launch it. See “Running the External Program” on page 6-37 for more information.

Using the Serial Implementation

You control host/target communications on a serial channel in a similar fashion to doing so for a TCP/IP channel.

To use Simulink external mode over a serial channel, you must

- Execute the target and host on a Windows platform.
- Have the name of the external interface MEX-file correctly specified in *matlabroot/toolbox/simulink/simulink/extmode_transports.m*. The name of the interface will appear as uneditable text in the **Host/Target interface** section of the **Interface** pane of the Configuration Parameters dialog box. The serial default is `serial_win32`.
- Be sure that the template makefile is configured to link the proper source files for the serial server code and that it defines the necessary compiler flags when building the generated code.
- Build the external program.

- Run the external program.
- Set Simulink to external mode and connect to the target.

MEX-File Optional Arguments for Serial Transport

In the **MEX-file arguments** field of the **Interface** pane of the Configuration Parameters dialog box, you can specify arguments that are passed to the external mode interface MEX-file for communicating with the executing targets. For serial transport, the optional arguments to `ext_serial_win32_comm` are

- Verbosity level: controls the level of detail of the information displayed during the data transfer. The value is either 0 or 1 and has the following meaning:
 - 0 — No information
 - 1 — Detailed information
- Serial port ID (for example, 1 for COM1, and so on)

If the target program is executing on the same machine as the host and communications is through a loopback serial cable, the target's port ID must differ from that of the host (as specified in the **MEX-file arguments** edit field).

When you start the target program using a serial connection, you must specify the port ID to use to connect it to the host. Do this by including the `-port` command-line option. For example,

```
mytarget.exe -port 2 -w
```

- Baud rate (selected from the set 1200, 2400, 4800, 9600, 14400, 19200, 38400, 57600, 115200, with a default baud rate of 57600)

The arguments are positional and must be specified in order. For example, if you want to specify the serial port ID (the second argument), then you must also specify the verbosity level (the first argument). Arguments can be delimited by whitespace or commas. For example:

```
1 1 115200
```

You can specify command-line options to the external program when you launch it. The following section provides details on using command-line arguments.

Running the External Program

The external program must be running before you can use Simulink in external mode. To run the external program, you type a command of the form

```
model -opt1 ... -optN
```

where *model* is the name of the external program and *-opt1 ... -optN* are options. (See “Command-Line Options for the External Program” on page 6-38.) In the examples in this section, the name of the external program is assumed to be *ext_example*.

Running the External Program Under Windows

In the Windows environment, you can run the external programs in either of the following ways:

- Open a Command Prompt window. At the command prompt, type the name of the target executable, followed by any options, as in the following example:

```
ext_example -tf inf -w
```

- Alternatively, you can launch the target executable from the MATLAB command prompt. In this case the command must be preceded by an exclamation point (!) and followed by an ampersand (&), as in the following example:

```
!ext_example -tf inf -w &
```

The ampersand (&) causes the operating system to spawn another process to run the target executable. If you do not include the ampersand, the program still runs, but you will be unable to communicate commands to MATLAB or manually terminate the executable.

Running the External Program Under UNIX

In the UNIX environment, you can run the external programs in either of the following ways:

- Open an Xterm window. At the command prompt, type the name of the target executable, followed by any options, as in the following example:

```
ext_example -tf inf -w
```

- Alternatively, you can launch the target executable from the MATLAB command prompt. In the UNIX environment, if you start the external program from MATLAB, you must run it in the background so that you can still access Simulink. The command must be preceded by an exclamation point (!) and followed by an ampersand (&), as in the following example:

```
!ext_example -tf inf -w &
```

runs the executable from MATLAB by spawning another process to run it.

Command-Line Options for the External Program

External mode target executables generated by Real-Time Workshop support the following command-line options:

- `-tf n` option

The `-tf` option overrides the stop time set for the model in Simulink. The argument `n` specifies the number of seconds the program will run. The value `inf` directs the model to run indefinitely. In this case, the model code will run until the target program receives a stop message from Simulink.

The following example sets the stop time to 10 seconds.

```
ext_example -tf 10
```

When integer-only ERT targets are built and executed in external mode, the stop time parameter (`-tf`) is interpreted by the target as the number of base rate ticks rather than the number of seconds to execute. See “Using External Mode with the ERT Target” in the Real-Time Workshop Embedded Coder documentation.

Note The `-tf` option works with GRT, GRT malloc, ERT, RSim, and Tornado targets. If you are creating a custom target and want to support the `-tf` option, you must implement the option yourself. See “Creating an External Mode Communication Channel” on page 17-23 for more information.

- `-w` option: Instructs the target program to enter a wait state until it receives a message from the host. At this point, the target is running, but not executing the model code. The start message is sent when you select **Start Real-Time Code** from the **Simulation** menu or click the **Start real-time code** button in the External Mode Control Panel.

Use the `-w` option if you want to view data from time step 0 of the target program execution, or if you want to modify parameters before the target program begins execution of model code.

- `-port n` option: Specifies the TCP/IP port number, `n`, for the target program. The port number of the target program must match that of the host. The default port number is 17725. The port number must be a value between 256 and 65535.

Note The `-tf`, `-w`, and `-port` options are supported by the TCP/IP and serial transport layer modules shipped with Real-Time Workshop (although `-port` is interpreted differently by each). The `-baud` option is serial only. By default, these modules are linked into external mode target executables. If you are implementing a custom external mode transport layer and want to support these options, you must implement them in your code.

Implementing an External Mode Protocol Layer

If you want to implement your own transport layer for external mode communication, you must modify certain code modules provided by Real-Time Workshop and create a new external interface MEX-file. This advanced topic is described in detail in “Creating an External Mode Communication Channel” on page 17-23.

Using External Mode Programmatically

You can run external-mode applications from the MATLAB command line or programmatically in scripts. Use the `get_param` and `set_param` commands to retrieve and set the values of model simulation command-line parameters, such as `SimulationMode` and `SimulationCommand`, and external mode command-line parameters, such as `ExtModeCommand` and `ExtModeTrigType`. (For more information on using `get_param` and `set_param` to tune model parameters, see “Parameter Tuning by Using MATLAB Commands” on page 5-28.)

The following sequence of model simulation commands assumes that a Simulink model is open and that you have loaded a target program to which the model will connect using external mode.

- 1 Change Simulink to external mode:

```
set_param(gcs, 'SimulationMode', 'external')
```

- 2 Connect the open model to the loaded target program:

```
set_param(gcs, 'SimulationCommand', 'connect')
```

- 3 Start running the target program:

```
set_param(gcs, 'SimulationCommand', 'start')
```

- 4 Stop running the target program:

```
set_param(gcs, 'SimulationCommand', 'stop')
```

- 5 Disconnect the target program from the model:

```
set_param(gcs, 'SimulationCommand', 'disconnect')
```

The next table lists external mode command-line parameters that you can use in `get_param` and `set_param` commands. The table provides brief descriptions, valid values (bold type highlights defaults), and a mapping to External Mode dialog box equivalents.

Note For external mode parameters that are equivalent to **Interface** pane options in the Configuration Parameters dialog box, see the ExtMode table entries in “Parameter Command-Line Information Summary”.

External Mode Command-Line Parameters

Parameter and Values	Dialog Box Equivalent	Description
ExtModeAddSuffixToVar off , on	Data Mode Archiving: Append file suffix to variable name check box	Increment variable names for each incremented filename.
ExtModeArchiveDirName <i>string</i>	Data Mode Archiving: Directory text box	Save data in specified directory.
ExtModeArchiveFileName <i>string</i>	Data Mode Archiving: File text box	Save data in specified file.
ExtModeArchiveMode <i>string</i> - off , on	Data Mode Archiving: Enable archiving check box	Activate automated data archiving features.
ExtModeArmWhenConnect off, on	External Signal & Triggering: Arm when connecting to target check box	Arm the trigger as soon as Real-Time Workshop connects to the target.
ExtModeAutoIncOneShot off , on	Data Mode Archiving: Increment file after one-shot check box	Save new data buffers in incremental files.
ExtModeAutoUpdateStatusClock (Windows only) off, on	Not available	Continuously upload and display target time on the model window status bar.
ExtModeBatchMode off , on	Control Panel: Batch download check box	Enable or disable downloading of parameters in batch mode.

External Mode Command-Line Parameters (Continued)

Parameter and Values	Dialog Box Equivalent	Description
ExtModeChangesPending off , on	Not available	When ExtModeBatchMode is enabled, indicates whether any parameters remain in the queue of parameters to be downloaded to the target.
ExtModeCommand <i>string</i>	Not available	Issue an external mode command to the target program.
ExtModeConnected off , on	Control Panel: Connect/Disconnect button	Indicate the state of the connection with the target program.
ExtModeEnableFloating off, on	Control Panel: Enable data uploading check box	Enable or disable the arming and canceling of triggers when a connection is established with floating scopes.
ExtModeIncDirWhenArm off , on	Data Mode Archiving: Increment directory when trigger armed check box	Write log files to incremental directories each time the trigger is armed.
ExtModeLogAll off, on	External Signal & Triggering: Select all check box	Upload all available signals from the target to the host.
ExtModeLogCtrlPanelDlg <i>string</i>	Not available	Return a handle to the External Mode Control Panel dialog box or -1 if the dialog box does not exist.

External Mode Command-Line Parameters (Continued)

Parameter and Values	Dialog Box Equivalent	Description
ExtModeParamChangesPending off , on	Not available	When Real-Time Workshop is connected to the target and ExtModeBatchMode is enabled, indicates whether any parameters remain in the queue of parameters to be downloaded to the target. More efficient than ExtModeChangesPending because it checks for a connection to the target.
ExtModeSkipDownloadWhenConnect off , on	Not available	Connect to the target program without downloading parameters.
ExtModeTrigDelay <i>integer</i> (0)	External Signal & Triggering: Delay text box	Specify the amount of time that elapses between a trigger occurrence and the start of data collection.
ExtModeTrigDirection <i>string</i> - rising , falling, either	External Signal & Triggering: Direction menu	Specify the direction in which the signal must be traveling when it crosses the threshold value.
ExtModeTrigDuration <i>integer</i> (1000)	External Signal & Triggering: Direction menu	Specify the number of base rate steps for which external mode is to log data after a trigger event.
ExtModeTrigDurationFloating <i>string</i> - <i>integer</i> (auto)	Control Panel: Duration text box	Specify the duration for floating scopes. If auto is specified, the value of ExtModeTrigDuration is used.

External Mode Command-Line Parameters (Continued)

Parameter and Values	Dialog Box Equivalent	Description
ExtModeTrigElement <i>string</i> - <i>integer</i> , any , last	External Signal & Triggering: Element text field	Specify the elements of the input port of the specified trigger block that can cause the trigger to fire.
ExtModeTrigHoldOff <i>integer</i> (0)	External Signal & Triggering: Hold-off text field	Specify the base rate steps between when a trigger event terminates and the trigger is rearmed.
ExtModeTrigLevel <i>integer</i> (0)	External Signal & Triggering: Level text field	Specify the threshold value the trigger signal must cross to fire the trigger.
ExtModeTrigMode <i>string</i> - normal , oneshot	External Signal & Triggering: Mode menu	Specify whether the trigger is to rearm automatically after each trigger event or whether only one buffer of data is to be collected each time the trigger is armed.
ExtModeTrigPort <i>string</i> - <i>integer</i> (1), last	External Signal & Triggering: Port text field	Specify the input port of the specified trigger block for which elements can cause the trigger to fire.
ExtModeTrigType <i>string</i> - manual , signal	External Signal & Triggering: Source text field	Specify whether to start logging data when the trigger is armed or when a specified trigger signal satisfies trigger conditions.

External Mode Command-Line Parameters (Continued)

Parameter and Values	Dialog Box Equivalent	Description
ExtModeUploadStatus off , on	Not available	Return the status of the upload mechanism — uploading, inactive, and so on.
ExtModeWriteAllDataToWs off , on	Data Mode Archiving: Write intermediate results to workspace check box	Write all intermediate results to the workspace.

External Mode Limitations

In this section...
“Limitations on Changing Parameters” on page 6-46
“Limitation on Mixing 32-bit and 64-bit Architectures” on page 6-47

Limitations on Changing Parameters

In general, you cannot change a parameter if doing so results in a change in the structure of the model. For example, you cannot change

- The number of states, inputs, or outputs of any block
- The sample time or the number of sample times
- The integration algorithm for continuous systems
- The name of the model or of any block
- The parameters to the Fcn block

If you cause any of these changes to the block diagram, then you must rebuild the program with newly generated code.

However, you can change parameters in transfer function and state space representation blocks in specific ways:

- The parameters (numerator and denominator polynomials) for the Transfer Fcn (continuous and discrete) and Discrete Filter blocks can be changed (as long as the number of states does not change).
- Zero entries in the State-Space and Zero Pole (both continuous and discrete) blocks in the user-specified or computed parameters (that is, the A, B, C, and D matrices obtained by a zero-pole to state-space transformation) cannot be changed once external simulation is started.
- In the State-Space block, if you specify the matrices in the controllable canonical realization, then all changes to the A, B, C, D matrices that preserve this realization and the dimensions of the matrices are allowed.

Note Opening a dialog box for a source block causes Simulink to pause. While Simulink is paused, you can edit the parameter values. You must close the dialog box to have the changes take effect and allow Simulink to continue.

If the Simulink block diagram does not match the external program, Simulink displays an error informing you that the checksums do not match (that is, the model has changed since you generated code). This means that you must rebuild the program from the new block diagram (or reload the correct one) to use external mode.

If the external program is not running, Simulink displays an error informing you that it cannot connect to the external program.

Limitation on Mixing 32-bit and 64-bit Architectures

When you use external mode, the machine running Simulink and the machine running the target executable must have matching bit architectures, either 32-bit or 64-bit. This is because Real-Time Workshop varies a model's checksum based on whether it is configured for a 32-bit or 64-bit platform.

If you attempt to connect from a 32-bit machine to a 64-bit machine or vice versa, the external mode connection fails.

Program Architecture

Code is generated by Real-Time Workshop in two styles, depending whether a target is embedded or not. In addition, the structure of code is affected by whether a multitasking environment is available for execution, and on what system and applications modules must be incorporated.

Introduction (p. 7-2)

Introduces code styles and targets appropriate for development of rapid prototyping and embedded systems

Model Execution (p. 7-4)

Explains how code generated from models executes, including single-tasking and multitasking execution, timing, data structures, entry points, and differences between rapid prototyping and embedded code

Rapid Prototyping Program Framework (p. 7-24)

Discusses the overall architecture and individual components of programs generated by rapid prototyping targets

Embedded Program Framework (p. 7-37)

Gives an overview of the architecture of programs generated by Real-Time Workshop Embedded Coder

For a detailed discussion of the structure of embedded real-time code, see the Real-Time Workshop Embedded Coder documentation.

Introduction

Real-Time Workshop generates two styles of code. One code style is suitable for rapid prototyping (and simulation by using code generation). The other style is suitable for embedded applications. This chapter discusses the program architecture, that is, the structure of code generated by Real-Time Workshop, associated with these two styles of code. The next table classifies the targets shipped with Real-Time Workshop. For related details about code style and target characteristics, see “Choosing a Code Format for Your Application” on page 3-10.

Code Styles Listed by Target

Target	Code Style (Using C or C++ Unless Noted)
Real-Time Workshop Embedded Coder embedded real-time (ERT) target	Embedded — Useful as a starting point when using generated C/C++ code in an embedded application (often referred to as a <i>production code target</i>).
Real-Time Workshop Generic real-time (GRT) target	Rapid prototyping — Use as a starting point for creating a rapid prototyping target that does not use real-time operating system tasking primitives, and for verifying the generated code on your workstation. Uses components of ERT, with a different calling interface.
Real-time malloc target	Rapid prototyping — Similar to the generic real-time (GRT) target except that this target allocates all model working memory dynamically rather than statically declaring it in advance.
Rapid simulation target (RSim)	Rapid prototyping — Non-real-time simulation of your model on your workstation. Useful as a high-speed or batch simulation tool.
S-function target	Rapid prototyping — Creates a C-MEX S-function for simulation of your model within another Simulink model; useful for intellectual property protection.

Code Styles Listed by Target (Continued)

Target	Code Style (Using C or C++ Unless Noted)
Tornado (VxWorks) real-time target	Rapid prototyping — Runs model in real time using the VxWorks real-time operating system tasking primitives. Also useful as a starting point for targeting a real-time operating system.
Real-Time Windows target	Rapid prototyping — Runs model in real time at interrupt level while your PC is running Microsoft Windows in the background.
xPC target	Rapid prototyping — Runs model in real time on target PC running xPC kernel.

Third-party vendors supply additional targets for Real-Time Workshop. Generally, these can be classified as rapid prototyping targets. For more information about third-party products, see the MathWorks Connections Program Web page: <http://www.mathworks.com/products/connections>.

This chapter is divided into three sections. The first section discusses model execution, the second section discusses the rapid prototyping style of code, and the third section discusses the embedded style of code.

Model Execution

In this section...

“Introduction” on page 7-4

“Models for Non-Real-Time Single-Tasking Systems” on page 7-6

“Models for Non-Real-Time Multitasking Systems” on page 7-7

“Models for Real-Time Single-Tasking Systems” on page 7-8

“Models for Real-Time Multitasking Systems” on page 7-9

“Models for Multitasking Systems that Use Real-Time Tasking Primitives” on page 7-12

“Program Timing” on page 7-13

“Program Execution” on page 7-14

“External Mode Communication” on page 7-15

“Data Logging in Single-Tasking and Multitasking Model Execution” on page 7-15

“Rapid Prototyping and Embedded Model Execution Differences” on page 7-16

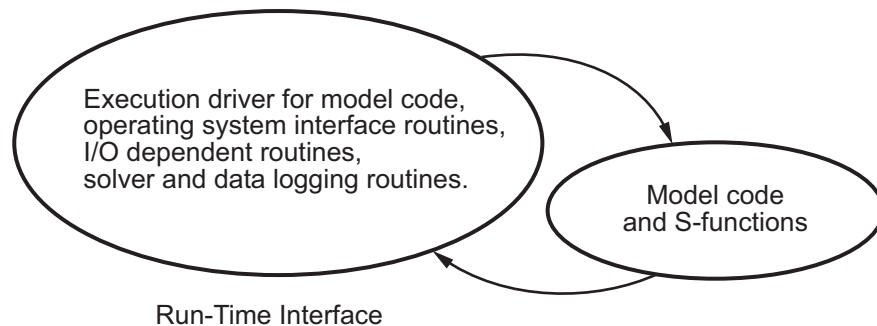
“Rapid Prototyping Model Functions” on page 7-17

“Embedded Model Functions” on page 7-23

Introduction

Before looking at the two styles of generated code, you need to have a high-level understanding of how the generated model code is executed. Real-Time Workshop generates algorithmic code as defined by your model. You can include your own code in your model by using S-functions. S-functions can range from high-level signal manipulation algorithms to low-level device drivers.

Real-Time Workshop also provides a run-time interface that executes the generated model code. The run-time interface and model code are compiled together to create the model executable. The next figure shows a high-level object-oriented view of the executable.



The Object-Oriented View of a Real-Time Program

In general, the conceptual design of the model execution driver does not change between the rapid prototyping and embedded style of generated code. The following sections describe model execution for single-tasking and multitasking environments both for simulation (non-real-time) and for real time. For most models, the multitasking environment will provide the most efficient model execution (that is, fastest sample rate).

The following concepts are useful in describing how models execute. Function names used in ERT and GRT targets are shown, followed by the comparable GRT-compatible calls in parentheses.

- **Initialization:** *model_initialize* (MdlInitializeSizes, MdlInitializeSampleTimes, MdlStart) initializes the run-time interface code and the model code.
- **ModelOutputs:** Calling all blocks in your model that have a sample hit at the current time and having them produce their output. *model_output* (MdlOutputs) can be done in major or minor time steps. In major time steps, the output is a given simulation time step. In minor time steps, the run-time interface integrates the derivatives to update the continuous states.
- **ModelUpdate:** *model_update* (MdlUpdate) calls all blocks in your model that have a sample hit at the current point in time and has them update their discrete states or similar type objects.
- **ModelDerivatives:** Calling all blocks in your model that have continuous states and having them update their derivatives. *model_derivatives* is only called in minor time steps.

- **ModelTerminate:** *model_terminate* (MdlTerminate) terminates the program if it is designed to run for a finite time. It destroys the real-time model data structure, deallocates memory, and can write data to a file.

The identifying names in the preceding list (ModelOutputs, and so on) identify functions in pseudocode examples shown in the following sections.

- “Models for Non-Real-Time Single-Tasking Systems” on page 7-6
- “Models for Non-Real-Time Multitasking Systems” on page 7-7
- “Models for Real-Time Single-Tasking Systems” on page 7-8
- “Models for Real-Time Multitasking Systems” on page 7-9
- “Models for Multitasking Systems that Use Real-Time Tasking Primitives” on page 7-12

For a complete set of correspondences between GRT and ERT function identifiers, see the table Identifiers for Real-Time Model Data Structure Variants on page 7-32.

Models for Non-Real-Time Single-Tasking Systems

The pseudocode below shows the execution of a model for a non-real-time single-tasking system.

```
main()
{
  Initialization
  While (time < final time)
    ModelOutputs      -- Major time step.
    LogTXY            -- Log time, states and root outputs.
    ModelUpdate       -- Major time step.
    Integrate         -- Integration in minor time step for
                      -- models with continuous states.

    ModelDerivatives
    Do 0 or more
      ModelOutputs
      ModelDerivatives
    EndDo -- Number of iterations depends upon the solver
    Integrate derivatives to update continuous states.
```

```

        EndIntegrate
    EndWhile
    Termination
}

```

The initialization phase begins first. This consists of initializing model states and setting up the execution engine. The model then executes, one step at a time. First ModelOutputs executes at time t , then the workspace I/O data is logged, and then ModelUpdate updates the discrete states. Next, if your model has any continuous states, ModelDerivatives integrates the continuous states' derivatives to generate the states for time $t_{new} = t + h$, where h is the step size. Time then moves forward to t_{new} and the process repeats.

During the ModelOutputs and ModelUpdate phases of model execution, only blocks that reach the current point in time execute.

Models for Non-Real-Time Multitasking Systems

The pseudocode below shows the execution of a model for a non-real-time multitasking system.

```

main()
{
    Initialization
    While (time < final time)
        ModelOutputs(tid=0)    -- Major time step.
        LogTXY                 -- Log time, states, and root
                               -- outputs.
        ModelUpdate(tid=0)     -- Major time step.
        Integrate              -- Integration in minor time step for
                               -- models with continuous states.
        ModelDerivatives
        Do 0 or more
            ModelOutputs(tid=0)
            ModelDerivatives
        EndDo (Number of iterations depends upon the solver.)
        Integrate derivatives to update continuous states.
    EndIntegrate
    For i=1:NumTids

```

```
        ModelOutputs(tid=i) -- Major time step.
        ModelUpdate(tid=i)  -- Major time step.
    EndFor
EndWhile
Termination
}
```

Multitasking operation is more complex than single-tasking execution because the output and update functions are subdivided by the *task identifier* (*tid*) that is passed into these functions. This allows for multiple invocations of these functions with different task identifiers using overlapped interrupts, or for multiple tasks when using a real-time operating system. In simulation, multiple tasks are emulated by executing the code in the order that would occur if there were no preemption in a real-time system.

Multitasking execution assumes that all tasks are multiples of the base rate. Simulink enforces this when you create a fixed-step multitasking model. The multitasking execution loop is very similar to that of single-tasking, except for the use of the task identifier (*tid*) argument to `ModelOutputs` and `ModelUpdate`.

Models for Real-Time Single-Tasking Systems

The pseudocode below shows the execution of a model in a real-time single-tasking system where the model is run at interrupt level.

```
rtOneStep()
{
    Check for interrupt overflow
    Enable "rtOneStep" interrupt
    ModelOutputs    -- Major time step.
    LogTXY          -- Log time, states and root outputs.
    ModelUpdate     -- Major time step.
    Integrate       -- Integration in minor time step for models
                   -- with continuous states.

    ModelDerivatives
    Do 0 or more
        ModelOutputs
        ModelDerivatives
    EndDo (Number of iterations depends upon the solver.)
}
```



```

        Integrate derivatives to update continuous states.
    EndIntegrate
}

main()
{
    Initialization (including installation of rtOneStep as an
    interrupt service routine, ISR, for a real-time clock).
    While(time < final time)
        Background task.
    EndWhile
    Mask interrupts (Disable rtOneStep from executing.)
    Complete any background tasks.
    Shutdown
}

```

Real-time single-tasking execution is very similar to non-real-time single-tasking execution, except that instead of free-running the code, the `rt_OneStep` function is driven by a periodic timer interrupt.

At the interval specified by the program's base sample rate, the interrupt service routine (ISR) preempts the background task to execute the model code. The base sample rate is the fastest in the model. If the model has continuous blocks, then the integration step size determines the base sample rate.

For example, if the model code is a controller operating at 100 Hz, then every 0.01 seconds the background task is interrupted. During this interrupt, the controller reads its inputs from the analog-to-digital converter (ADC), calculates its outputs, writes these outputs to the digital-to-analog converter (DAC), and updates its states. Program control then returns to the background task. All these steps must occur before the next interrupt.

Models for Real-Time Multitasking Systems

The following pseudocode shows how a model executes in a real-time multitasking system where the model is run at interrupt level.

```

rtOneStep()
{
    Check for interrupt overflow
}

```

```
Enable "rtOneStep" interrupt
ModelOutputs(tid=0)    -- Major time step.
LogTXY                -- Log time, states and root outputs.
ModelUpdate(tid=0)    -- Major time step.
Integrate             -- Integration in minor time step for
                    -- models with continuous states.

    ModelDerivatives
    Do 0 or more
        ModelOutputs(tid=0)
        ModelDerivatives
    EndDo (Number of iterations depends upon the solver.)
    Integrate derivatives and update continuous states.
EndIntegrate
For i=1:NumTasks
    If (hit in task i)
        ModelOutputs(tid=i)
        ModelUpdate(tid=i)
    EndIf
EndFor
}

main()
{
    Initialization (including installation of rtOneStep as an
        interrupt service routine, ISR, for a real-time clock).
    While(time < final time)
        Background task.
    EndWhile
    Mask interrupts (Disable rtOneStep from executing.)
    Complete any background tasks.
    Shutdown
}
```

Running models at interrupt level in a real-time multitasking environment is very similar to the previous single-tasking environment, except that overlapped interrupts are employed for concurrent execution of the tasks.

The execution of a model in a single-tasking or multitasking environment when using real-time operating system tasking primitives is very similar to

the interrupt-level examples discussed above. The pseudocode below is for a single-tasking model using real-time tasking primitives.

```

tSingleRate()
{
  MainLoop:
    If clockSem already "given", then error out due to overflow.
    Wait on clockSem
    ModelOutputs           -- Major time step.
    LogTXY                 -- Log time, states and root
                           -- outputs
    ModelUpdate            -- Major time step
    Integrate              -- Integration in minor time step
                           -- for models with continuous
                           -- states.

    ModelDerivatives
    Do 0 or more
      ModelOutputs
      ModelDerivatives
    EndDo (Number of iterations depends upon the solver.)
    Integrate derivatives to update continuous states.
  EndIntegrate
EndMainLoop
}

main()
{
  Initialization
  Start/spawn task "tSingleRate".
  Start clock that does a "semGive" on a clockSem semaphore.
  Wait on "model-running" semaphore.
  Shutdown
}

```

In this single-tasking environment, the model executes as real-time operating system tasking primitives. In this environment, create a single task (tSingleRate) to run the model code. This task is invoked when a clock tick occurs. The clock tick gives a clockSem (clock semaphore) to the model task (tSingleRate). The model task waits for the semaphore before executing. The clock ticks occur at the fundamental step size (base rate) for your model.

Models for Multitasking Systems that Use Real-Time Tasking Primitives

The pseudocode below is for a multitasking model using real-time tasking primitives.

```

tSubRate(subTaskSem,i)
{
  Loop:
    Wait on semaphore subTaskSem.
    ModelOutputs(tid=i)
    ModelUpdate(tid=i)
  EndLoop
}
tBaseRate()
{
  MainLoop:
    If clockSem already "given", then error out due to overflow.
    Wait on clockSem
    For i=1:NumTasks
      If (hit in task i)
        If task i is currently executing, then error out due to
        overflow.
        Do a "semGive" on subTaskSem for task i.
      EndIf
    EndFor
    ModelOutputs(tid=0)    -- major time step.
    LogTXY                -- Log time, states and root outports.
    ModelUpdate(tid=0)    -- major time step.
    Loop:                 -- Integration in minor time step for
                        -- models with continuous states.

      ModelDerivatives
      Do 0 or more
        ModelOutputs(tid=0)
        ModelDerivatives
      EndDo (number of iterations depends upon the solver).
      Integrate derivatives to update continuous states.
    EndLoop
  EndMainLoop
}
main()

```

```
{
  Initialization
  Start/spawn task "tSubRate".
  Start/spawn task "tBaseRate".

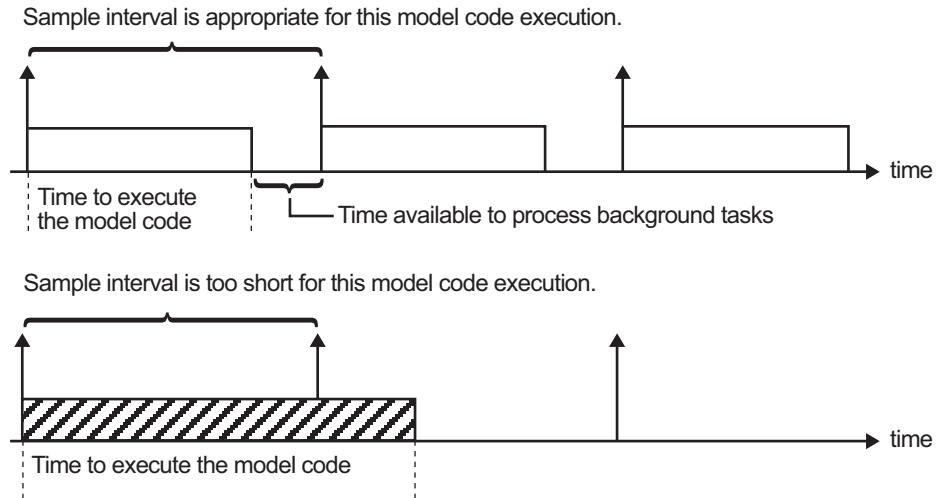
  Start clock that does a "semGive" on a clockSem semaphore.
  Wait on "model-running" semaphore.
  Shutdown
}
```

In this multitasking environment, the model is executed using real-time operating system tasking primitives. Such environments require several model tasks (tBaseRate and several tSubRate tasks) to run the model code. The base rate task (tBaseRate) has a higher priority than the subrate tasks. The subrate task for tid=1 has a higher priority than the subrate task for tid=2, and so on. The base rate task is invoked when a clock tick occurs. The clock tick gives a clockSem to tBaseRate. The first thing tBaseRate does is give semaphores to the subtasks that have a hit at the current point in time. Because the base rate task has a higher priority, it continues to execute. Next it executes the fastest task (tid=0), consisting of blocks in your model that have the fastest sample time. After this execution, it resumes waiting for the clock semaphore. The clock ticks are configured to occur at the fundamental step size for your model.

Program Timing

Real-time programs require careful timing of the task invocations (either by using an interrupt or a real-time operating system tasking primitive) to ensure that the model code executes to completion before another task invocation occurs. This includes time to read and write data to and from external hardware.

The next figure illustrates interrupt timing.



Task Timing

The sample interval must be long enough to allow model code execution between task invocations.

In the figure above, the time between two adjacent vertical arrows is the sample interval. The empty boxes in the upper diagram show an example of a program that can complete one step within the interval and still allow time for the background task. The gray box in the lower diagram indicates what happens if the sample interval is too short. Another task invocation occurs before the task is complete. Such timing results in an execution error.

Note also that, if the real-time program is designed to run forever (that is, the final time is 0 or infinite so the while loop never exits), then the shutdown code never executes.

For more information on how the timing engine works, see Chapter 15, “Timing Services”.

Program Execution

As the previous section indicates, a real-time program cannot require 100% of the CPU’s time. This provides an opportunity to run background tasks during the free time.

Background tasks include operations such as writing data to a buffer or file, allowing access to program data by third-party data monitoring tools, or using Simulink external mode to update program parameters.

It is important, however, that the program be able to preempt the background task at the appropriate time to ensure real-time execution of the model code.

The way the program manages tasks depends on capabilities of the environment in which it operates.

External Mode Communication

External mode allows communication between the Simulink block diagram and the standalone program that is built from the generated code. In this mode, the real-time program functions as an interprocess communication server, responding to requests from Simulink.

Data Logging in Single-Tasking and Multitasking Model Execution

The Real-Time Workshop data-logging features, described in “Configuring a Model for Data Logging” on page 2-25, enable you to save system states, outputs, and time to a MAT-file at the completion of the model execution. The LogTXY function, which performs data logging, operates differently in single-tasking and multitasking environments.

If you examine how LogTXY is called in the single-tasking and multitasking environments, you will notice that for single-tasking LogTXY is called after ModelOutputs. During this ModelOutputs call, all blocks that have a hit at time t execute, whereas in multitasking, LogTXY is called after ModelOutputs(tid=0), which executes only the blocks that have a hit at time t and that have a task identifier of 0. This results in differences in the logged values between single-tasking and multitasking logging. Specifically, consider a model with two sample times, the faster sample time having a period of 1.0 second and the slower sample time having a period of 10.0 seconds. At time $t = k*10$, $k=0,1,2...$ both the fast (tid=0) and slow (tid=1) blocks execute. When executing in multitasking mode, when LogTXY is called, the slow blocks execute, but the previous value is logged, whereas in single-tasking the current value is logged.

Another difference occurs when logging data in an enabled subsystem. Consider an enabled subsystem that has a slow signal driving the enable port and fast blocks within the enabled subsystem. In this case, the evaluation of the enable signal occurs in a slow task, and the fast blocks see a delay of one sample period; thus the logged values will show these differences.

To summarize differences in logged data between single-tasking and multitasking, differences will be seen when

- Any root output block has a sample time that is slower than the fastest sample time
- Any block with states has a sample time that is slower than the fastest sample time
- Any block in an enabled subsystem where the signal driving the enable port is slower than the rate of the blocks in the enabled subsystem

For the first two cases, even though the logged values are different between single-tasking and multitasking, the model results are not different. The only real difference is where (at what point in time) the logging is done. The third (enabled subsystem) case results in a delay that can be seen in a real-time environment.

Rapid Prototyping and Embedded Model Execution Differences

The rapid prototyping program framework provides a common application programming interface (API) that does not change between model definitions.

Real-Time Workshop Embedded Coder provides a different framework called the embedded program framework. The embedded program framework provides an optimized API that is tailored to your model. When you use the embedded style of generated code, you are modeling how you would like your code to execute in your embedded system. Therefore, the definitions defined in your model should be specific to your embedded targets. Items such as the model name, parameter, and signal storage class are included as part of the API for the embedded style of code.

One major difference between the rapid prototyping and embedded style of generated code is that the latter contains fewer entry-point functions. The

embedded style of code can be configured to have only one run-time function, *model_step*.

Thus, when you look again at the model execution pseudocode presented earlier in this chapter, you can eliminate the `Loop...EndLoop` statements, and group `ModelOutputs`, `LogTXY`, and `ModelUpdate` into a single statement, *model_step*.

For a detailed discussion of how generated embedded code executes, see the Real-Time Workshop Embedded Coder documentation.

Rapid Prototyping Model Functions

The rapid prototyping code defines the following functions that interface with the run-time interface:

- `Model()`: The model registration function. This function initializes the work areas (for example, allocating and setting pointers to various data structures) needed by the model. The model registration function calls the `MdlInitializeSizes` and `MdlInitializeSampleTimes` functions. These two functions are very similar to the S-function `mdlInitializeSizes` and `mdlInitializeSampleTimes` methods.
- `MdlStart(void)`: After the model registration functions `MdlInitializeSizes` and `MdlInitializeSampleTimes` execute, the run-time interface starts execution by calling `MdlStart`. This routine is called once at startup.

The function `MdlStart` has four basic sections:

- Code to initialize the states for each block in the root model that has states. A subroutine call is made to the “initialize states” routines of conditionally executed subsystems.
- Code generated by the one-time initialization (start) function for each block in the model.
- Code to enable the blocks in the root model that have enable methods, and the blocks inside triggered or function-call subsystems residing in the root model. Simulink blocks can have enable and disable methods. An enable method is called just before a block starts executing, and the disable method is called just after the block stops executing.

- Code for each block in the model that has a constant sample time.
- `MdlOutputs(int_T tid)`: `MdlOutputs` updates the output of blocks at appropriate times. The `tid` (task identifier) parameter identifies the task that in turn maps when to execute blocks based upon their sample time. This routine is invoked by the run-time interface during major and minor time steps. The major time steps are when the run-time interface is taking an actual time step (that is, it is time to execute a specific task). If your model contains continuous states, the minor time steps will be taken. The minor time steps are when the solver is generating integration stages, which are points between major outputs. These integration stages are used to compute the derivatives used in advancing the continuous states. The solver is called to updates
- `MdlUpdate(int_T tid)`: `MdlUpdate` updates the states and work vector state information (that is, states that are neither continuous nor discrete) saved in work vectors. The `tid` (task identifier) parameter identifies the task that in turn indicates which sample times are active, allowing you to conditionally update only states of active blocks. This routine is invoked by the run-time interface after the major `MdlOutputs` has been executed. The solver is also called, and `model_Derivatives` is called in minor steps by the solver during its integration stages. All blocks that have continuous states have an identical number of derivatives. These blocks are required to compute the derivatives so that the solvers can integrate the states.
- `MdlTerminate(void)`: `MdlTerminate` contains any block shutdown code. `MdlTerminate` is called by the run-time interface, as part of the termination of the real-time program.

The contents of the above functions are directly related to the blocks in your model. A Simulink block can be generalized to the following set of equations.

$$y = f_0(t, x_c, x_d, u)$$

Output y is a function of continuous state x_c , discrete state x_d , and input u . Each block writes its specific equation in the appropriate section of `MdlOutput`.

$$x_{d+1} = f_u(t, x_d, u)$$

The discrete states x_d are a function of the current state and input. Each block that has a discrete state updates its state in `MdlUpdate`.

$$\dot{x} = f_d(t, x_c, u)$$

The derivatives x are a function of the current input. Each block that has continuous states provides its derivatives to the solver (for example, ode5) in *model_Derivatives*. The derivatives are used by the solver to integrate the continuous state to produce the next value.

The output, y , is generally written to the block I/O structure. Root-level Output blocks write to the external outputs structure. The continuous and discrete states are stored in the states structure. The input, u , can originate from another block's output, which is located in the block I/O structure, an external input (located in the external inputs structure), or a state. These structures are defined in the *model.h* file that Real-Time Workshop generates.

The next example shows the general contents of the rapid prototyping style of C code written to the *model.c* file.

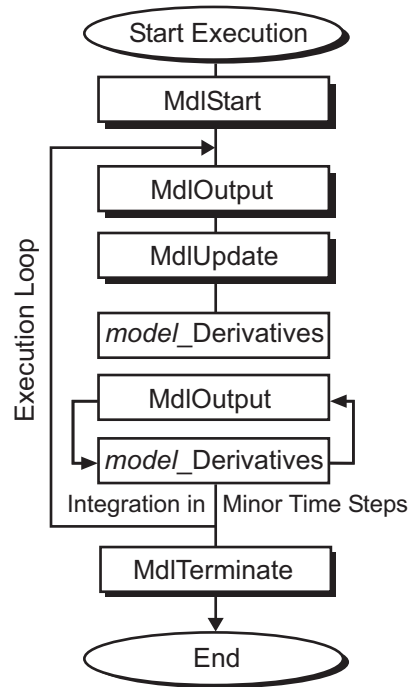
```
/*
 * Version, Model options, TLC options,
 * and code generation information are placed here.
 */
<includes>
void MdlStart(void)
{
    /*
     * State initialization code.
     * Model start-up code - one time initialization code.
     * Execute any block enable methods.
     * Initialize output of any blocks with constant sample times.
     */
}

void MdlOutputs(int_T tid)
{
    /* Compute: y = f0(t,xc,xd,u) for each block as needed. */
}

void MdlUpdate(int_T tid)
{
    /* Compute: xd+1 = fu(t,xd,u) for each block as needed. */

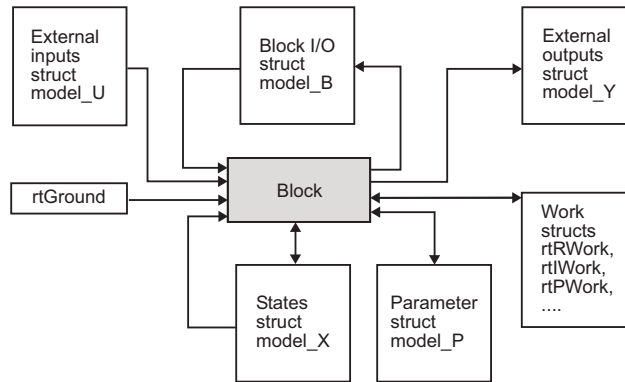
    /* Compute: dxc = fd(t,xc,u) for each block in model_derivatives
       as needed. */
}
void MdlTerminate(void)
{
    /* Perform shutdown code for any blocks that
       have a termination action */
}
}
```

The next figure shows a flow chart describing the execution of the rapid prototyping generated code.



Rapid Prototyping Execution Flow Chart

Each block places code in specific Mdl routines according to the algorithm that it is implementing. Blocks have input, output, parameters, and states, as well as other general items. For example, in general, block inputs and outputs are written to a block I/O structure (*model_B*). Block inputs can also come from the external input structure (*model_U*) or the state structure when connected to a state port of an integrator (*model_X*), or ground (*rtGround*) if unconnected or grounded. Block outputs can also go to the external output structure (*model_Y*). The next figure shows the general mapping between these items.



Data View of the Generated Code

The following list defines the structures shown in the preceding figure:

- Block I/O structure (*model_B*): This structure consists of persistent block output signals. The number of block output signals is the sum of the widths of the data output ports of all nonvirtual blocks in your model. If you activate block I/O optimizations, Simulink and Real-Time Workshop reduce the size of the *model_B* structure by
 - Reusing the entries in the *model_B* structure
 - Making other entries local variables

See “Signal Storage, Optimization, and Interfacing” on page 5-31 for more information on these optimizations.

Structure field names are determined either by the block’s output signal name (when present) or by the block name and port number when the output signal is left unlabeled.

- Block states structures: The continuous states structure (*model_X*) contains the continuous state information for any blocks in your model that have continuous states. Discrete states are stored in a data structure called the *DWork vector* (*model_DWork*).
- Block parameters structure (*model_P*): The parameters structure contains all block parameters that can be changed during execution (for example, the parameter of a Gain block).

- External inputs structure (*model_U*): The external inputs structure consists of all root-level Inport block signals. Field names are determined by either the block's output signal name, when present, or by the Inport block's name when the output signal is left unlabeled.
- External outputs structure (*model_Y*): The external outputs structure consists of all root-level Outport blocks. Field names are determined by the root-level Outport block names in your model.
- Real work, integer work, and pointer work structures (*model_RWork*, *model_IWork*, *model_PWork*): Blocks might have a need for real, integer, or pointer work areas. For example, the Memory block uses a real work element for each signal. These areas are used to save internal states or similar information.

Embedded Model Functions

The Real-Time Workshop Embedded Coder target generates the following functions:

- *model_initialize*: Performs all model initialization and should be called once before you start executing your model.
- If the **Single output/update function** code generation option is selected, then you see
 - *model_step*: Contains the output and update code for all blocks in your model.

Otherwise, you see

- *model_output*: Contains the output code for all blocks in your model.
- *model_update*: Contains the update code for all blocks in your model.
- If the **Terminate function required** code generation option is selected, then you see
 - *model_terminate*: This contains all model shutdown code and should be called as part of system shutdown.

See “Model Entry Points” in the Real-Time Workshop Embedded Coder documentation for complete descriptions of these functions.

Rapid Prototyping Program Framework

In this section...

“Introduction” on page 7-24

“Rapid Prototyping Program Architecture” on page 7-24

“Rapid Prototyping System-Dependent Components” on page 7-25

“Rapid Prototyping System-Independent Components” on page 7-27

“Rapid Prototyping Application Components” on page 7-30

Introduction

The code modules generated from a Simulink mode—*model.c* (or *.cpp*), *model.h*, and other files — implement the model’s system equations, contain block parameters, and perform initialization.

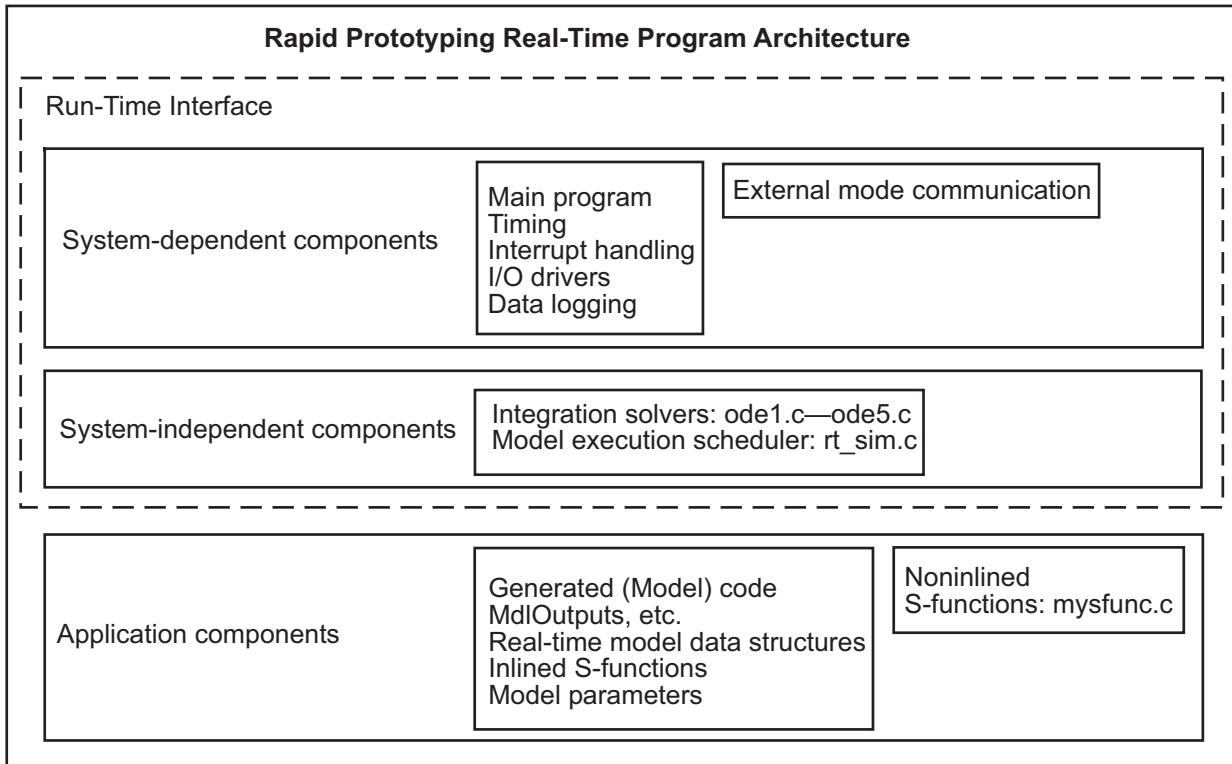
The Real-Time Workshop program framework provides the additional source code necessary to build the model code into a complete, standalone program. The program framework consists of *application modules* (files containing source code to implement required functions) designed for a number of different programming environments.

The automatic program builder ensures that the program is created with the proper modules once you have configured your template makefile. The application modules and the code generated for a Simulink model are implemented using a common API. This API defines a data structure (called a *real-time model*, sometimes abbreviated as *rtM*) that encapsulates all data for your model.

This API is similar to that of S-functions, with one major exception: the API assumes that there is only one instance of the model, whereas S-functions can have multiple instances. The function prototypes also differ from S-functions.

Rapid Prototyping Program Architecture

The structure of a real-time program consists of three components. Each component has a dependency on a different part of the environment in which the program executes. The next figure shows this structure.



The Real-Time Workshop architecture consists of three parts, the first two of which include system-dependent components and system-independent components. Together these two parts form the *run-time interface*.

This architecture adapts readily to a wide variety of environments by isolating the dependencies of each program component. The following sections discuss each component in more detail and include descriptions of the application modules that implement the functions carried out by the system-dependent components, system-independent components, and application components.

Rapid Prototyping System-Dependent Components

These components contain the program's main function, which controls program timing, creates tasks, installs interrupt handlers, enables data logging, and performs error checking.

The way in which application modules implement these operations depends on the type of computer. This means that, for example, the components used for a PC-based program perform the same operations, but differ in method of implementation from components designed to run on a VME target.

The main Function

The main function in a C/C++ program is the point where execution begins. In Real-Time Workshop application programs, the main function must perform certain operations. These operations can be grouped into three categories: initialization, model execution, and program termination.

Initialization

- Initialize special numeric parameters `rtInf`, `rtMinusInf`, and `rtNaN`. These are variables that the model code can use.
- Call the model registration function to get a pointer to the real-time model. The model registration function has the same name as your model. It is responsible for initializing real-time model fields and any S-functions in your model.
- Initialize the model size information in the real-time model. This is done by calling `MdlInitializeSizes`.
- Initialize a vector of sample times and offsets (for systems with multiple sample rates). This is done by calling `MdlInitializeSampleTimes`.
- Get the model ready for execution by calling `MdlStart`, which initializes states and similar items.
- Set up the timer to control execution of the model.
- Define background tasks and enable data logging, if selected.

Model Execution

- Execute a background task: for example, communicate with the host during external mode simulation or introduce a wait state until the next sample interval.
- Execute model (initiated by interrupt).

- Log data to buffer (if data logging is used).
- Return from interrupt.

Program Termination

- Call a function to terminate the program if it is designed to run for a finite time — destroy the real-time model data structure, deallocate memory, and write data to a file.

Rapid Prototyping Application Modules for System-Dependent Components

The application modules contained in the system-dependent components generally include a main module such as `rt_main.c`, containing the main entry point for C. There can also be additional application modules for such things as I/O support and timer handling.

Rapid Prototyping System-Independent Components

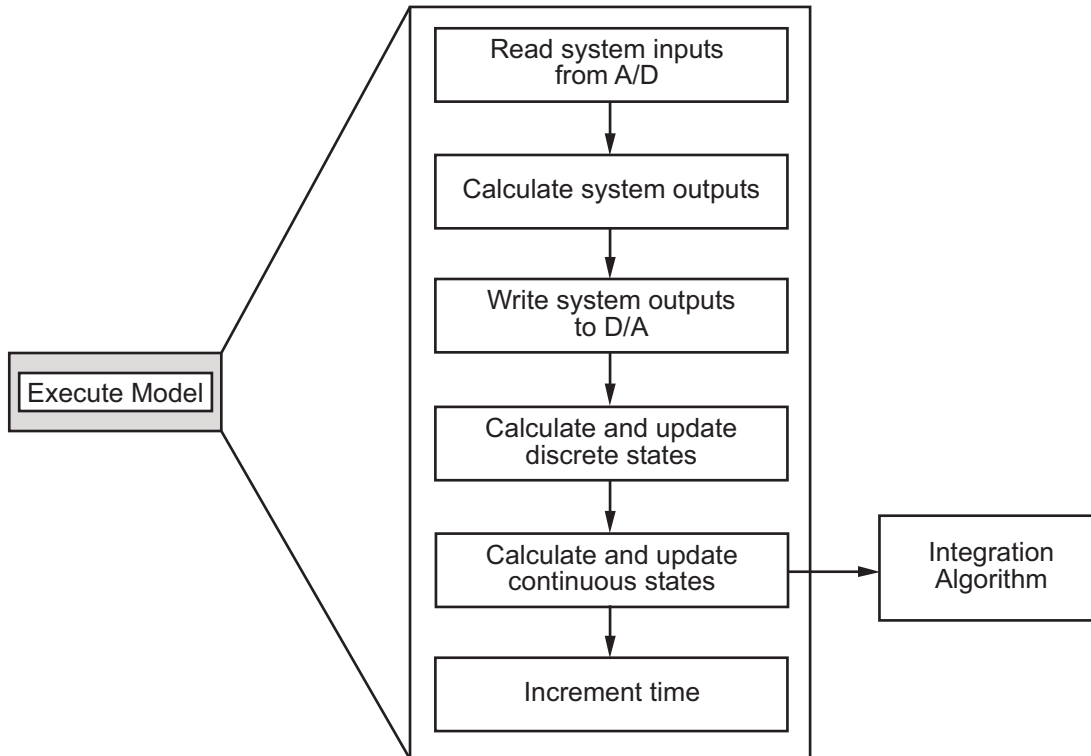
These components are collectively called system independent because all environments use the same application modules to implement these operations. This section steps through the model code (and if the model has continuous states, calls one of the numerical integration routines). This section also includes the code that defines, creates, and destroys the real-time model data structure (`rtM`). The model code and all S-functions included in the program define their own `SimStructs`.

The model code execution driver calls the functions in the model code to compute the model outputs, update the discrete states, integrate the continuous states (if applicable), and update time. These functions then write their calculated data to the real-time model.

Model Execution

At each sample interval, the main program passes control to the model execution function, which executes one step through the model. This step reads inputs from the external hardware, calculates the model outputs, writes outputs to the external hardware, and then updates the states.

The next figure shows these steps.



Executing the Model

This scheme writes the system outputs to the hardware before the states are updated. Separating the state update from the output calculation minimizes the time between the input and output operations.

Integration of Continuous States

The real-time program calculates the next values for the continuous states based on the derivative vector, dx/dt , for the current values of the inputs and the state vector.

These derivatives are then used to calculate the next values of the states using a state-update equation. This is the state-update equation for the first-order Euler method (ode1)

$$x = x + \frac{dx}{dt}h$$

where h is the step size of the simulation, x represents the state vector, and dx/dt is the vector of derivatives. Other algorithms can make several calls to the output and derivative routines to produce more accurate estimates.

Note, however, that real-time programs use a fixed-step size because it is necessary to guarantee the completion of all tasks within a given amount of time. This means that, while you should use higher order integration methods for models with widely varying dynamics, the higher order methods require additional computation time. In turn, the additional computation time might force you to use a larger step size, which can diminish the improvement of accuracy initially sought from the higher order integration method.

Generally, the stiffer the equations, (that is, the more dynamics in the system with widely varying time constants), the higher the order of the method that you must use.

In practice, the simulation of very stiff equations is impractical for real-time purposes except at very low sample rates. You should test fixed-step size integration in Simulink to check stability and accuracy before implementing the model for use in real-time programs.

For linear systems, it is more practical to convert the model that you are simulating to a discrete time version, for instance, using the `c2d` function in Control System Toolbox.

Application Modules for System-Independent Components

The system-independent components include these modules:

- `ode1.c`, `ode2.c`, `ode3.c`, `ode4.c`, `ode5.c`: These modules implement the integration algorithms supported for real-time applications. See “Choosing a Solver” in the Simulink documentation for more information about fixed-step solvers.

- `rt_sim.c`: Performs the activities necessary for one time step of the model. It calls the model function to calculate system outputs and then updates the discrete and continuous states.
- `simstruc_types.h`: Contains definitions of various events, including subsystem enable/disable and zero crossings. It also defines data-logging variables.

The system-independent components also include code that defines, creates, and destroys the real-time model data structure. All S-functions included in the program define their own `SimStructs`.

The `SimStruct` data structure encapsulates all the data relating to an S-function, including block parameters and outputs. See “The `SimStruct`” in the Simulink Writing S-Functions documentation for more information about `SimStruct`.

Rapid Prototyping Application Components

The application components contain the generated code for the Simulink model, including the code for any S-functions in the model. This code is referred to as the model code because these functions implement the Simulink model.

However, the generated code contains more than just functions to execute the model (as described in the previous section). There are also functions to perform initialization, facilitate data access, and complete tasks before program termination. To perform these operations, the generated code must define functions that

- Create the real-time model
- Initialize model size information in the real-time model
- Initialize a vector of sample times and sample time offsets and store this vector in the real-time model
- Store the values of the block initial conditions and program parameters in the real-time model
- Compute the block and system outputs
- Update the discrete state vector

- Compute derivatives for continuous models
- Perform an orderly termination at the end of the program (when the current time equals the final time, if a final time is specified)
- Collect block and scope data for data logging (either with Real-Time Workshop or third-party tools)

The Real-Time Model Data Structure

The real-time model data structure encapsulates model data and associated information necessary to fully describe the model. Its contents include

- Model parameters, inputs, and outputs
- Storage areas, such as dWork
- Timing information
- Solver identification
- Data logging information
- Simstructs for all child S-functions
- External mode information

The required information is stored in fields in the real-time model structure, which is defined in *model.h* as

```

/* Real-time Model Data Structure */
struct _rtModel_model_Tag {
    const char *path;
    const char *modelName;
    struct SimStruct_tag * *childSfunctions;
    const char *errorStatus;
    SS_SimMode simMode;
    RTWLogInfo *rtwLogInfo;
    RTWExtModeInfo *extModeInfo;
    RTWSolverInfo solverInfo;
    RTWSolverInfo *solverInfoPtr;
    void *sfcnInfo;

    /*

```

```

    * ModelData:
    * The following substructure contains information regarding
    * the data used in the model.
    */
    .
    .
}

```

The (possibly mangled) name of the model replaces *model* in the above tag. The individual substructures have been omitted, as they can vary.

For GRT targets, *model.h* also includes aliases to map global identifiers to identifiers used in prior versions (rtB, rtP, rtY, and so on). The following table lists the structure identifiers used in the generated code for these variants of the real-time model data structure. The column **GRT Symbol** contains the old-style (pre-Version 6) GRT identifiers, which are still used by the GRT calling interface, but not within the generated code.

Identifiers for Real-Time Model Data Structure Variants

Identifier	GRT Symbol	Data
<i>model_B</i>	rtB	Block IO
<i>model_U</i>	rtU	External inputs
<i>model_X</i>	rtX	Continuous states
<i>model_Xdot</i>	rtXdot	State derivatives
<i>model_Xdix</i>	rtXdis	Continuous state disabled
<i>model_Y</i>	rtY	External outputs
<i>model_P</i>	rtP	Parameters
rts	rts	Child Simstruct
<i>model_DWork</i>	rtDWork	DWork
<i>model_ConstB</i>	rtC	Constant block IO define, structure

Identifiers for Real-Time Model Data Structure Variants (Continued)

Identifier	GRT Symbol	Data
<i>model_ConstP</i>	rtcP	Constant parameter Structure
<i>model_PrevZCSigState</i>	rtPrevZCSigState	Previous zero-crossing signal states
<i>model_NonsampledZC</i>	rtNonsampledZC	Nonsampled zero-crossings

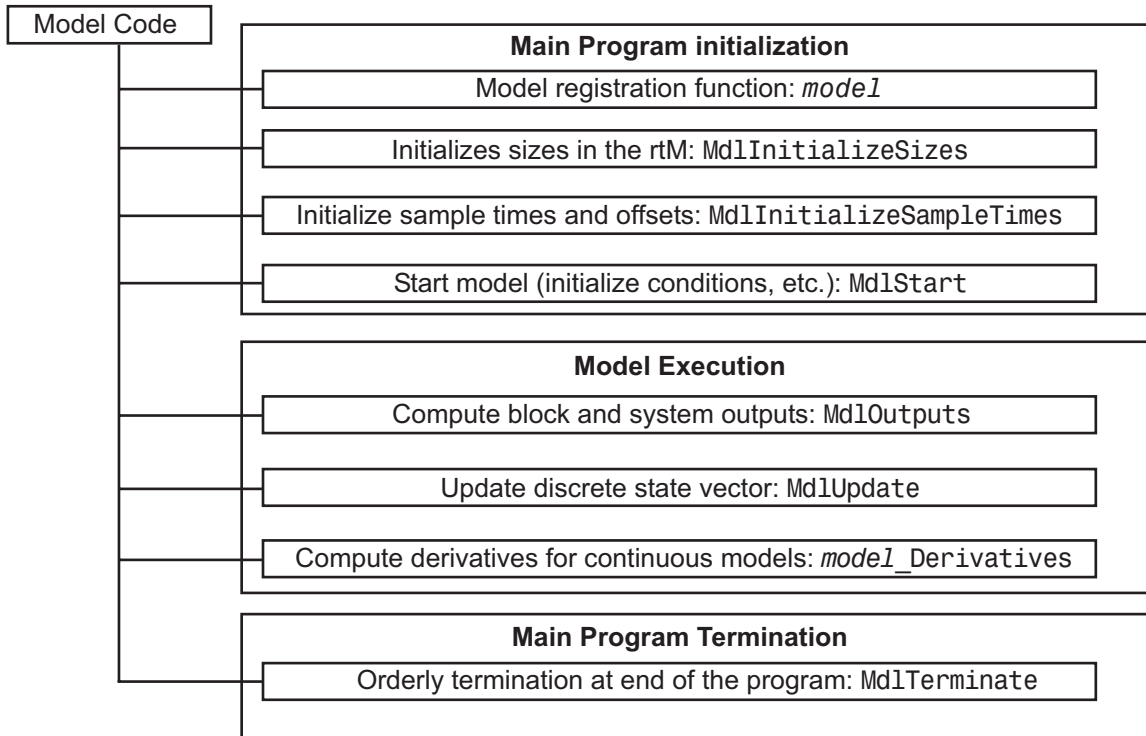
Users of Real-Time Workshop Embedded Coder can tailor identifiers, and can make them look like the GRT symbols listed above, should they desire such a coding style. The above GRT-ERT identifier equivalences (or at least as many of them as are required to build a given model) are established by using a set of `#define` macros in *model.h*, under the comment `/* Backward compatible GRT Identifiers */`.

The real-time model data structure is used for all targets. Prior to Version 5, the ERT target used the `rtObject` data structure, and other targets used the `Simstruct` data structure for encapsulating model data. Now all targets are treated the same, except for the fact that the real-time model data structure is *pruned* for ERT targets to save space in executables. Even when not pruned, the real-time model data structure is more space efficient than the root `Simstruct` used by earlier releases for non-ERT targets, as it only contains fields for child (S-function) `Simstructs` that are actually used in a model.

Rapid Prototyping Model Code Functions

The functions defined by the model code are called at various stages of program execution (that is, initialization, model execution, or program termination).

The next figure shows the functions defined in the generated code and shows what part of the program executes each function.



The Model Registration Function

The model registration function has the same name as the Simulink model from which it is generated. It is called directly by the main program during initialization. Its purpose is to initialize and return a pointer to the real-time model data structure.

Models Containing S-Functions

A *noninlined S-function* is any C or C++ MEX S-function that is not implemented using a customized TLC file. If you create a C or C++ MEX S-function as part of a Simulink model, it is by default noninlined unless you write your own TLC file that inlines it within the body of the *model.c* or *model.cpp* code. Real-Time Workshop automatically incorporates your noninlined C or C++ S-functions into the program if they adhere to the S-function API described in the Simulink documentation.

This format defines functions and a `SimStruct` that are local to the S-function. This allows you to have multiple instances of the S-function in the model. The model's real-time model data structure contains a pointer to each S-function's `SimStruct`.

Code Generation and S-Functions

If a model contains S-functions, the source code for the S-function must be on the search path the make utility uses to find other source files. The directories that are searched are specified in the template makefile that is used to build the program.

S-functions are implemented in a way that is directly analogous to the model code. They contain their own public registration functions (called by the top-level model code) that initialize static function pointers in their `SimStructs`. When the top-level model needs to execute the S-function, it does so by using the function pointers in the S-function's `SimStruct`. There can be more than one S-function with the same name in your model. This is accomplished by having function pointers to static functions.

Inlining S-Functions

You can incorporate C/C++ MEX S-functions, along with the generated code, into the program executable. You can also write a target file for your C/C++ MEX S-function to inline the S-function, thus improving performance by eliminating function calls to the S-function itself. For more information on inlining S-functions, see the Target Language Compiler documentation.

Application Modules for Application Components

When Real-Time Workshop generates code, it produces the following files:

- *model.c* or *model.cpp*: C or C++ code generated from the Simulink block diagram. This code implements the block diagram's system equations as well as performing initialization and updating outputs.
- *model_data.c* or *model_data.cpp*: Optional file containing data for parameters and constant block I/O, which are also declared as extern in *model.h*. Only generated when *model_P* and *model_ConstB* structures are populated.

- `model_types.h`: Forward declarations for the real-time model data structure and the parameters data structure.
- `model.h`: Header file containing the block diagram's simulation parameters, I/O structures, work structures, and other declarations.
- `model_private.h`: Header file containing declarations of exported signals and parameters.

These files are named for the Simulink model from which they are generated.

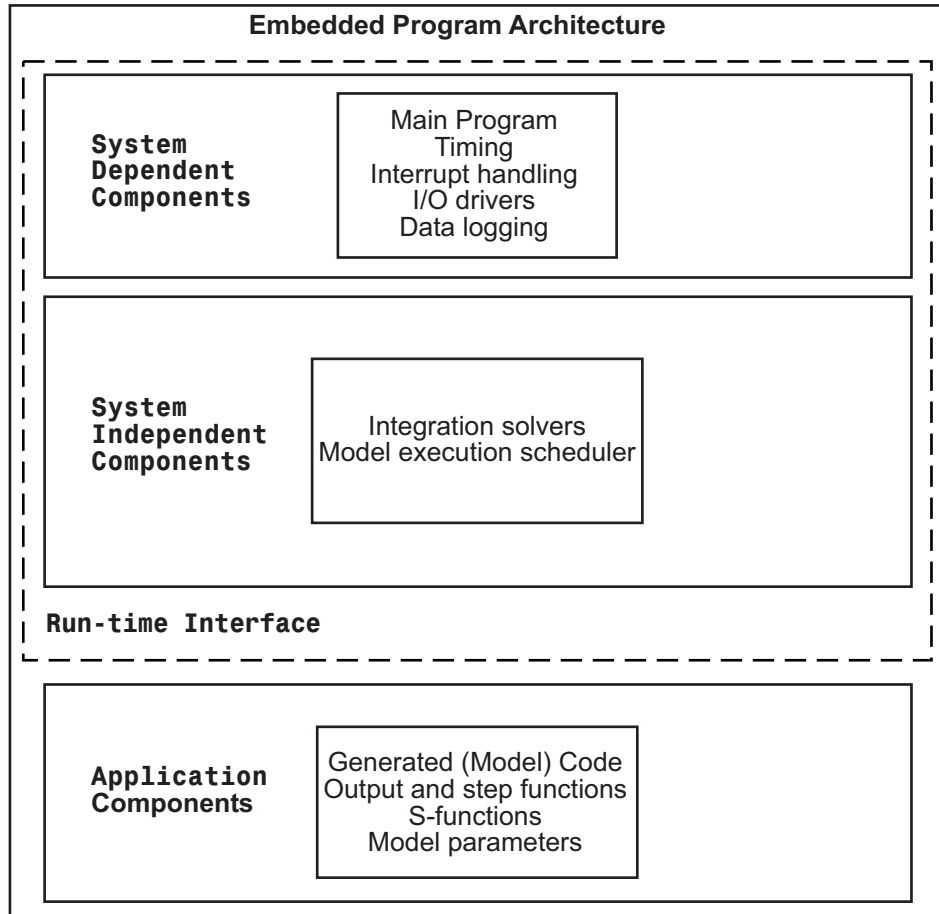
In addition, a dummy include file always named `rtmodel.h` is generated, which includes the above model-specific data structures and entry points. This enables the (static) target-specific main programs to reference files generated by Real-Time Workshop without needing to know the names of the models involved.

Another dummy file, `rtwtypes.h`, is generated, which simply includes `simstruc_types.h` (only for GRT and GRT-malloc targets).

If you have created custom blocks using C/C++ MEX S-functions, you need the source code for these S-functions available during the build process.

Embedded Program Framework

Real-Time Workshop Embedded Coder provides a framework for embedded programs. Its architecture is outlined in the next figure.



Note the similarity between this architecture and the rapid prototyping architecture in the figure “Rapid Prototyping Program Architecture” on page 7-24. The main difference is the use of the `rtModel` data structure in place of the `SimStruct` data structure.

Using the above figure, you can compare the embedded style of generated code, used in Real-Time Workshop Embedded Coder, with the rapid prototyping style of generated code of the previous section. Most of the rapid prototyping explanations in the previous section hold for the Real-Time Workshop Embedded Coder target. The Real-Time Workshop Embedded Coder target simplifies the process of using the generated code in your custom-embedded applications by providing a model-specific API and eliminating the `SimStruct`. This target contains the same conceptual layering as the rapid prototyping target, but each layer has been simplified.

For a discussion of the structure of embedded real-time code, see the Real-Time Workshop Embedded Coder documentation.

Models with Multiple Sample Rates

The following sections explain and illustrate how Simulink and Real-Time Workshop handle multirate (mixed-rate) models, depending on whether code is being generated for single-tasking or multitasking environments.

Introduction (p. 8-2)

Describes types of sample times and issues to consider regarding execution of multirate models

Single-Tasking and Multitasking Execution Modes (p. 8-4)

Discusses how Real-Time Workshop handles execution of multirate systems, in both multitasking and pseudomultitasking environments

Sample Rate Transitions (p. 8-14)

Shows how to handle transitions between blocks with unequal sample rates using Rate Transition blocks

Single-Tasking and Multitasking Execution of a Model: an Example (p. 8-28)

Discusses how an example model executes in both single-tasking and multitasking solver models, with timing diagrams.

Introduction

Simulink models operate at one or more data rates, called sample times. Sample times can be *block-based* (in which case all of a block's inputs and outputs run at the same rate), or be *port-based* (in which input and output ports operate at different rates). Some blocks have *continuous* sample times, some blocks have *discrete* sample times, and some can have either (*implicit* sample time). See “Block Sample Times” in the Simulink documentation for more information.

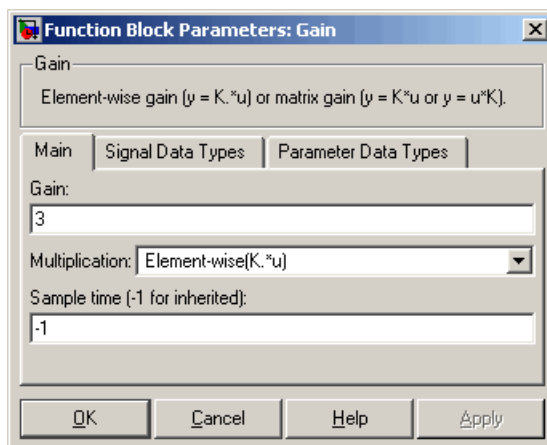
Blocks are classified according to how they handle sample time in the context of a model, as *constant*, *continuous-time*, *discrete-time*, *inherited*, or *variable*: The types of sample times are described in the following table:

Types of Sample Times Used by Simulink Blocks

Time Type	Description	Examples (defaults)
Constant	Block outputs are computed once only, before simulation begins	Constant, Width
Continuous	Block outputs are computed at each step the solver takes	Integrator, Derivative, Transfer Function
Discrete	Block outputs are computed at fixed (sample) time intervals	Unit Delay, Digital Filter
Inherited	Block outputs are computed at rates that depend on the context of the block in the model	Gain, Sum, Lookup Table
Variable	Blocks that set the time of the next sample hit themselves, based on current information	Pulse Generator, some S-Functions

Variable-time blocks work only with variable-step solvers. Many Simulink blocks can set their own sample time.

The following Gain block parameters dialog box shows how you can specify sample times for blocks that inherit the sample time by default:



Every Simulink block has a sample time. Blocks in the inherited category assume the sample time of blocks that drive them. Continuous blocks have a nominal sample time of zero. You can design blocks to operate at different sample times at different input and output ports. Such blocks have *port-based sample times*. Alternatively, blocks — whether constant, continuous-time, discrete-time, inherited, or variable — can have *block-based sample times*. For more information on how S-Function blocks handle multiple sample times, see “Sample Times” in the Simulink Writing S-Functions documentation.

You can create models without restrictions on connections between blocks with different sample times. Therefore, it is possible to have blocks with differing sample times in a model. A possible advantage of employing multiple sample times is improved efficiency when executing in a multitasking real-time environment.

Simulink provides considerable flexibility in building multirate systems. However, the same flexibility also allows you to construct models for which the code generator cannot generate correct real-time code for execution in a multitasking environment. To make multirate models operate correctly in real time (that is, to give the right answers), you sometimes must modify your model or instruct Simulink to modify the model for you. In general, the modifications involve placing Rate Transition blocks between blocks that have unequal sample rates. The following sections discuss issues you must address to use a multirate model successfully in a multitasking environment.

Single-Tasking and Multitasking Execution Modes

In this section...

“Introduction” on page 8-4

“Executing Multitasking Models” on page 8-6

“Multitasking and Pseudomultitasking Modes” on page 8-7

“Building a Program for Multitasking Execution” on page 8-10

“Single-Tasking Mode” on page 8-10

“Building a Program for Single-Tasking Execution” on page 8-11

“Model Execution and Rate Transitions” on page 8-11

“Simulating Models with Simulink” on page 8-12

“Executing Models in Real Time” on page 8-12

“Single-Tasking Versus Multitasking Operation” on page 8-13

Introduction

There are two execution modes for a fixed-step Simulink model: single-tasking and multitasking. These modes are available only for fixed-step solvers. To select an execution mode, use the **Tasking mode for periodic sample times** menu on the **Solver** pane of the Configuration Parameters dialog box. Auto mode (the default) applies multitasking execution for a multirate model, and otherwise selects single-tasking execution. You can also select Single-tasking or MultiTasking execution explicitly.

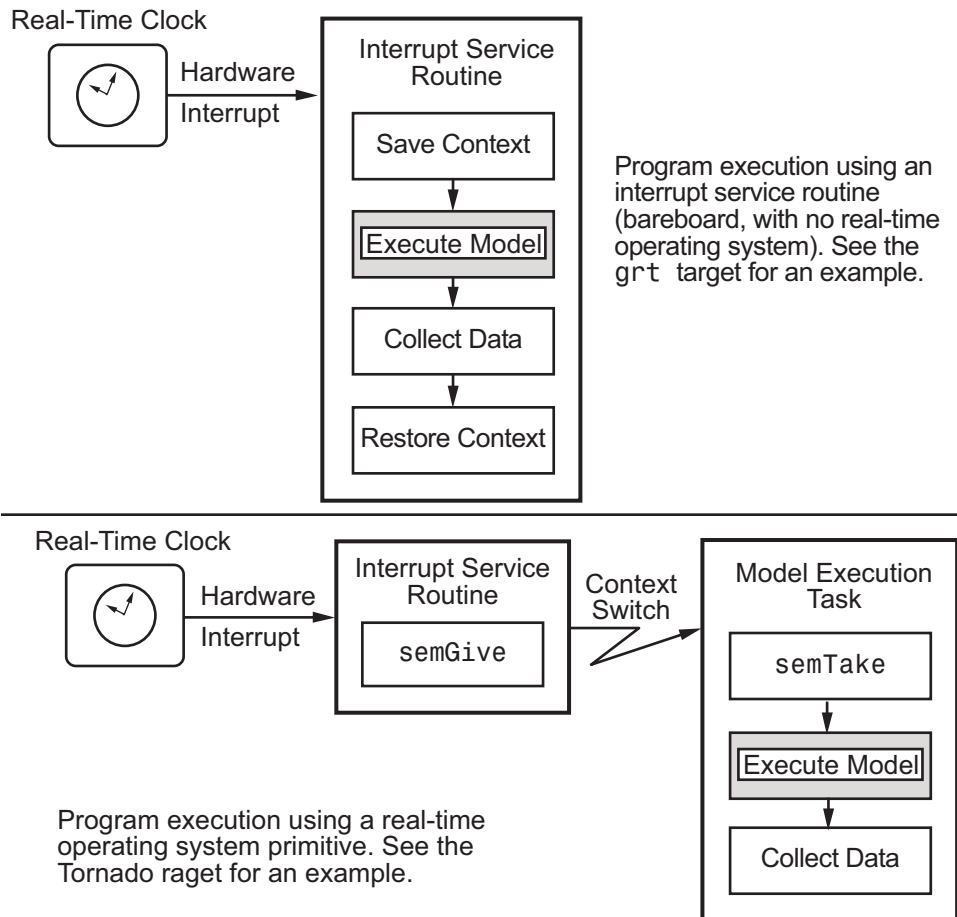
Execution of models in a real-time system can be done with the aid of a real-time operating system, or it can be done on a *bare-board* target, where the model runs in the context of an interrupt service routine (ISR).

The fact that a system (such as UNIX or Microsoft Windows) is multitasking does not guarantee that your program can execute in real time. This is because it is not guaranteed that the program can preempt other processes when required.

In operating systems (such as PC-DOS) where only one process can exist at any given time, an interrupt service routine (ISR) must perform the steps of

saving the processor context, executing the model code, collecting data, and restoring the processor context.

Other operating systems, such as POSIX-compliant ones, provide automatic context switching and task scheduling. This simplifies the operations performed by the ISR. In this case, the ISR simply enables the model execution task, which is normally blocked. The next figure illustrates this difference.



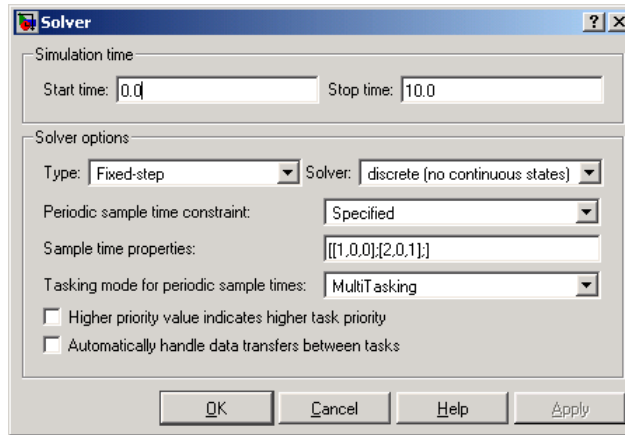
This chapter focuses on when and how the run-time interface executes the generated code for your model. See “Program Execution” on page 7-14 for a description of what happens during model execution.

Executing Multitasking Models

In cases where the continuous part of a model executes at a rate that is different from the discrete part, or a model has blocks with different sample rates, Simulink assigns each block a *task identifier* (tid) to associate the block with the task that executes at the block’s sample rate.

You set sample rates and their constraints on the **Solver** pane of the Configuration Parameters dialog box. To generate code with Real-Time Workshop, you must select Fixed-step for the solver type. Certain restrictions apply to the sample rates that you can use:

- The sample rate of any block must be an integer multiple of the base (that is, the fastest) sample period.
- When **Periodic sample time constraint** is unconstrained, the base sample period is determined by the **Fixed step size** specified on the **Solvers** pane of the Configuration parameters dialog box.
- When **Periodic sample time constraint** is Specified, the base rate fixed-step size is the first element of the sample time matrix that you specify in the companion option **Sample time properties**. The **Solver** pane from the demo model `rtwdemo_mrmtbb` shows an example.



- Continuous blocks always execute by using an integration algorithm that runs at the base sample rate. The base sample period is the greatest common denominator of all rates in the model only when **Periodic sample time constraint** is set to Unconstrained and **Fixed step size** is Auto.
- The continuous and discrete parts of the model can execute at different rates only if the discrete part is executed at the same or a slower rate than the continuous part and is an integer multiple of the base sample rate.

Multitasking and Pseudomultitasking Modes

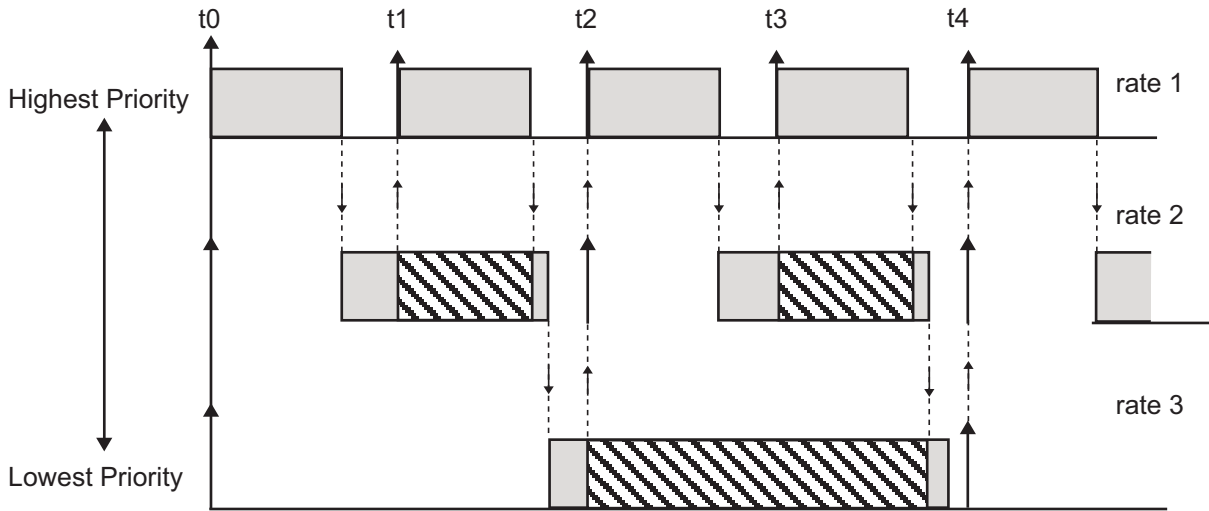
When periodic tasks execute in a multitasking mode, by default the blocks with the fastest sample rates are executed by the task with the highest priority, the next fastest blocks are executed by a task with the next higher priority, and so on. Time available in between the processing of high-priority tasks is used for processing lower priority tasks. This results in efficient program execution.

Where tasks are asynchronous rather than periodic, there may not necessarily be a relationship between sample rates and task priorities; the task with the highest priority need not have the fastest sample rate. You specify asynchronous task priorities using Async Interrupt and Task Synchronization blocks. You can switch the sense of what priority numbers mean by selecting or deselecting the Solver option **Higher priority value indicates higher task priority**.

In multitasking environments (that is, under a real-time operating system), you can define separate tasks and assign them priorities. In a bare-board target (that is, no real-time operating system present), you cannot create separate tasks. However, Real-Time Workshop application modules implement what is effectively a multitasking execution scheme using overlapped interrupts, accompanied by programmatic context switching.

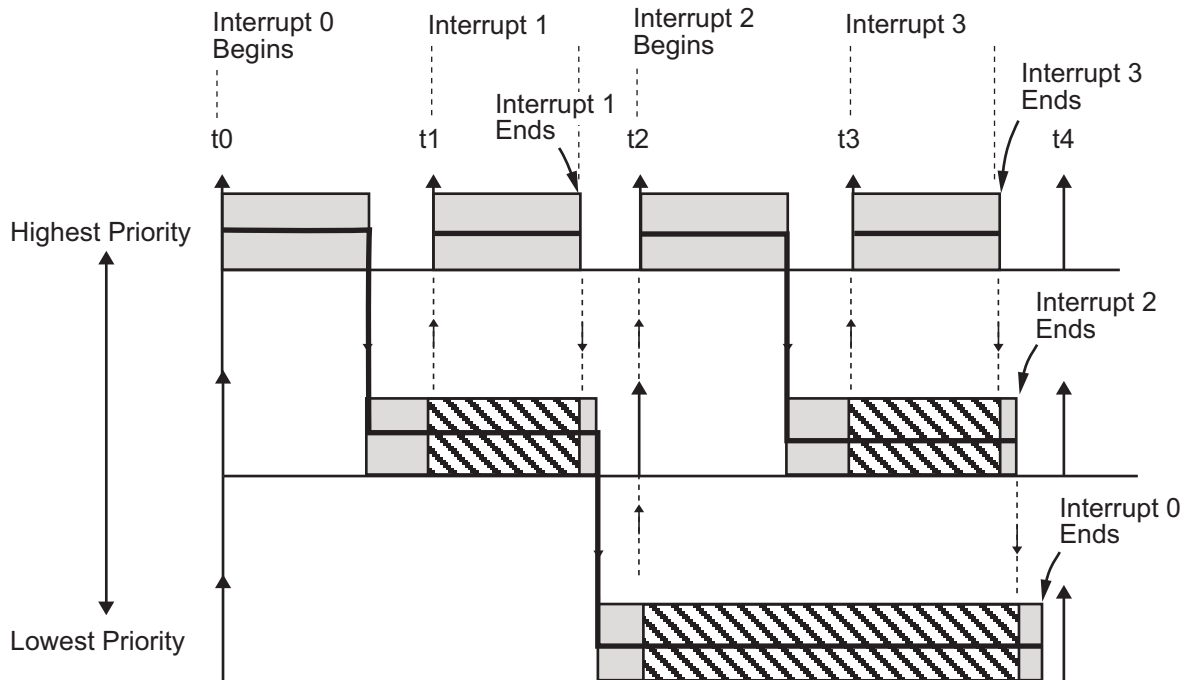
This means an interrupt can occur while another interrupt is currently in progress. When this happens, the current interrupt is preempted, the floating-point unit (FPU) context is saved, and the higher priority interrupt executes its higher priority (that is, faster sample rate) code. Once complete, control is returned to the preempted ISR.

The next figures illustrate how timing of tasks in multirate systems are handled by Real-Time Workshop in multitasking, pseudomultitasking, and single-tasking environments.



- ↑ Vertical arrows indicate sample time hits.
- ↓ Dotted lines with downward pointing arrows indicate the release of control to a lower priority task.
- ↑ Dotted lines with upward pointing arrows indicate preemption by a higher priority task.
- Dark gray areas indicate task execution.
- Hashed areas indicate task preemption by a higher priority task.
- Light gray areas indicate task execution is pending.

The next figure shows how overlapped interrupts are used to implement pseudomultitasking. In this case, Interrupt 0 does not return until after Interrupts 1, 2, and 3.



Building a Program for Multitasking Execution

To use multitasking execution, select Auto (the default) or MultiTasking from the **Tasking mode for periodic sample times** menu on the **Solver** pane of the Configuration Parameters dialog box. This menu is active only if you select Fixed-step as the solver type. Auto mode results in a multitasking environment if your model has two or more different sample times. A model with a continuous and a discrete sample time runs in single-tasking mode if the fixed-step size is equal to the discrete sample time.

Single-Tasking Mode

You can execute model code in a strictly single-tasking manner. While this mode is less efficient with regard to execution speed, in certain situations, it can simplify your model.

In single-tasking mode, the base sample rate must define a time interval that is long enough to allow the execution of all blocks within that interval.

The next figure illustrates the inefficiency inherent in single-tasking execution.



Single-tasking system execution requires a base sample rate that is long enough to execute one step through the entire model.

Building a Program for Single-Tasking Execution

To use single-tasking execution, select **Single-tasking** from the **Tasking mode for periodic sample times** menu on the **Solver** pane of the Configuration Parameters dialog box. If you select **Auto**, single-tasking is used in the following cases:

- If your model contains one sample time
- If your model contains a continuous and a discrete sample time and the fixed step size is equal to the discrete sample time

Model Execution and Rate Transitions

To generate code that executes correctly in real time, you (or Simulink) might need to identify and properly handle sample rate transitions within the model. In multitasking mode, by default Simulink flags errors during simulation if the model contains invalid rate transitions, although you can use the **Multitask rate transition** diagnostic to alter this behavior. A similar diagnostic, called **Single task rate transition**, exists for single-tasking mode.

To avoid raising rate transition errors, insert Rate Transition blocks between tasks. You can request Simulink to handle rate transitions automatically by inserting hidden Rate Transition blocks. See “Automatic Rate Transition” on page 8-19 for an explanation of this option.

To understand such problems, first consider how Simulink simulations differ from real-time programs.

Simulating Models with Simulink

Before Simulink simulates a model, it orders all the blocks based upon their topological dependencies. This includes expanding virtual subsystems into the individual blocks they contain and flattening the entire model into a single list. Once this step is complete, each block is executed in order.

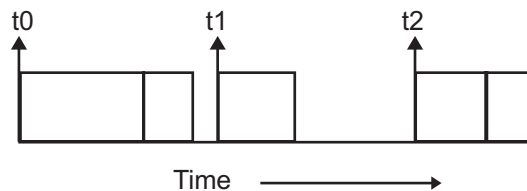
The key to this process is the proper ordering of blocks. Any block whose output is directly dependent on its input (that is, any block with direct feedthrough) cannot execute until the block driving its input executes.

Some blocks set their outputs based on values acquired in a previous time step or from initial conditions specified as a block parameter. The output of such a block is determined by a value stored in memory, which can be updated independently of its input. During simulation, all necessary computations are performed prior to advancing the variable corresponding to time. In essence, this results in all computations occurring instantaneously (that is, no computational delay).

Executing Models in Real Time

A real-time program differs from a Simulink simulation in that the program must execute the model code synchronously with real time. Every calculation results in some computational delay. This means the sample intervals cannot be shortened or lengthened (as they can be in Simulink), which leads to less efficient execution.

Consider the following timing figure.



Note the processing inefficiency in the sample interval t_1 . That interval cannot be compressed to increase execution speed because, by definition, sample times are clocked in real time.

You can circumvent this potential inefficiency by using the multitasking mode. The multitasking mode defines tasks with different priorities to execute parts of the model code that have different sample rates.

See “Multitasking and Pseudomultitasking Modes” on page 8-7 for a description of how this works. It is important to understand that section before proceeding here.

Single-Tasking Versus Multitasking Operation

Single-tasking programs require longer sample intervals, because all computations must be executed within each clock period. This can result in inefficient use of available CPU time, as shown in the previous figure.

Multitasking mode can improve the efficiency of your program if the model is large and has many blocks executing at each rate.

However, if your model is dominated by a single rate, and only a few blocks execute at a slower rate, multitasking can actually degrade performance. In such a model, the overhead incurred in task switching can be greater than the time required to execute the slower blocks. In this case, it is more efficient to execute all blocks at the dominant rate.

If you have a model that can benefit from multitasking execution, you might need to modify your Simulink model by adding Rate Transition blocks (or instruct Simulink to do so) to generate correct results. The next section, “Sample Rate Transitions” on page 8-14, discusses issues related to rate transition blocks.

Sample Rate Transitions

In this section...

- “Introduction” on page 8-14
- “Data Transfer Problems” on page 8-16
- “Data Transfer Assumptions” on page 8-17
- “Rate Transition Block Options” on page 8-17
- “Faster to Slower Transitions in Simulink” on page 8-21
- “Faster to Slower Transitions in Real Time” on page 8-22
- “Slower to Faster Transitions in Simulink” on page 8-24
- “Slower to Faster Transitions in Real Time” on page 8-25

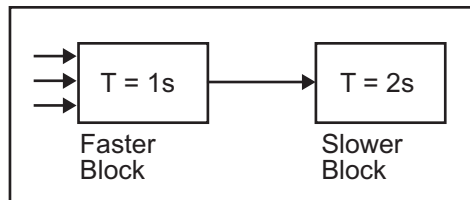
Introduction

Two periodic sample rate transitions can exist within a model:

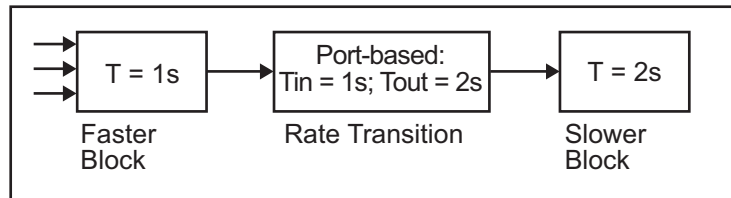
- A faster block driving a slower block
- A slower block driving a faster block

The following sections concern models with periodic sample times with zero offset only. Other considerations apply to multirate models that involve asynchronous tasks. For details on how to generate code for asynchronous multitasking, see Chapter 16, “Asynchronous Support”.

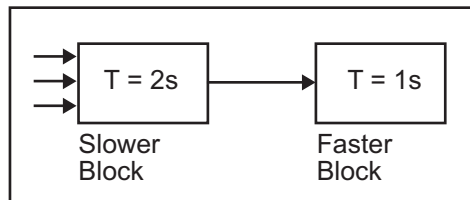
In single-tasking systems, there are no issues involving multiple sample rates. In multitasking and pseudomultitasking systems, however, differing sample rates can cause problems by causing blocks to be executed in the wrong order. To prevent possible errors in calculated data, you must control model execution at these transitions. When connecting faster and slower blocks, you or Simulink must add Rate Transition blocks between them. Fast-to-slow transitions are illustrated in the next figure.



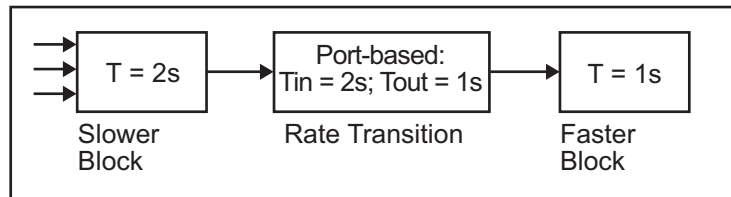
becomes



Slow-to-fast transitions are illustrated in the next figure.



becomes



Note Although the Rate Transition block offers a superset of the capabilities of the Unit Delay block (for slow-to-fast transitions) and the Zero-Order Hold block (for fast-to-slow transitions), you should use the Rate Transition block instead of these blocks.

Data Transfer Problems

Rate Transition blocks deal with issues of data integrity and determinism associated with data transfer between blocks running at different rates.

- *Data integrity*: A problem of data integrity exists when the input to a block changes during the execution of that block. Data integrity problems can be caused by preemption.

Consider the following scenario:

- A faster block supplies the input to a slower block.
- The slower block reads an input value V_1 from the faster block and begins computations using that value.
- The computations are preempted by another execution of the faster block, which computes a new output value V_2 .
- A data integrity problem now arises: when the slower block resumes execution, it continues its computations, now using the “new” input value V_2 .

Such a data transfer is called *unprotected*. “Faster to Slower Transitions in Real Time” on page 8-22 shows an unprotected data transfer.

In a *protected* data transfer, the output V_1 of the faster block is held until the slower block finishes executing.

- *Deterministic versus nondeterministic data transfer*: In a *deterministic* data transfer, the timing of the data transfer is completely predictable, as determined by the sample rates of the blocks.

The timing of a *nondeterministic* data transfer depends on the availability of data, the sample rates of the blocks, and the time at which the receiving block begins to execute relative to the driving block.

You can use the Rate Transition block to ensure that data transfers in your application are both protected and deterministic. These characteristics are considered desirable in most applications. However, the Rate Transition block supports flexible options that allow you to compromise data integrity and determinism in favor of lower latency. The next section summarizes these options.

Data Transfer Assumptions

When processing data transfers between tasks, Real-Time Workshop assumes the following:

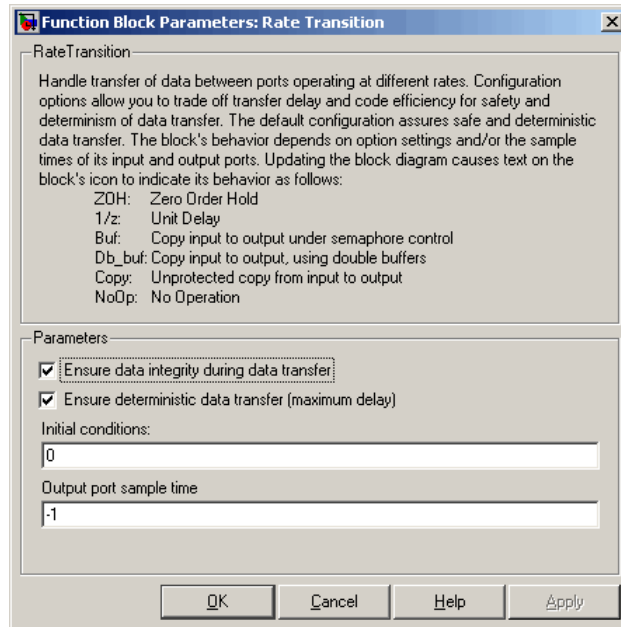
- Data transitions occur between a single reading task and a single writing task.
- A read or write of a byte-sized variable is atomic.
- When two tasks interact through a data transition, only one of them can preempt the other.
- For periodic tasks, the faster rate task has higher priority than the slower rate task; the faster rate task always preempts the slower rate task.
- All tasks run on a single processor. Time slicing is not allowed.
- Processes do not crash or restart (especially while data is transferred between tasks).

Rate Transition Block Options

Several parameters of the Rate Transition block are relevant to its use in code generation for real-time execution, as discussed below. For a complete block description, see Rate Transition in the Simulink documentation.

The Rate Transition block handles periodic (fast to slow and slow to fast) and asynchronous transitions. When inserted between two blocks of differing sample rates, the Rate Transition block automatically configures its input and output sample rates for the appropriate type of transition; you do not need to specify whether a transition is slow-to-fast or fast-to-slow (low-to-high or high-to-low priorities for asynchronous tasks).

The critical decision you must make in configuring a Rate Transition block is the choice of data transfer mechanism to be used between the two rates. Your choice is dictated by considerations of safety, memory usage, and performance. As the Rate Transition block parameter dialog box in the next figure shows, the data transfer mechanism is controlled by two options.



- **Ensure data integrity during data transfer:** When this option is on, the integrity of data transferred between rates is guaranteed (the data transfer is protected). When this option is off, data integrity is not guaranteed (the data transfer is unprotected). By default, **Ensure data integrity during data transfer** is on.
- **Ensure deterministic data transfer (maximum delay):** This option is supported for periodic tasks with an offset of zero and fast and slow rates that are multiples of each other. Enable this option for protected data transfers (when **Ensure data integrity during data transfer** is on). When this option is on, the Rate Transition block behaves like a Zero-Order Hold block (for fast to slow transitions) or a Unit Delay block (for slow to fast transitions). The Rate Transition block controls the timing of data transfer in a completely predictable way. When this option is off, the data transfer is nondeterministic. By default, **Ensure deterministic data transfer (maximum delay)** is on for transitions between periodic rates with an offset of zero; for asynchronous transitions, it cannot be selected.

Thus the Rate Transition block offers three modes of operation with respect to data transfer. In order of safety, from safest to least safe, these are

- **Protected/Deterministic (default):** This is the safest mode. The drawback of this mode is that it introduces deterministic latency into the system for the case of slow-to-fast periodic rate transitions. For that case, the latency introduced by the Rate Transition block is one sample period of the slower task. For the case of fast-to-slow periodic rate transitions, the Rate Transition block introduces no additional latency.
- **Protected/NonDeterministic:** In this mode, for slow-to-fast periodic rate transitions, data integrity is protected by double-buffering data transferred between rates. For fast-to-slow periodic rate transitions, a semaphore flag is used. The blocks downstream from the Rate Transition block always use the latest available data from the block that drives the Rate Transition block. Maximum latency is less than or equal to one sample period of the faster task.

The drawbacks of this mode are its nondeterministic timing. The advantage of this mode is its low latency.

- **Unprotected/NonDeterministic:** This mode is the least safe, and is not recommended for mission-critical applications. The latency of this mode is the same as for Protected/NonDeterministic mode, but memory requirements are reduced since neither double-buffering nor semaphores are needed. That is, the Rate Transition block does nothing in this mode other than to pass signals through; it simply exists to notify you that a rate transition exists (and can cause generated code to compute incorrect answers). Selecting this mode, however, generates the least amount of code.

Note In unprotected mode (**Ensure data integrity during data transfer** option off), the Rate Transition block does nothing other than allow the rate transition to exist in the model.

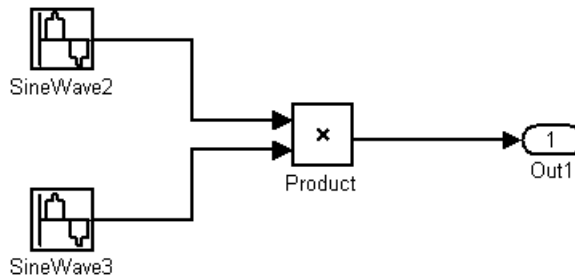
Automatic Rate Transition

Simulink can detect mismatched rate transitions in a multitasking model and automatically insert Rate Transition blocks to handle them. To instruct Simulink to do this, select **Automatically handle data transfers between tasks** on the **Solver** pane of the Configuration Parameters dialog box.

The **Automatically handle data transfers between tasks** option is off by default. When you select it,

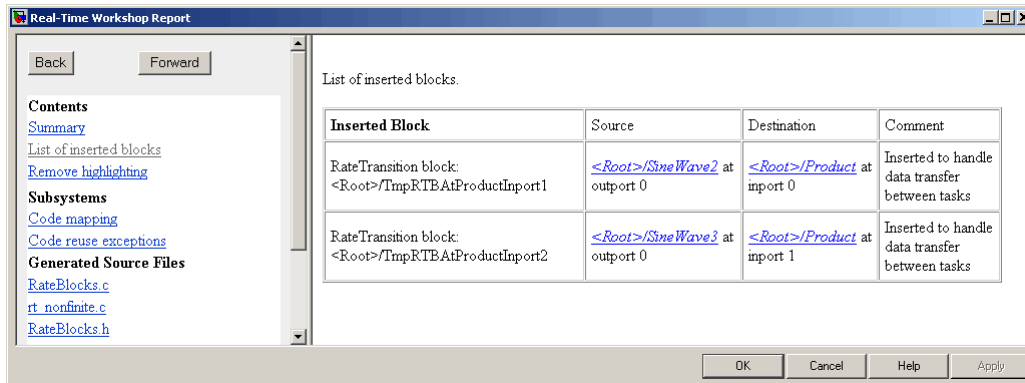
- Simulink handles all transitions between periodic sample times and asynchronous tasks.
- Simulink inserts “hidden” Rate Transition blocks that are not visible on the block diagram.
- Real-Time Workshop generates code for the automatically inserted Rate Transition blocks that is identical to that generated for manually inserted Rate Transition blocks.
- Automatically inserted Rate Transition blocks operate in protected/deterministic mode for periodic tasks and protected mode for asynchronous tasks (see “Automatic Rate Transition” on page 8-19), which you cannot alter. To use other modes, you must insert Rate Transition blocks and set their modes manually.

For example, in the following model SineWave2 has a Sample time of 2, and SineWave3 has a Sample time of 3.



If **Automatically handle data transfers between tasks** is on, Simulink inserts an invisible Rate Transition block between each Sine Wave block and the Product block. The inserted blocks have the parameter values necessary to reconcile the Sine Wave block sample times.

Inserted Rate Transition Block HTML Report. When Simulink has automatically inserted Rate Transition blocks into a model, after code generation the optional HTML code generation report includes a List of inserted blocks that describes the blocks. For example, the following report describes the two Rate Transition blocks that Simulink automatically inserts into the previous model.



Only automatically inserted Rate Transition blocks appear in a List of inserted blocks. If no such blocks exist in a model, the HTML code generation report does not include a List of inserted blocks.

Rate Transition Blocks and Continuous Time

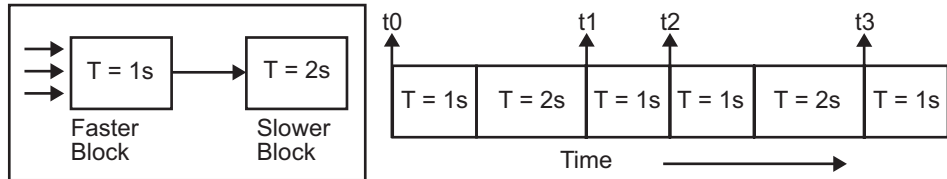
The sample time at the output port of a Rate Transition block can only be discrete or fixed in minor time step. This means that when a Rate Transition block inherits continuous sample time from its destination block, it treats the inherited sample time as Fixed in Minor Time Step. Therefore, the output function of the Rate Transition block runs only at major time steps. If the destination block sample time is continuous, Rate Transition block output sample time is the base rate sample time (if solver is fixed-step), or zero-order-hold-continuous sample time (if solver is variable-step).

The next four sections describe cases in which Rate Transition blocks are necessary for periodic sample rate transitions. The discussion and timing diagrams in these sections are based on the assumption that the Rate Transition block is used in its default (protected/deterministic) mode; that is, the **Ensure data integrity during data transfer** and **Ensure deterministic data transfer (maximum delay)** options are both on. These are the settings used for automatically inserted Rate Transition blocks.

Faster to Slower Transitions in Simulink

In a model where a faster block drives a slower block having direct feedthrough, the outputs of the faster block are always computed first. In

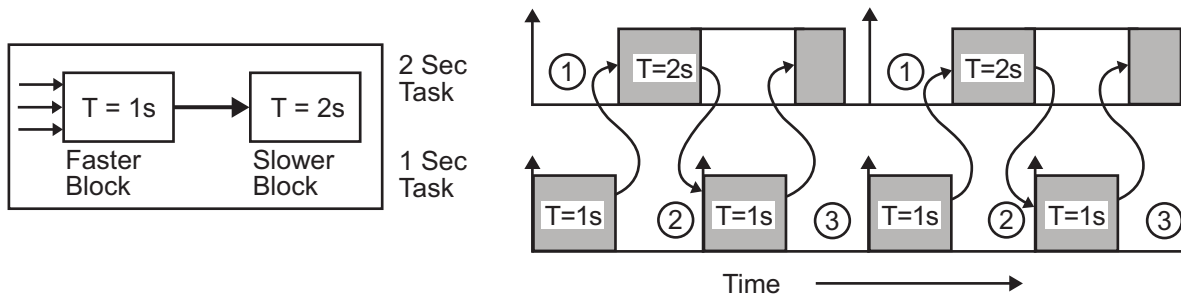
simulation intervals where the slower block does not execute, the simulation progresses more rapidly because there are fewer blocks to execute. The next figure illustrates this situation.



Simulink does not execute in real time, which means that it is not bound by real-time constraints. Simulink waits for, or moves ahead to, whatever tasks are necessary to complete simulation flow. The actual time interval between sample time steps can vary.

Faster to Slower Transitions in Real Time

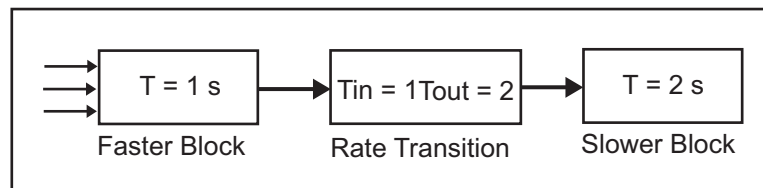
In models where a faster block drives a slower block, you must compensate for the fact that execution of the slower block might span more than one execution period of the faster block. This means that the outputs of the faster block can change before the slower block has finished computing its outputs. The next figure shows a situation in which this problem arises ($T = \text{sample time}$). Note that lower priority tasks are preempted by higher priority tasks before completion.



- ① The faster task ($T=1s$) completes.
- ② Higher priority preemption occurs.
- ③ The slower task ($T=2s$) resumes and its inputs have changed. This leads to unpredictable results.

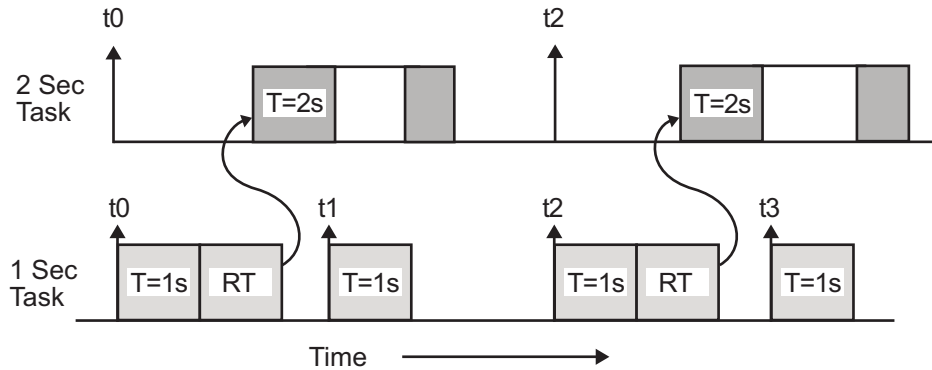
In the above figure, the faster block executes a second time before the slower block has completed execution. This can cause unpredictable results because the input data to the slow task is changing. Data integrity is not guaranteed in this situation.

To avoid this situation, Simulink must hold the outputs of the 1 second (faster) block until the 2 second (slower) block finishes executing. The way to accomplish this is by inserting a Rate Transition block between the 1 second and 2 second blocks. This guarantees that the input to the slower block does not change during its execution, ensuring data integrity.



It is assumed that the Rate Transition block is used in its default (protected/deterministic) mode.

The Rate Transition block executes at the sample rate of the slower block, but with the priority of the faster block.

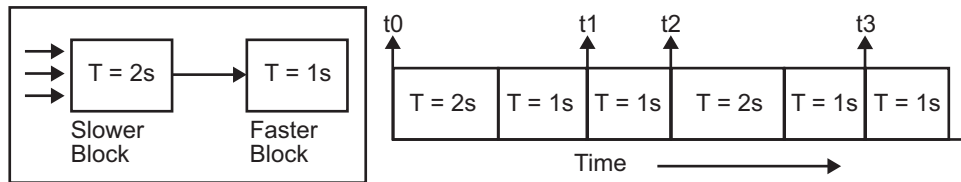


Adding a Rate Transition block ensures that the Rate Transition block executes before the 2 second block (its priority is higher) and that its output value is held constant while the 2 second block executes (it executes at the slower sample rate).

Slower to Faster Transitions in Simulink

In a model where a slower block drives a faster block, Simulink again computes the output of the driving block first. During sample intervals where only the faster block executes, the simulation progresses more rapidly.

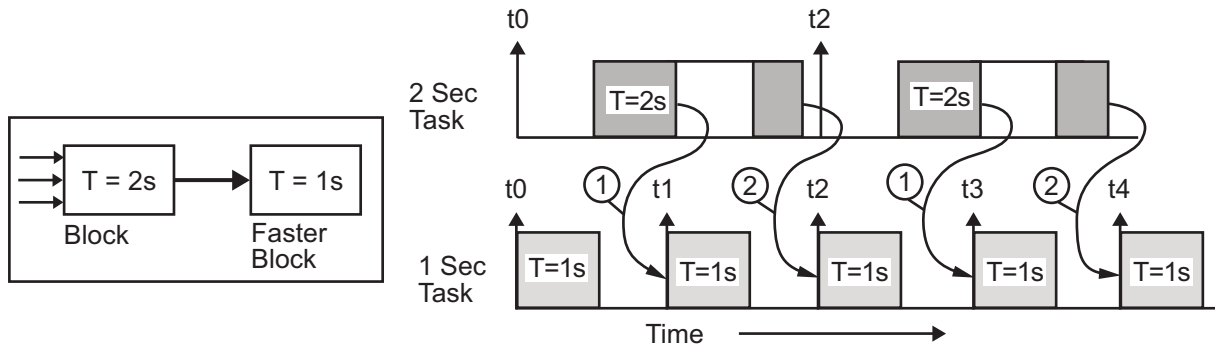
The next figure shows the execution sequence.



As you can see from the preceding figures, Simulink can simulate models with multiple sample rates in an efficient manner. However, Simulink does not operate in real time.

Slower to Faster Transitions in Real Time

In models where a slower block drives a faster block, the generated code assigns the faster block a higher priority than the slower block. This means the faster block is executed before the slower block, which requires special care to avoid incorrect results.

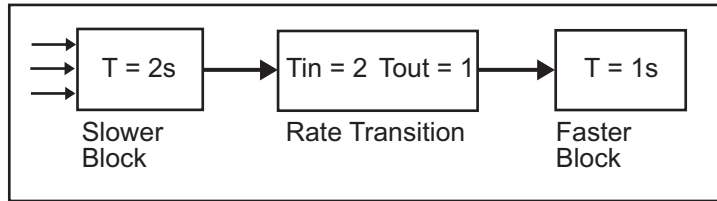


- ① The faster block executes a second time prior to the completion of the slower block.
- ② The faster block executes before the slower block.

This timing diagram illustrates two problems:

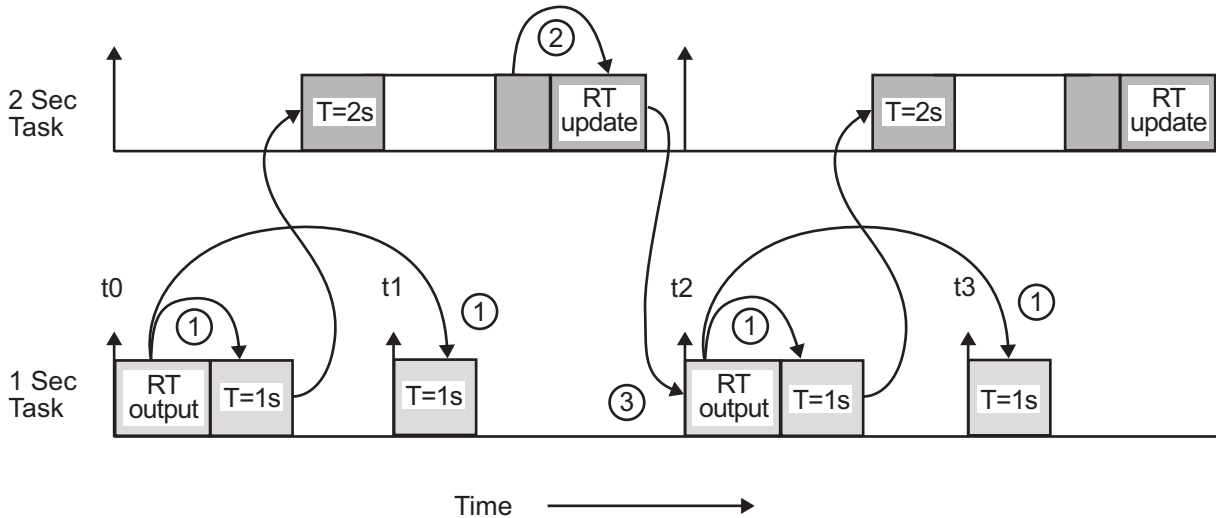
- Execution of the slower block is split over more than one faster block interval. In this case the faster task executes a second time before the slower task has completed execution. This means the inputs to the faster task can have incorrect values some of the time.
- The faster block executes before the slower block (which is backward from the way Simulink operates). In this case, the 1 second block executes first; but the inputs to the faster task have not been computed. This can cause unpredictable results.

To eliminate these problems, you must insert a Rate Transition block between the slower and faster blocks.



It is assumed that the Rate Transition block is used in its default (protected/deterministic) mode.

The next figure shows the timing sequence that results with the added Rate Transition block.



Three key points about transitions in this diagram (refer to circled numbers):

- 1 The Rate Transition block output runs in the 1 second task, but at a slower rate (2 seconds). The output of the Rate Transition block feeds the 1 second task blocks.
- 2 The Rate Transition update uses the output of the 2 second task to update its internal state.

- 3** The Rate Transition output in the 1 second task uses the state of the Rate Transition that was updated in the 2 second task.

The first problem is alleviated because the Rate Transition block is updating at a slower rate and at the priority of the slower block. The input to the Rate Transition block (which is the output of the slower block) is read after the slower block completes executing.

The second problem is alleviated because the Rate Transition block executes at a slower rate and its output does not change during the computation of the faster block it is driving. The output portion of a Rate Transition block is executed at the sample rate of the slower block, but with the priority of the faster block. Since the Rate Transition block drives the faster block and has effectively the same priority, it is executed before the faster block.

Note This use of the Rate Transition block changes the model. The output of the slower block is now delayed by one time step compared to the output without a Rate Transition block.

Single-Tasking and Multitasking Execution of a Model: an Example

In this section...

“Introduction” on page 8-28

“Single-Tasking Execution” on page 8-29

“Multitasking Execution” on page 8-31

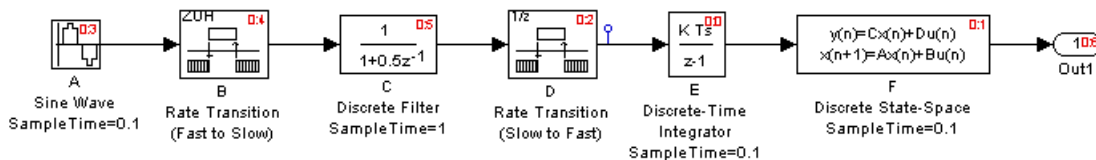
Introduction

This section examines how a simple multirate model executes in both real time and simulation, using a fixed-step solver. It considers the operation of both SingleTasking and MultiTasking solver **Tasking modes**.

The example model is shown in the next figure. The discussion refers to the six blocks of the model as A through F, as labeled in the block diagram.

The execution order of the blocks (indicated in the upper right of each block) has been forced into the order shown by assigning higher priorities to blocks F, E, and D. The ordering shown is one possible valid execution ordering for this model. (See “Simulating Dynamic Systems” in the Simulink documentation.)

The execution order is determined by data dependencies between blocks. In a real-time system, the execution order determines the order in which blocks execute within a given time interval or task. This discussion treats the model’s execution order as a given, because it is concerned with the allocation of block computations to tasks, and the scheduling of task execution.



Note The discussion and timing diagrams in this section are based on the assumption that the Rate Transition blocks are used in the default (protected/deterministic) mode, with the **Ensure data integrity during data transfer** and **Ensure deterministic data transfer (maximum delay)** options on.

Single-Tasking Execution

This section considers the execution of the above model when the solver **Tasking mode** is `SingleTasking`.

In a single-tasking system, if the **Block reduction** option is on, fast-to-slow Rate Transition blocks are optimized out of the model. The default case is shown (**Block reduction** on), so block B does not appear in the timing diagrams in this section. See “Reducing the Number of Blocks in a Model” on page 9-29 for more information.

The following table shows, for each block in the model, the execution order, sample time, and whether the block has an output or update computation. Block A does not have discrete states, and accordingly does not have an update computation.

Execution Order and Sample Times (Single-Tasking)

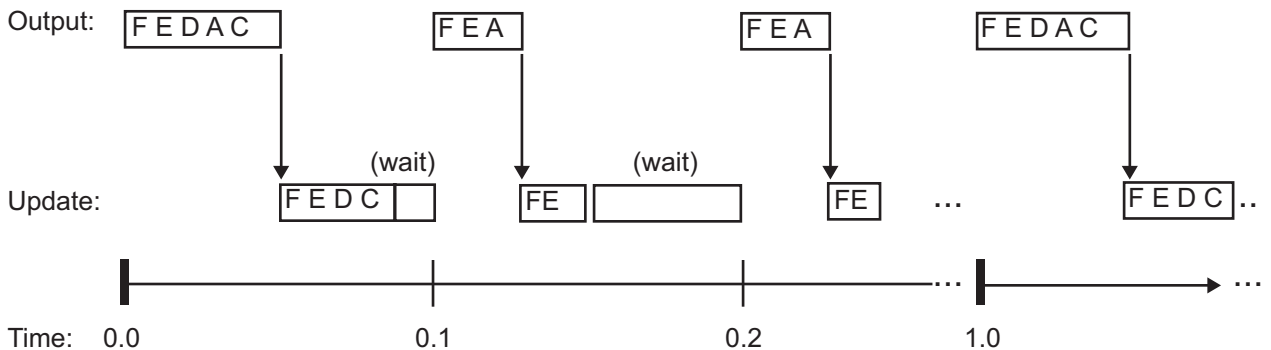
Blocks (in Execution Order)	Sample Time (in Seconds)	Output	Update
F	0.1	Y	Y
E	0.1	Y	Y
D	1	Y	Y

Execution Order and Sample Times (Single-Tasking) (Continued)

Blocks (in Execution Order)	Sample Time (in Seconds)	Output	Update
A	0.1	Y	N
C	1	Y	Y

Real-Time Single-Tasking Execution

The next figure shows the scheduling of computations when the generated code is deployed in a real-time system. The generated program is shown running in real time, under control of interrupts from a 10 Hz timer.



At time 0.0, 1.0, and every second thereafter, both the slow and fast blocks execute their output computations; this is followed by update computations for blocks that have states. Within a given time interval, output and update computations are sequenced in block execution order.

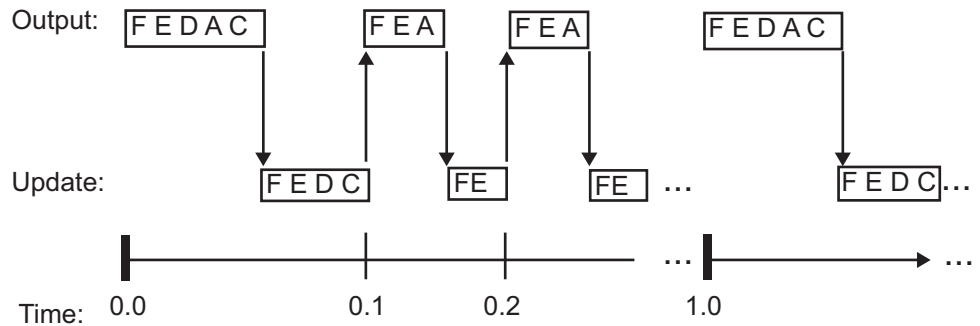
The fast blocks execute on every tick, at intervals of 0.1 second. Output computations are followed by update computations.

The system spends some portion of each time interval (labeled “wait”) idling. During the intervals when only the fast blocks execute, a larger portion

of the interval is spent idling. This illustrates an inherent inefficiency of single-tasking mode.

Simulated Single-Tasking Execution

The next figure shows the execution of the model in Simulink by using the simulation loop.



Because time is simulated, the placement of ticks represents the iterations of the simulation loop. Blocks execute in exactly the same order as in the previous figure, but without the constraint of a real-time clock. Therefore there is no idle time between simulated sample periods.

Multitasking Execution

This section considers the execution of the above model when the solver **Tasking mode** is `MultiTasking`. Block computations are executed under two tasks, prioritized by rate:

- The slower task, which gets the lower priority, is scheduled to run every second. This is called the *1 second task*.
- The faster task, which gets higher priority, is scheduled to run 10 times per second. This is called the *0.1 second task*. The 0.1 second task can preempt the 1 second task.

The following table shows, for each block in the model, the execution order, the task under which the block runs, and whether the block has an output

or update computation. Blocks A and B do not have discrete states, and accordingly do not have an update computation.

Task Allocation of Blocks in Multitasking Execution

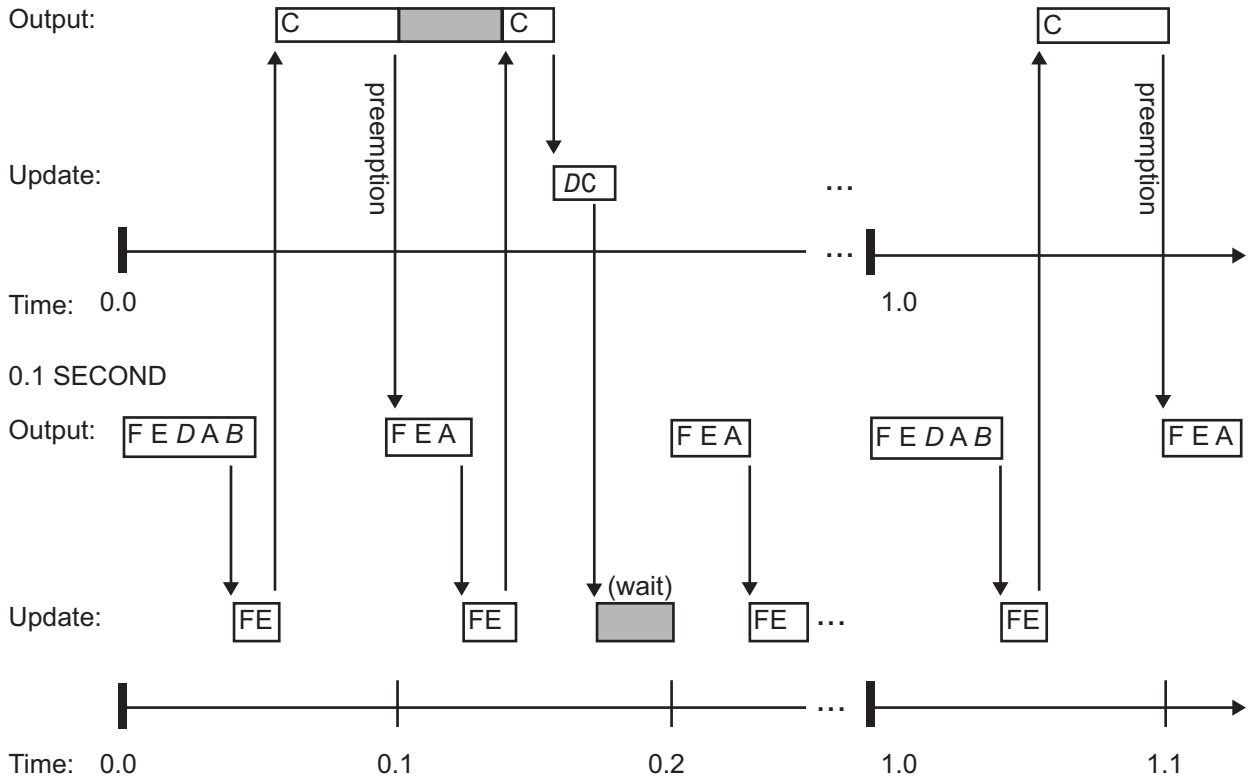
Blocks (in Execution Order)	Task	Output	Update
F	0.1 second task	Y	Y
E	0.1 second task	Y	Y
D	The Rate Transition block uses port-based sample times. Output runs at the output port sample time under 0.1 second task. Update runs at input port sample time under 1 second task. For more information on port-based sample times, see “Inheriting Sample Times” in the Simulink documentation.	Y	Y
A	0.1 second task	Y	N
B	The Rate Transition block uses port-based sample times. Output runs at the output port sample time under 0.1 second task. For more information on port-based sample times, see “Inheriting Sample Times” in the Simulink documentation.	Y	N
C	1 second task	Y	Y

Real-Time Multitasking Execution

The next figure shows the scheduling of computations in MultiTasking solver mode when the generated code is deployed in a real-time system. The

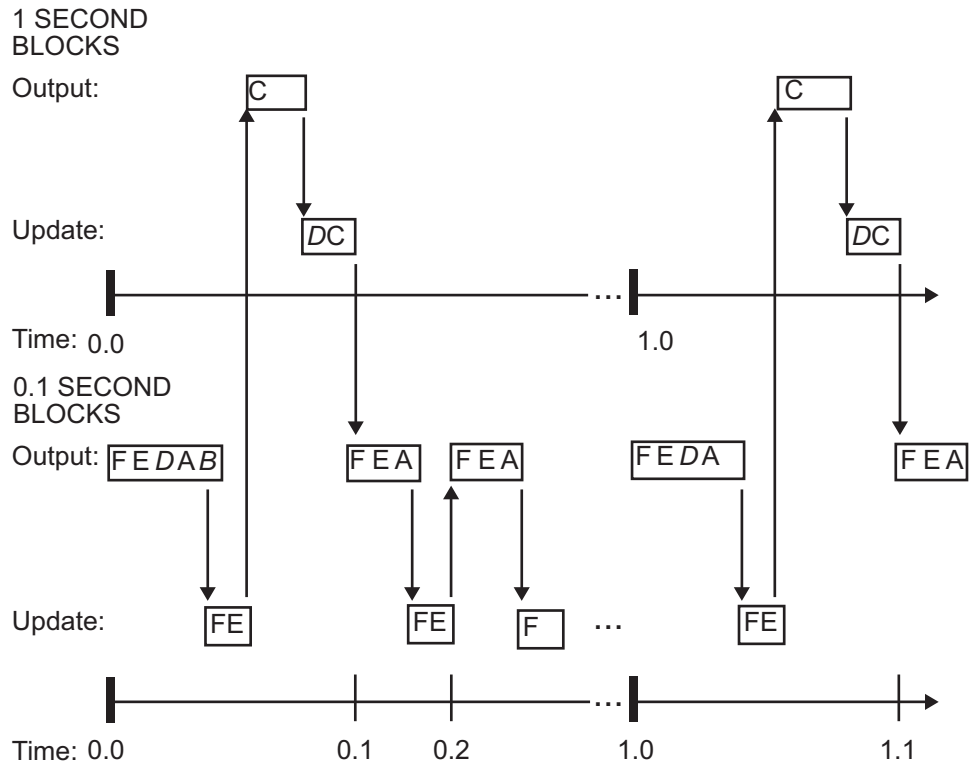
generated program is shown running in real time, as two tasks under control of interrupts from a 10 Hz timer.

1 SECOND



Simulated Multitasking Execution

The next figure shows the execution of the same model in Simulink, in MultiTasking solver mode. In this case, Simulink runs all blocks in one thread of execution, simulating multitasking. No preemption occurs.



Optimizing a Model for Code Generation

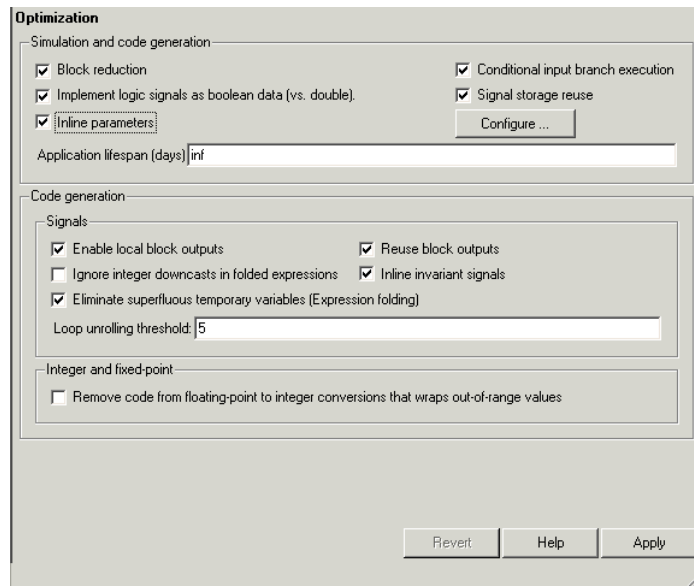
You can optimize memory usage and performance of code generated from your model by Real-Time Workshop a number of ways. This chapter discusses optimization techniques that are common to all target configurations and code formats. For an overview of controlling optimization, see “Configuring Optimizations” on page 2-28. For optimizations specific to a particular target configuration, see the chapters relevant to that target.

Optimization Parameters Overview (p. 9-3)	Discusses options on the Configuration Parameters dialog box that affect code size and efficiency
Optimizing Models (p. 9-5)	Discusses optimization tools and techniques that you can use with any target configuration
Minimizing Computations and Storage for Intermediate Results (p. 9-9)	Explains an optimization that significantly reduces the need to compute and store temporary results
Block Diagram Performance Tuning (p. 9-16)	Explains how to use lookup tables, accumulator constructs, and data types efficiently
Optimizing Signals (p. 9-40)	Explains how you can optimize logic signals and how signals, in general, are stored
Inlining Parameters (p. 9-43)	Explains how to configure a model to inline parameters

Configuring a Loop Unrolling Threshold (p. 9-45)	Explains how to optimize generated code by setting a loop unrolling threshold
Controlling Memory Allocation for Time Counters (p. 9-47)	Explains how you can control how memory is allocated for time counters
Optimizing Code Resulting from Floating-Point to Integer Conversions (p. 9-48)	Explains how to optimize code resulting from floating-point to integer conversions
Optimization Dependencies (p. 9-50)	Describes parameter dependencies in the Optimization pane

Optimization Parameters Overview

Many options on the **Optimization** pane of the Configuration Parameters dialog box affect generated code. The next figure shows the default optimization settings, plus **Inline parameters** and **Inline invariant signals** (which are both off by default).



Some basic optimization suggestions are given below, cross-referenced to more extensive relevant discussions in the documentation.

- Turn on the **Signal storage reuse** option. The option directs Real-Time Workshop to store signals in reusable memory locations. It also enables the **Local block outputs** option (see below, and “Reducing Memory Requirements for Signals” on page 9-40).

Disabling **Signal storage reuse** makes all block outputs global and unique, which in many cases significantly increases RAM and ROM usage.

- Select the **Inline parameters** check box. Inlining parameters reduces global RAM usage, because parameters are not declared in the global parameters structure. You can override the inlining of individual

parameters by using the Model Parameter Configuration dialog box. You tune parameters used in referenced models differently, by declaring them as Model block parameter arguments, rather than using the Model Parameter Configuration dialog box. See “Inlining Parameters” on page 9-43 and “Using Model Arguments” in the Simulink documentation for more details.

- Set an appropriate **Loop unrolling threshold**. The loop unrolling threshold determines when a wide signal should be wrapped into a for loop and when it should be generated as a separate statement for each element of the signal. See “Configuring a Loop Unrolling Threshold” on page 9-45 for details on this feature.
- Select the **Inline invariant signals** option. Real-Time Workshop does not generate code for blocks with a constant (invariant) sample time. You must select **Inline parameters** to invoke this option. See “Inlining Invariant Signals” on page 9-41.
- Select the **Enable local block outputs** option. Block signals are declared locally in functions instead of being declared globally (when possible). You must select **Signal storage reuse** to enable the **Enable local block outputs** option. See “Declaring Signals as Local Function Data” on page 9-41.
- Select the **Eliminate superfluous temporary variables (Expression folding)** option, discussed in “Minimizing Computations and Storage for Intermediate Results” on page 9-9.
- Select the **Reuse block outputs** option. This option can reduce stack size where signals are being buffered in local variables. See “Reusing Memory Allocated for Signals” on page 9-41.

Optimizing Models

In this section...

“Using the Model Advisor” on page 9-5

“Demos Illustrating Optimizations” on page 9-5

“Other Optimization Tools and Techniques” on page 9-5

Using the Model Advisor

Using the Model Advisor, you can quickly analyze a model for code generation and identify aspects of your model that impede production deployment or limit code efficiency. You control the tool from a browser window, from which you can select from a set of checks on a model’s current configuration. Model Advisor analyzes the model and in the same window generates a report describing both good and bad conditions, providing suggestions for improvements in each area. Most Model Advisor diagnostics do not require the model to be in a compiled state; those that do are noted.

For more information on using the Model Advisor, see “Consulting Model Advisor” in the Simulink documentation.

Demos Illustrating Optimizations

The `rtwdemos` demo suite includes a set of demonstration models that illustrate optimization settings and techniques. To access these demos, type

```
rtwdemos
```

or click the above command. The MATLAB Help browser opens the Real-Time Workshop demos page. Click **Optimizations** in the navigation pane. Use the listed demos to learn about the specific effects that optimization parameters and techniques have on models.

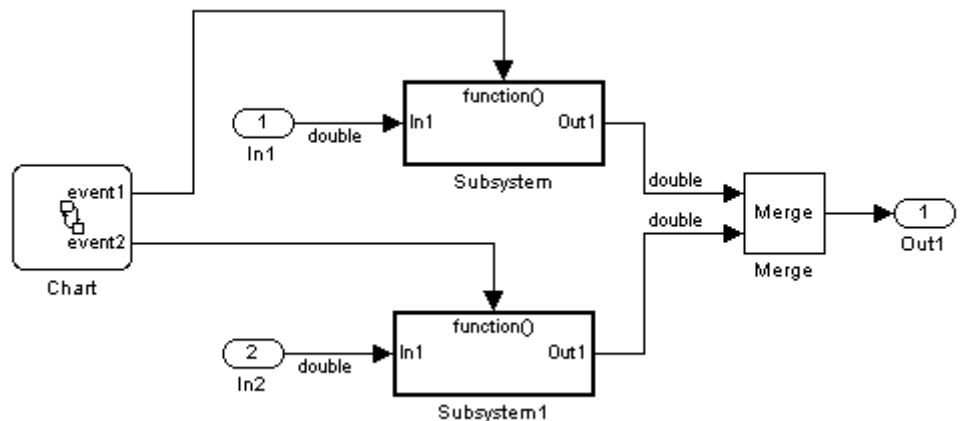
Other Optimization Tools and Techniques

In addition to analyzing models with Model Advisor (see “Using the Model Advisor” on page 9-5), you can use a variety of other tools and techniques that work with any code format. Here are some particularly useful ones:

- Run the `slupdate` command to automatically convert older models (saved by prior versions or by the current one) to use current features. For details about what `slupdate` does, type

```
help slupdate
```

- Before building, set optimization flags for the compiler (for example, `-O2` for `gcc`, `-Ot` for Microsoft Visual C).
- Directly inline C/C++ S-functions into the generated code by writing a TLC file for the S-function. See Chapter 11, “S-Function Target” and the Target Language Compiler documentation for more information on inlining S-functions.
- Use a Simulink data type other than `double` when possible. The available data types are `Boolean`, signed and unsigned 8-, 16-, and 32-bit integers, and 32- and 64-bit floats (a `double` is a 64-bit float). See “Working with Data” in the Simulink documentation for more information on data types. For a block-by-block summary, click `showblockdatatypetable` or type the command in the MATLAB Command Window.
- Remove repeated values in lookup table data.
- Use the Merge block to merge the output of signals wherever possible. This block is particularly helpful when you need to control the execution of function-call subsystems with Stateflow. The following model shows an example of how to use the Merge block.



When more than one signal connected to a Merge block has a non-Auto storage class, all non-Auto signals connected to that block must *be identically labeled and have the same storage class*. When Merge blocks connect directly to one another, these rules apply to all signals connected to any of the Merge blocks in the group.

Minimizing Memory Requirements for Parameters and Data During Code Generation

When Real-Time Workshop generates code, it creates an intermediate representation of your model (called `model.rtw`), which the Target Language Compiler parses to transform block computations, parameters, signals, and constant data into a high-level language, (for example, C). Parameters and data are normally copied into the `model.rtw` file, whether they originate in the model itself or come from variables or objects in a workspace.

Models which have large amounts of parameter and constant data (such as lookup tables) can tax memory resources and slow down code generation because of the need to copy their data to `model.rtw`. You can improve code generation performance by limiting the size of data that is copied by using a `set_param` command, described below.

Data vectors such as those for parameters, lookup tables, and constant blocks whose sizes exceed a specified value are not copied into the `model.rtw` file. In place of the data vectors, Real-Time Workshop places a special reference key

in the intermediate file that enables the Target Language Compiler to access the data directly from Simulink when it is needed and format it directly into the generated code. This results in maintaining only one copy of large data vectors in memory.

You can specify the maximum number of elements that a parameter or other data source can have for Real-Time Workshop to represent it literally in the *model.rtw* file. Whenever this threshold size is exceeded, Real-Time Workshop writes a reference to the data to the *model.rtw* file, rather than its values. The default threshold value is 10 elements, which you can verify with

```
get_param(0, 'RTWDataReferencesMinSize')
```

To set the threshold to a different value, type the following `set_param` function in the MATLAB Command Window:

```
set_param(0, 'RTWDataReferencesMinSize', <size>)
```

Provide an integer value for `size` that specifies the number of data elements above which reference keys are to be used in place of actual data values.

Minimizing Computations and Storage for Intermediate Results

In this section...

“Introduction” on page 9-9

“Expression Folding Example” on page 9-10

“Using and Configuring Expression Folding” on page 9-11

Introduction

Expression folding is a code optimization technique that minimizes the computation of intermediate results at block outputs and the storage of such results in temporary buffers or variables. **Eliminate superfluous temporary variables (Expression folding)** is used to enable expression folding. When expression folding is on, Real-Time Workshop collapses, or “folds,” block computations into a single expression, instead of generating separate code statements and storage declarations for each block in the model.

Expression folding can dramatically improve the efficiency of generated code, frequently achieving results that compare favorably to hand-optimized code. In many cases, entire groups of model computations fold into a single highly optimized line of code.

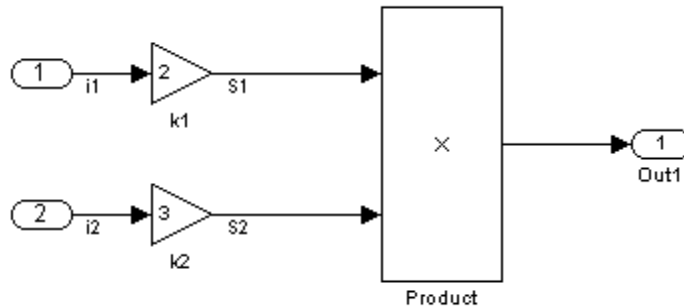
By default, expression folding is on. The Real-Time Workshop code generation options are configured to use expression folding wherever possible. Most Simulink blocks support expression folding.

You can also take advantage of expression folding in your own inlined S-function blocks. See “Writing S-Functions That Support Expression Folding” on page 10-53 for information on how to do this.

In the code generation examples that follow, the **Signal storage reuse** optimizations (**Enable local block outputs**, **Reuse block outputs**, and **Eliminate superfluous temporary variables (Expression folding)**) are all turned on.

Expression Folding Example

As a simple example of how expression folding affects the code generated from a model, consider the following model.



With expression folding on, this model generates a single-line output computation, as shown in this *model_output* function.

```
static void exprfld_output(int_T tid)
{
    /* local block i/o variables */

    /* Outputport: '<Root>/Out1' incorporates:
     * Gain: '<Root>/k1'
     * Gain: '<Root>/k2'
     * Product: '<Root>/Product'
     */
    exprfld_Y.Out1 = exprfld_U.i1 * exprfld_P.k1_Gain *
        (exprfld_U.i2 * exprfld_P.k2_Gain);
}
```

The generated comments indicate the block computations that were combined into a single expression. The comments also document the block parameters that appear in the expression.

With expression folding off, the same model computes temporary results for both Gain blocks and the Product block before the final output, as shown in this output function:

```
static void exprfld_output(int_T tid)
{
    /* local block i/o variables */

    real_T rtb_k2_i;
    real_T rtb_Product_i;

    /* Gain: '<Root>/k1' */
    rtb_Product_i = exprfld_U.i1 * exprfld_P.k1_Gain;

    /* Gain: '<Root>/k2' */
    rtb_k2_i = exprfld_U.i2 * exprfld_P.k2_Gain;

    /* Product: '<Root>/Product' */
    rtb_Product_i *= rtb_k2_i;

    /* Output: '<Root>/Out1' */
    exprfld_Y.Out1 = rtb_Product_i;
}
```

For an example of expression folding in the context of a more complex model, click `rtwdemo_slexprfold`, or type the following command at the MATLAB prompt.

```
rtwdemo_slexprfold
```

Using and Configuring Expression Folding

The options described in this section let you control the operation of expression folding.

- “Enabling Expression Folding” on page 9-12
- “Expression Folding Options” on page 9-13

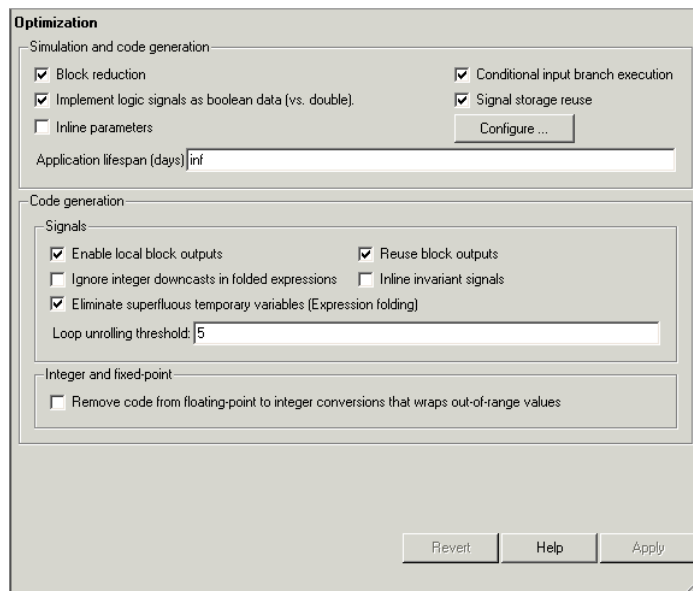
Enabling Expression Folding

Expression folding operates only on expressions involving local variables. Expression folding is therefore available only when the **Signal storage reuse** code generation option is on.

For a new model, default code generation options are set to use expression folding. If you are configuring an existing model, you can ensure that expression folding is turned on as follows:

- 1 Open the Configuration Parameters dialog box and select the **Optimization** pane.
- 2 Select the **Signal storage reuse** option.
- 3 Select the **Enable Local block outputs** option.
- 4 Enable expression folding by selecting **Eliminate superfluous temporary variables (Expression folding)**.

The **Optimization** pane appears in the next figure. By default, all expression folding related options are selected, as shown.



5 Click **Apply**.

Expression Folding Options

This section discusses the optimization code generation options related to expression folding.

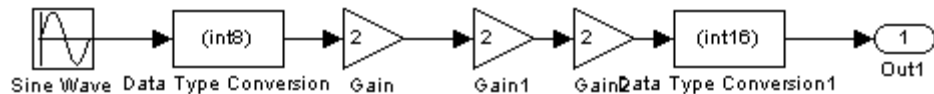
Eliminate superfluous temporary variables (Expression folding). This option turns the expression folding feature on or off.

Ignore integer downcasts in folded expressions. This option specifies how Real-Time Workshop should handle 8-bit operations on 16-bit microprocessors and 8- and 16-bit operations on 32-bit microprocessors. To ensure consistency between simulation and code generation, the results of 8 and 16-bit integer expressions must be explicitly downcast.

Selecting this option improves code efficiency by avoiding casts of intermediate variables. However, the primary effect of selecting this option is that expressions involving 8- and 16-bit arithmetic are less likely to overflow in code than they are in simulation. Therefore, it is good practice to turn off **Ignore integer downcasts in folded expressions** for safety, to ensure that answers obtained from generated code are consistent with simulation results. Turn the option on only if

- You are concerned with generating the least amount of code possible
- Code generation and simulation results do not need to match

As an example, consider this model.



The following code shows the output computation (within the output function) when **Ignore integer downcasts in folded expressions** is off. The Gain blocks are folded into a single expression. In addition to the typecasts generated by the Type Conversion blocks, each Gain block output is cast to `int8_T`.

```

int8_T rtb_Data_Type_Conversion;
.
.
.
rtY.Out1 = (int16_T)(int8_T)(rtP.Gain2_Gain * (int8_T)
(rtP.Gain1_Gain * (int8_T)(rtP.Gain_Gain *
rtb_Data_Type_Conversion)));

```

If **Ignore integer downcasts in folded expressions** is on, the code contains only the typecasts generated by the Type Conversion blocks, as shown in the following code.

```

int8_T rtb_Data_Type_Conversion;
.
.
.
rtY.Out1 = (int16_T)(rtP.Gain2_Gain * (rtP.Gain1_Gain *
(rtP.Gain_Gain * rtb_Data_Type_Conversion)));

```

As another example, consider the following pseudo code:

```

Int16 a,b,c,d,e1,e2;
c = a + b;
e1 = c + d;

```

This would be bit equivalent to the following when **Ignore integer downcasts in folded expressions** is off.

```

e1 = (Int16)(a + b) + d;

```

If **Ignore integer downcasts in folded expressions** is on, the code would be generated as

```

e2 = a + b + d;

```

If the processor's accumulator is 16 bits, then e1 equals e2. If the accumulator is greater than 16 bits, e1 and e2 might not be equal. As an example, consider a case where (a+b) would result in a value greater than 16-bits, but (a+b+d) could be represented in 16 bits. In general, the integer down cast implementation, e2, gives correct mathematical results over a larger range of values.

Discussion. Suppose you create a model in which the output of a Sum block is a signed 8-bit number. Such numbers have a range of from -128 to +127. During simulation, the value of the Sum block's output will always be in the range -128 to +127. If the calculations involved in computing the output exceeded that range, then an overflow would occur and Simulink would provide an (optional) diagnostic.

When it comes to code running on a target processor, integer downcasts occur frequently. Most microprocessors are designed to do direct math on integers of certain sizes.

For example, a typical 16-bit microprocessor might only provide for direct multiplication on 16-bit integers and direct addition for 16- and 32-bit integers. Such a processor can perform math operations on smaller integers, but only indirectly, according to the following steps:

- 1 The smaller integers are loaded into bigger CPU registers.
- 2 The “big math” is performed.
- 3 The results are “integer downcast” so they are limited to the range of the smaller integers, for example, -128 to +127

Step 3 requires extra machine instructions, ROM code, and clock cycles.

In many situations, Step 3 is a total waste of effort. For example, you might have designed your model so that it is impossible for the results to exceed the range -128 to +127. With such safeguards in place, step 3 will never change the results of calculations, and simply gives a less efficient implementation. In this type of situation you should turn on the **Ignore integer downcasts in folded expressions** optimization and bypass the range checks that decrease your application's efficiency without contributing any value.

If the calculations had overflowed, then turning on the **Ignore integer downcasts in folded expressions** option would cause your generated code to give different results from the Simulink model produced. You might or might not consider this difference to be a problem, but it is something you should be aware can happen.

Block Diagram Performance Tuning

In this section...

- “Introduction” on page 9-16
- “Lookup Tables and Polynomials” on page 9-16
- “Reducing the Number of Blocks in a Model” on page 9-29
- “Optimizing Code for Switch Blocks” on page 9-33
- “Optimizing Data Type Usage” on page 9-34
- “Additional Integer and Fixed-Point Optimizations” on page 9-38

Introduction

Certain block constructs in Simulink will run faster, or require less code or data memory, than other seemingly equivalent constructs. Knowing the tradeoffs between similar blocks and block parameter options enables you to create Simulink models that have intuitive diagrams, and to produce the tight code that you want from Real-Time Workshop. Many of the options and constructs discussed in this section improve the simulation speed of the model itself, even without code generation.

Lookup Tables and Polynomials

Simulink provides several blocks that allow approximation of functions. These include blocks that perform direct, interpolated, and cubic spline lookup table operations, and a polynomial evaluation block.

There are currently six different blocks in Simulink that perform lookup table operations:

- Look-Up Table
- Look-Up Table (2-D)
- Look-Up Table (n-D)
- Direct Look-Up Table (n-D)
- PreLook-Up Index Search

- Interpolation (n-D) Using PreLook-Up Index Search

In addition, the Repeating Sequence block uses a lookup table operation, the output of which is a function of the real-time (or simulation-time) clock.

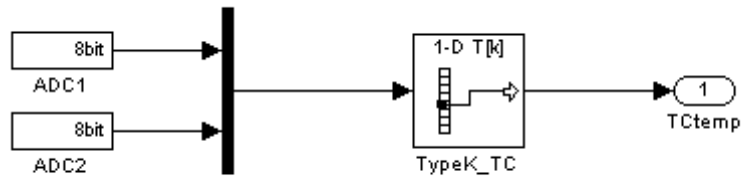
To get the most out of the following discussion, you should familiarize yourself with the features of these blocks, as discussed in the Simulink documentation.

Each type of lookup table block has its own set of options and associated tradeoffs. The examples in this section show how to use lookup tables effectively. The techniques demonstrated here will help you achieve maximal performance with minimal code and data sizes.

Multichannel Nonlinear Signal Conditioning

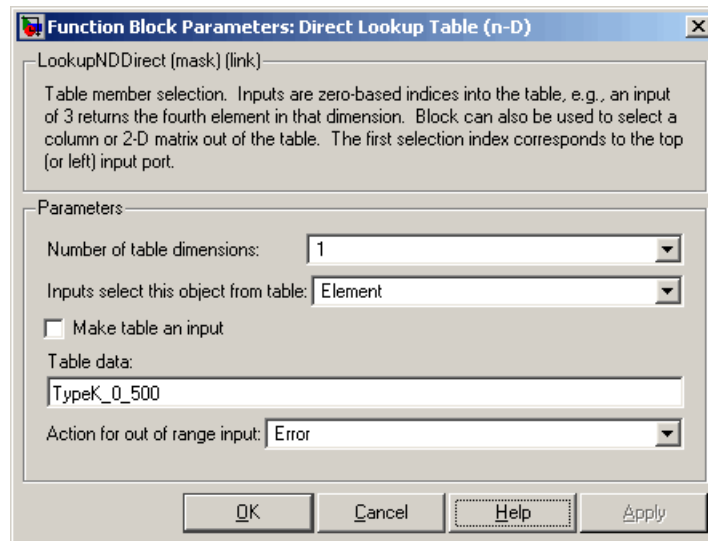
The next figure shows a Simulink model that reads input from two 8-channel, high-speed 8-bit analog/digital converters (ADCs). The ADCs are connected to Type K thermocouples through a gain circuit with an amplification of 250. Since the popular Type K thermocouples are highly nonlinear, there is an international standard for converting their voltages to temperature. In the range of 0 to 500 degrees Celsius, this conversion is a tenth-order polynomial. One way to perform the conversion from ADC readings (0-255) into temperature (in degrees Celsius) is to evaluate this polynomial. In the best case, the polynomial evaluation requires 9 multiplications and 10 additions per channel.

A polynomial evaluation is not the fastest way to convert these 8-bit ADC readings into measured temperature. Instead, the model uses a Direct Look-Up (n-D) Table block (named TypeK_TC) to map 8-bit values to temperature values. This block performs one array reference per channel.



Direct Look-Up Table (n-D) Block Conditions ADC Input

The block's table parameter has 256 values that correspond to the temperature at an ADC reading of 0, 1, 2, ... up to 255. The table data, calculated in MATLAB, is stored in the workspace variable `TypeK_0_500`. The block's **Table data** parameter field references `TypeK_0_500`, as the preceding figure shows.



Parameters of Direct Look-Up Table (n-D) Block

The model uses a Mux block to collect all similar signals (for example, Type K thermocouple readings) and feed them into a single Direct Look-Up Table block. This is more efficient than using one Direct Look-Up Table block per device. If multiple blocks share a common parameter (such as the table in

this example), Real-Time Workshop creates only one copy of that parameter in the generated code.

This is the recommended approach for signal conditioning when the size of the table can fit within your memory constraints. In this example, the table stores 256 double (8-byte) values, utilizing 2 KB of memory.

The TypeK_TC block processes 24 channels of data sequentially.

Real-Time Workshop generates the following code for the TypeK_TC block shown previously.

```

/* LookupNDDirect: '<Root>/TypeK_TC' */
/* 1-dimensional Direct Look-Up returning 24 Scalars */
{
    int_T i1;

    const uint8_T *u0 = rtb_TmpHiddenBuffer_Feeding_Typ;
    real_T *y0 = rtb_TypeK_TC_k;

    for (i1=0; i1 < 24; i1++) {
        y0[i1] = (lookupADC_ConstP.TypeK_TC_table[u0[i1]]);
    }
}

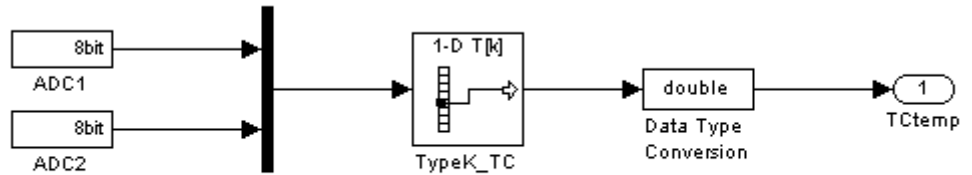
{
    int32_T i1;

    /* Output: '<Root>/TCtemp' */
    for(i1=0; i1<24; i1++) {
        lookupADC_Y.TCtemp[i1] = rtb_TypeK_TC_k[i1];
    }
}

```

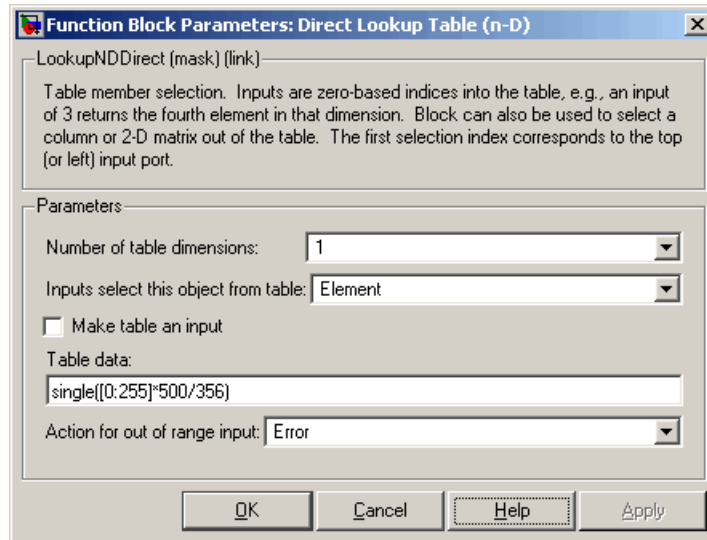
Notice that the core of each loop is one line of code that directly retrieves a table element from the table and places it in the block output variable. There are two loops in the generated code because the two simulated ADCs are not merged into a contiguous memory array in the Mux block. Instead, to avoid a copy operation, the Direct Look-Up Table block performs the lookup on two sets of data using a single table array (lookupADC_ConstP.TypeK_TC_table[]).

If the input accuracy for your application (not to be confused with the number of I/O bits) is 24 bits or less, you can use a single-precision table for signal conditioning. Then, cast the lookup table output to double precision for use in the rest of the block diagram. This technique, shown in the next section, causes no loss of precision.



Single-Precision Lookup Table Output Is Cast to Double Precision

A direct lookup table covering 24 bits of accuracy would require 64 megabytes of memory, which is typically not practical. To create a single-precision table, use the MATLAB `single()` cast function in your table calculations. Alternatively, you can perform the typecast directly in the **Table data** parameter, as shown in the next section.



Typcasting Table Data in a Direct Lookup Block

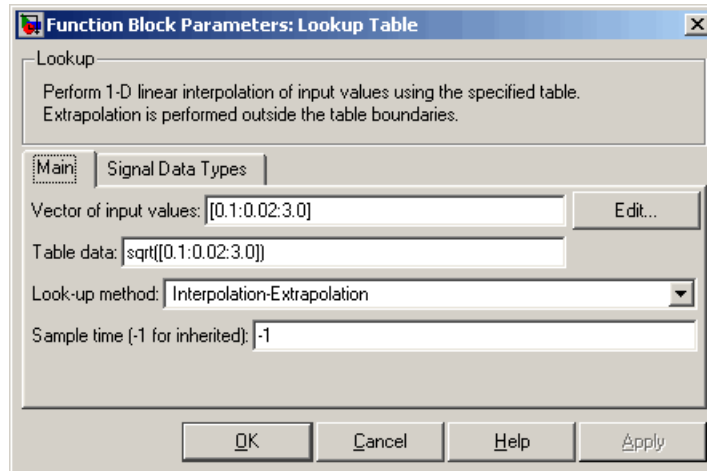
When table size becomes impractical, you must use other nonlinear techniques, such as interpolation or polynomial techniques. The Look-Up Table (n-D) block supports linear interpolation and cubic spline interpolation. The Polynomial block supports evaluation of noncomplex polynomials.

Compute-Intensive Equations

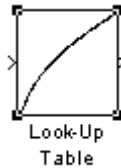
The blocks described in this section are useful for simplifying fixed, complex relationships that are normally too time consuming to compute in real time.

The only practical way to implement some compute-intensive functions or arbitrary nonlinear relationships in real time is to use some form of lookup table. On processors that do not have floating-point instructions, even functions like `sqrt()` can become too expensive to evaluate in real time.

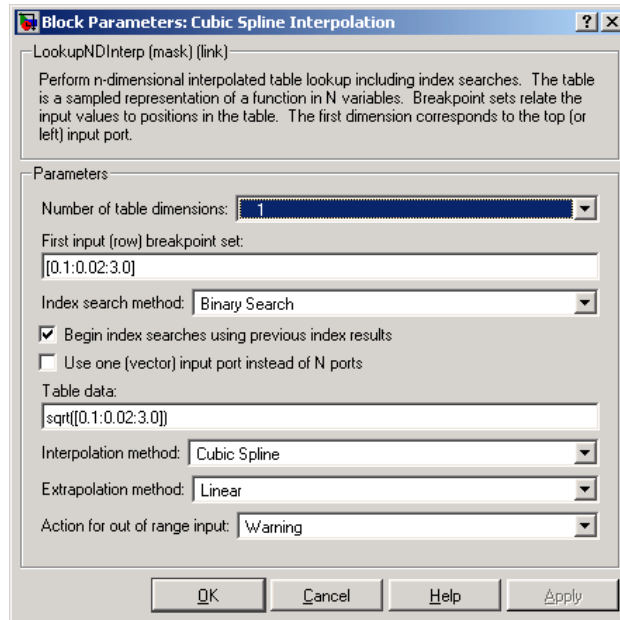
An approximation to the nonlinear relationship in a known range will work in most cases. For example, your application might require a square root calculation that your target processor's instruction set does not support. The next figure shows how you can use a Look-Up Table block to calculate an approximation of the square root function that covers a given range of the function.



The interpolated values are plotted on the block icon.



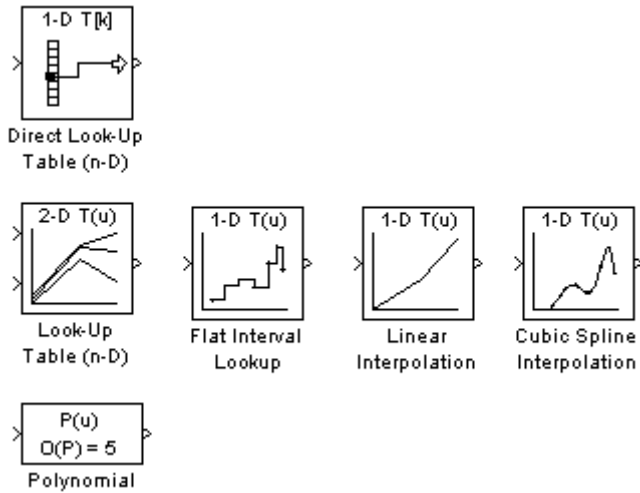
For more accuracy on widely spaced points, use a cubic spline interpolation in the Look-Up Table (n-D) block, as shown in the next figure.



Techniques available in Simulink include n-dimensional support for direct lookup, linear interpolations in a table, cubic spline interpolations in a table, and 1-D real polynomial evaluation.

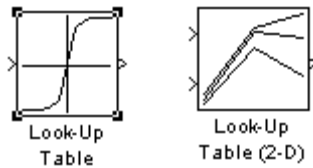
The Look-Up Table (n-D) block supports flat interval lookup, linear interpolation and cubic spline interpolation. Extrapolation for the Look-Up Table (n-D) block can either be disabled (clipping) or enabled for linear or spline extrapolations.

The icons for the Direct Look-Up Table (n-D) and Look-Up Table (n-D) blocks change depending on the type of interpolation selected and the number of dimensions in the table, as shown in the next figure.



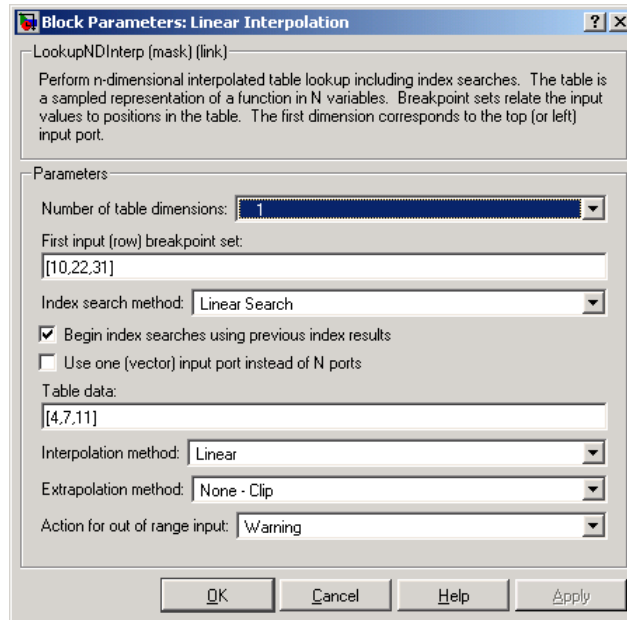
Tables with Repeated Points

The Look-Up Table and Look-Up Table (2-D) blocks, shown in the next figure, support linear interpolation with linear extrapolation. In these blocks, the row and column parameters can have repeated points, allowing pure step behavior to be mixed in with the linear interpolations. This capability is not supported by the Look-Up Table (n-D) block.



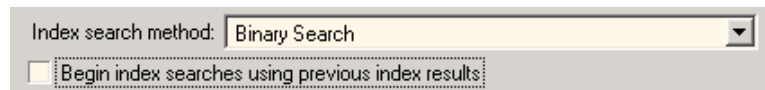
Slowly Versus Rapidly Changing Look-Up Table Block Inputs

You can optimize lookup table operations using the Look-Up Table (n-D) block for efficiency if you know the input signal's normal rate of change. The next figure shows the parameters for the Look-Up Table (n-D) block.

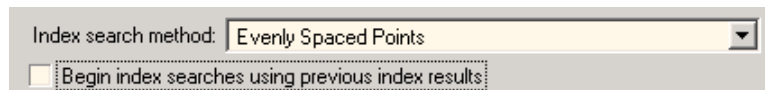


Parameter Dialog Box for the Look-Up Table (n-D) Block

If you do not know the input signal's normal rate of change in advance, it would be better to choose the **Binary Search** option for the index search in the Look-Up Table (n-D) block and the PreLook-Up Index Search block.



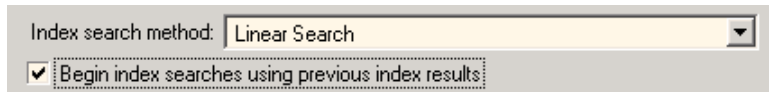
Regardless of signal behavior, if the table's breakpoints are evenly spaced, it is best to select the **Evenly Spaced Points** option from the Look-Up Table (n-D) block's parameter dialog box.



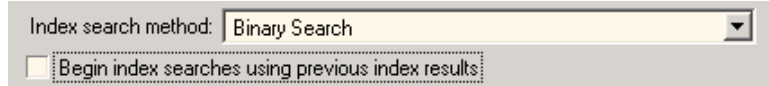
If the breakpoints are not evenly spaced, first decide which of the following best describes the input signal behavior.

- Behavior 1: The signal stays in a given breakpoint interval from one time step to the next. When the signal moves to a new interval, it tends to move to an adjacent interval.
- Behavior 2: The signal has many discontinuities. It jumps around in the table from one time step to the next, often moving three or more intervals per time step.

Given behavior 1, the best optimization for a given lookup table is to use the **Linear search option** and **Begin index searches using previous index results** options, as shown in the next figure.

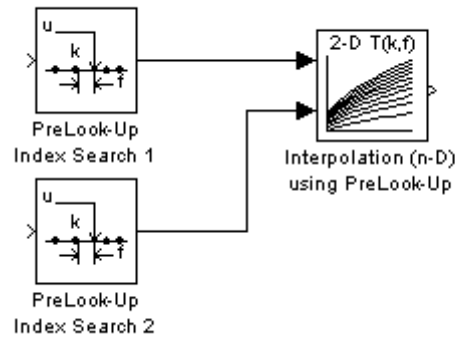


Given behavior 2, the **Begin index searches using previous index results** option does not necessarily improve performance. Choose the **Binary Search** option, as shown in the next figure.



The choice of an index search method can be more complicated for lookup table operations of two or more dimensions with linear interpolation. In this case, several signals are input to the table. Some inputs may have evenly spaced points, while others can exhibit behavior 1 or behavior 2.

Here it might be best to use PreLook-Up Index Search blocks with different search methods (evenly spaced, linear search, or binary search) chosen according to the input signal characteristics. The outputs of these search blocks are then connected to an Interpolation (n-D) Using PreLook-Up Index Search block, as shown in the block diagram in the next figure.

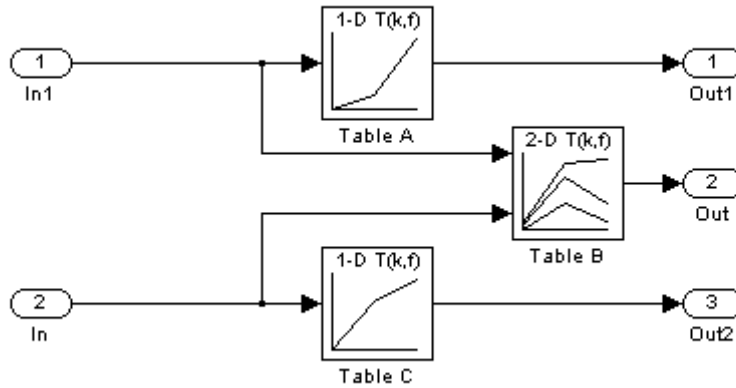


You can configure each PreLook-Up Index Search block independently to use the best search algorithm for the breakpoints and input time variation cases.

Multiple Tables with Common Inputs

The index search can be the most time consuming part of flat or linear interpolation calculations. In large block diagrams, lookup table blocks often have the same input values as other lookup table blocks. If this is the case in your block diagram, you can save much computation time by making the breakpoints common to all tables. This saving is obtained by using one set of PreLook-Up Index Search blocks to perform the searches once for all tables, so that only the interpolation remains to be calculated.

The next figure is an example of a block diagram that can be optimized by this method.

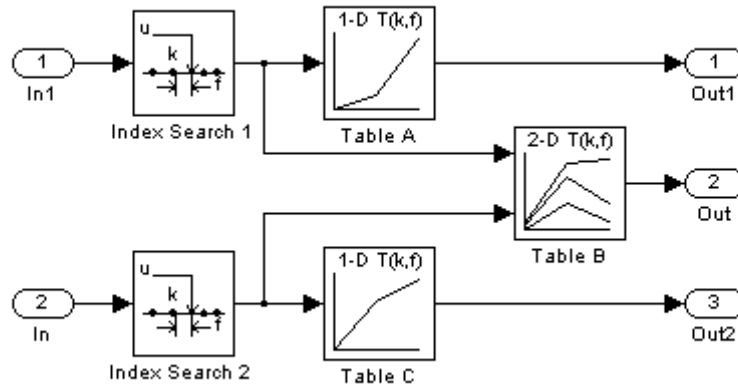


Before Optimization

Assume that Table A's breakpoints are the same as Table B's first input breakpoints, and that Table C's breakpoints are the same as Table B's second input breakpoints.

A 50% reduction in index search time is obtained by pulling these common breakpoints out into a pair of PreLook-Up Index Search blocks, and using Interpolation (n-D) Using PreLook-Up Index Search blocks to perform the interpolation.

The next figure shows the optimized block diagram.



After Optimization

In the above diagram, the Look-Up Table (n-D) blocks have been replaced with Interpolation (n-D) Using PreLook-Up blocks. The PreLook-Up Index Search blocks have been added to perform the index searches separately from the interpolations, to realize the savings in computation time.

In large controllers and simulations, it is not uncommon for hundreds of multidimensional tables to rely on a dozen or so breakpoint sets. Using the optimization technique shown in this example, you can greatly increase the efficiency of your application.

Reducing the Number of Blocks in a Model

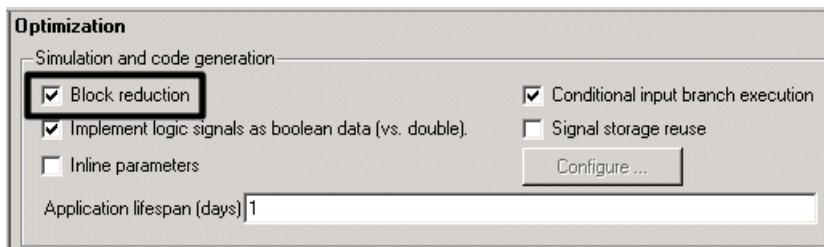
When you check **Block reduction**, Simulink collapses certain groups of blocks into a single, more efficient block, or removes them entirely. This results in faster execution during model simulation and in generated code. The appearance of the source model does not change.

Note that block reduction is only intended to remove the code that represents execution of a block. Other supporting data, such as definitions for sample time and data types might remain in the generated code.

By default, **Block reduction** is checked. The types of block reduction are

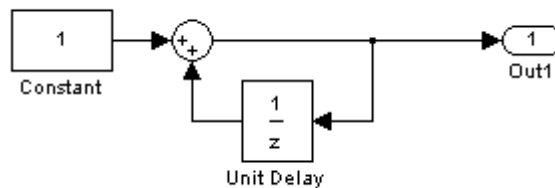
- “Accumulators” on page 9-30
- “Removal of Redundant Type Conversions” on page 9-31
- “Dead Code Elimination” on page 9-32
- “Fast-to-slow Rate Transition block in a single-tasking system” on page 9-33

To enable this option, select **Block reduction** on the **Optimization** pane of the Configuration Parameters dialog box, as shown in the next figure.



Accumulators

Simulink recognizes the block diagram shown in the next figure as an accumulator. An accumulator construct — comprising a Constant block, a Sum block, and feedback through a Unit Delay block — is recognized anywhere across a block diagram, or within subsystems at lower levels.



An Accumulator Algorithm

With the **Block reduction** option enabled, Simulink creates a synthesized block, `Sum_synth_accum`. The synthesized block replaces the previous block diagram, resulting in a simple increment calculation.

```

static void accum_output(int_T tid)
{
    /* UnitDelay Block: '<Root>/Unit Delay'
     *   Operating as an accumulator
     */

    accum_DWork.UnitDelay_DSTATE++;
    accum_B.UnitDelay_j = accum_DWork.UnitDelay_DSTATE;

    /* Outport: '<Root>/Out1' */
    accum_Y.Out1 = accum_B.UnitDelay_j;
}

```

With **Block reduction** turned off, the generated code reflects the block diagram more literally, but less efficiently.

```

static void accum_output(int_T tid)
{
    /* UnitDelay: '<Root>/Unit Delay' */
    accum_B.UnitDelay_j = accum_DWork.UnitDelay_DSTATE;

    /* Sum: '<Root>/Sum' */
    accum_B.Sum_l = 1.0 + accum_B.UnitDelay_j;

    /* Outport: '<Root>/Out1' */
    accum_Y.Out1 = accum_B.Sum_l;
}

```

Removal of Redundant Type Conversions

Unnecessary type conversion blocks are removed. For example, an int type conversion block whose input and output are of type int is redundant and is removed.

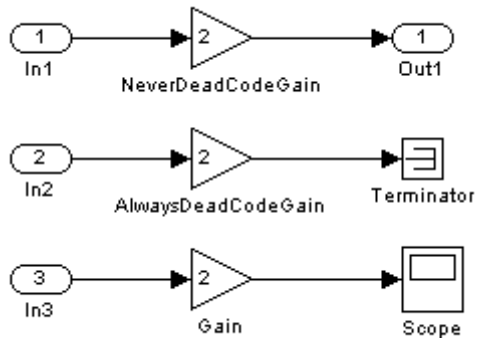
Dead Code Elimination

Any blocks or signals in an *unused code path* are eliminated from generated code. The following conditions need to be met for a block to be considered part of an unused code path:

- All signal paths for the block end with a block that does not execute. Examples of blocks that do not execute include Terminator blocks, disabled Assertion blocks, S-Function blocks configured for block reduction, and To Workspace blocks for which MAT-file logging is disabled for code generation.
- No signal paths for the block include global signal storage downstream from the block.

Tunable parameters do not prevent a block from being reduced by dead code elimination.

Consider the signal paths in the following block diagram.



If you check **Block reduction**, Real-Time Workshop responds to each signal path as follows:

For Signal Path...	Real-Time Workshop...
In1 to Out1	Always generates code because dead code elimination conditions are not met.
In2 to Terminator	Never generates code because dead code elimination conditions are met.
In3 to Scope	Generates code if MAT-file logging is enabled and eliminates code if MAT-file logging is disabled.

Fast-to-slow Rate Transition block in a single-tasking system

In a single-tasking system, if the **Block reduction** option is on, fast-to-slow Rate Transition blocks are optimized out of the model. The default case is shown (**Block reduction** on), so block B does not appear in the timing diagrams in this section.

Optimizing Code for Switch Blocks

You can optimize simulation and code generation for Switch and Multiport Switch blocks by enabling conditional input branch execution. By default, the Real-Time Workshop code generation parameters are configured to use the conditional input branch optimization.

When conditional input branch optimization is on, instead of executing all blocks driving the Switch block input ports at each time step, only the blocks required to compute the control input and the data input selected by the control input are executed.

Several considerations affect or limit Switch block optimization:

- Only blocks with -1 (inherited) or inf (Constant) sample time can participate in Switch block optimization.
- Blocks with outputs flagged as test points cannot participate.
- No multirate block can participate.
- Blocks with states cannot participate.

- Only S-functions with option `SS_OPTION_CAN_BE_CALLED_CONDITIONALLY` set can participate.

You control conditional input branch optimization by selecting and deselecting the **Conditional input branch execution** parameter on the **Optimization** pane of the Configuration Parameters dialog box.

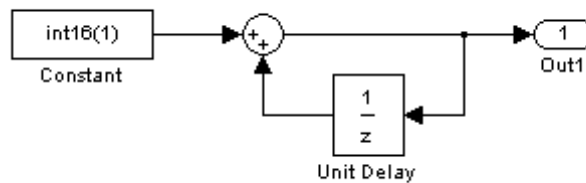
To run a conditional input branch optimization demo, click `rtwdemo_condinput` or type the following command at the MATLAB prompt.

```
rtwdemo_condinput
```

Optimizing Data Type Usage

In most processors, the use of integer data types can result in a significant reduction in data storage requirements, as well as a large increase in the speed of operation. You can achieve large performance gains on most processors by identifying those portions of your block diagram that are really integer calculations (such as accumulators), and implementing them with integer data types. Floating-point DSP targets are an obvious exception to this rule.

The accumulator from the previous example used 64-bit floating-point calculations by default. The block diagram in the next figure implements the accumulator with 16-bit integer operations.



Accumulator Implemented with 16-bit Integers

If the **Saturate on integer overflow** option of the Sum block is turned off, the code generated from the integer implementation looks the same as code generated from the floating-point block diagram. However, since `Sum_synth_accum` is performing integer arithmetic internally, the accumulator executes more efficiently.

By default, the **Saturate on integer overflow** option is on. This option generates extra error-checking code from the integer implementation, as shown in the following example.

```
static void accum_int16_output(int_T tid)
{
    /* local block i/o variables */

    int16_T rtb_UnitDelay_k;

    /* UnitDelay: '<Root>/Unit Delay' incorporates:
     * Constant: '<Root>/Constant'
     *
     * Regarding '<Root>/Unit Delay':
     * Operating as an accumulator
     */
    {
        int16_T tmpVar = accum_int16_DWork.UnitDelay_DSTATE;
        accum_int16_DWork.UnitDelay_DSTATE = tmpVar + (1);
        if ((tmpVar >= 0) && ((1) >= 0) &&
            (accum_int16_DWork.UnitDelay_DSTATE < 0))
        {
            accum_int16_DWork.UnitDelay_DSTATE = MAX_int16_T;
        } else if ((tmpVar < 0) && ((1) < 0) &&
            (accum_int16_DWork.UnitDelay_DSTATE >= 0)) {
            accum_int16_DWork.UnitDelay_DSTATE = MIN_int16_T;
        }
    }
    rtb_UnitDelay_k = accum_int16_DWork.UnitDelay_DSTATE;

    /* Output: '<Root>/Out1' */
    accum_int16_Y.Out1 = rtb_UnitDelay_k;
}

```

The floating-point implementation would not have generated the saturation error checks, which apply only to integers. When using integer data types, consider whether or not you need to generate saturation checking code.

If you are able to ignore saturation checks, turn **Saturate on integer overflow** off for the Sum block. The generated code then omits the preceding checks:

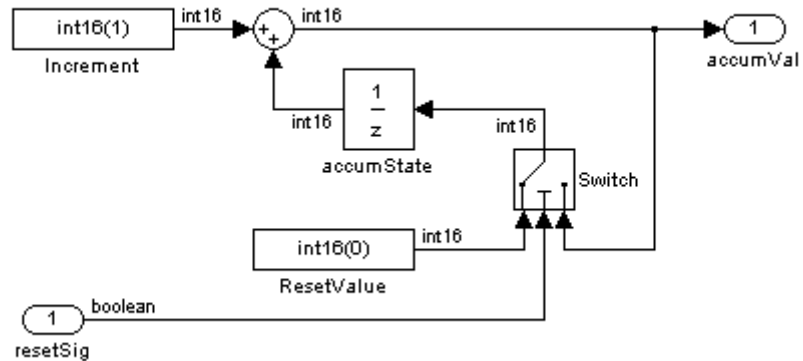
```
static void accum_int16_output(int_T tid)
{
    /* local block i/o variables */

    int16_T rtb_UnitDelay_k;

    /* UnitDelay: '<Root>/Unit Delay' incorporates:
     * Constant: '<Root>/Constant'
     *
     * Regarding '<Root>/Unit Delay':
     * Operating as an accumulator
     */
    accum_int16_DWork.UnitDelay_DSTATE++;
    rtb_UnitDelay_k = accum_int16_DWork.UnitDelay_DSTATE;

    /* Outport: '<Root>/Out1' */
    accum_int16_Y.Out1 = rtb_UnitDelay_k;
}
```

The next figure shows an efficient way to add a reset to an integer accumulator. When `resetSig` is greater than or equal to the threshold of the Switch block, the Switch block passes the reset value (0) back into the accumulator.



The reset signal can protect computations from overflows, and the size of the resultant code is minimal. The code uses no floating-point operations.

```
static void accum_rst_output(int_T tid)
{
    /* local block i/o variables */

    int16_T rtb_Sum_j;

    /* Sum: '<Root>/Sum' */
    rtb_Sum_j = (int16_T)(1 + accum_rst_DWork.accumState_DSTATE);

    /* Outport: '<Root>/accumVal' */
    accum_rst_Y.accumVal = rtb_Sum_j;

    /* Switch: '<Root>/Switch' */
    if(accum_rst_U.resetSig) {
        accum_rst_B.Switch_k = 0;
    } else {
        accum_rst_B.Switch_k = rtb_Sum_j;
    }
}
```

This example uses an input to the system as the reset value, but you can also use an int16 constant.

Note You should not use preprocessor compile-time mechanisms to redefine the Real-Time Workshop data types used in generated code. Redefining data type size or sign properties, using such mechanisms, can affect numerical results or cause runtime exceptions due to the data not matching properties expected by the generated code. Instead, use the Hardware Implementation pane of the Configuration Parameters dialog box to specify the appropriate word size for the model and specify the desired data types (double, single, int32, ...) for signals and parameters within the model.

Additional Integer and Fixed-Point Optimizations

You may find several companion products useful in optimizing the performance and size of integer-based generated code.

Generating Pure Integer Code with Real-Time Workshop Embedded Coder

The Real-Time Workshop Embedded Coder target provides the **Support floating-point numbers** option (the inverse of an obsolete option named **Integer code only**) to control whether generated code contains any floating-point data or operations. When this option is deselected, an error is raised if any noninteger data or expressions are encountered during compilation of the model. The error message reports the offending blocks and parameters.

If pure integer code generation is important to your design, you should consider using the Real-Time Workshop Embedded Coder target (or a target of your own, based on the Real-Time Workshop Embedded Coder target).

The Real-Time Workshop Embedded Coder target offers many additional optimizations. See the Real-Time Workshop Embedded Coder documentation for more information.

Optimizing Integer Code with Simulink Fixed Point and Stateflow

Simulink (a separate product) is designed to deliver the highest levels of performance for noninteger algorithms on processors lacking floating-point hardware. Simulink code generation in Real-Time Workshop implements

calculations using a processor's integer operations. The code generation strategy maps the integer value set to a range of expected real-world values to achieve the high efficiency.

Finite-state machine or flowchart constructs can often represent decision logic (or mode logic) efficiently. Stateflow (a separate product) provides these capabilities. Stateflow, which is fully integrated into Simulink, supports integer data-typed code generation.

Optimizing Signals

In this section...

“Implementing Logic Signals as Boolean Data” on page 9-40

“Reducing Memory Requirements for Signals” on page 9-40

“Declaring Signals as Local Function Data” on page 9-41

“Reusing Memory Allocated for Signals” on page 9-41

“Inlining Invariant Signals” on page 9-41

Implementing Logic Signals as Boolean Data

By default, Simulink does not signal an error when it detects that double signals are connected to blocks that prefer Boolean input. This ensures compatibility with models created by earlier versions of Simulink that support only double data types. You can enable strict Boolean type checking by selecting the **Implement logic signals as boolean data (versus double)** check box.

Selecting this check box is recommended. Generated code requires less memory because a Boolean signal typically requires one byte of storage while a double signal requires eight bytes of storage.

Reducing Memory Requirements for Signals

To instruct Real-Time Workshop to reuse signal memory, which can reduce memory requirements of your real-time program, select the configuration parameter **Signal storage reuse**. Disabling **Signal storage reuse** makes all block outputs global and unique, which in many cases significantly increases RAM and ROM usage.

For more details on the **Signal storage reuse** option, see “Signal Storage, Optimization, and Interfacing” on page 5-31.

Note Selecting **Signal storage reuse** also enables the **Enable local block outputs** option and the **Reuse block outputs** option in the **Code generation Signals** section of the **Optimization** pane. See “Declaring Signals as Local Function Data” on page 9-41 and “Reusing Memory Allocated for Signals” on page 9-41.

Declaring Signals as Local Function Data

To declare block signals locally in functions instead of being declared globally (when possible), select the **Enable local block outputs** configuration parameter . This parameter is available only when you select **Signal storage reuse**.

For more information on the use of the **Enable local block outputs** option, see “Signal Storage, Optimization, and Interfacing” on page 5-31. Also see “First Look at Generated Code” in Getting Started.

Reusing Memory Allocated for Signals

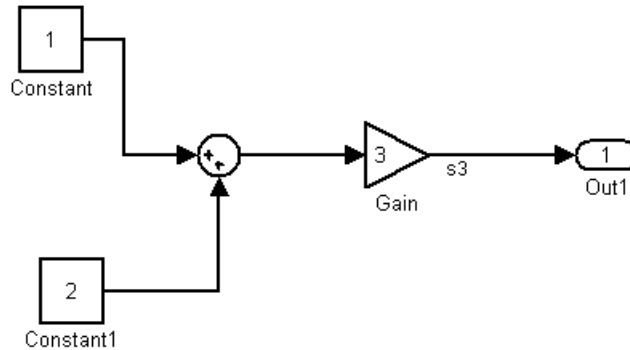
To reuse memory allocated for signals, select the configuration parameter **Reuse block output**. Real-Time Workshop reuses signal memory whenever possible. When **Reuse block output** is cleared, signals are stored in unique locations.

Reuse block output is available only when you select **Signal storage reuse**.

See “Signal Storage, Optimization, and Interfacing” on page 5-31 for more information (including generated code example) on **Reuse block output** and other signal storage options.

Inlining Invariant Signals

An invariant signal is a block output signal that does not change during Simulink simulation. For example, the signal S3 in this block diagram is an invariant signal.



For the previous model, if you select **Inline invariant signals** on the **Optimization** pane, Real-Time Workshop inlines the invariant signal S3 in the generated code.

Note that an *invariant signal* is not the same as an *invariant constant*. (See “Optimization Pane” in the Simulink documentation for information on invariant constants.) In the preceding example, the two constants (1 and 2) and the gain value of 3 are invariant constants. To inline these invariant constants, select **Inline parameters**.

The **Ignore integer downcasts in folded expressions** option performs downcasts in expressions.

Note If your model contains Model blocks, **Inline parameters** must be *on* for all referenced models. If a referenced model does not have **Inline Parameters** set to *on*, Simulink temporarily enables this option while generating code for the referenced model, then turns it off again when the build completes. Thus the referenced model is left in its previous state and need not be resaved. For the top-level model, **Inline parameters** can be either *on* or *off*.

Inlining Parameters

When you select the **Inline parameters** configuration parameter:

- Real-Time Workshop uses the numerical values of model parameters, instead of their symbolic names, in generated code.

If the value of a parameter is a workspace variable, or an expression including one or more workspace variables, the variable or expression is evaluated at code generation time. The hard-coded result value appears in the generated code. An inlined parameter, because it has in effect been transformed into a constant, is no longer tunable. That is, it is not visible to externally written code, and its value cannot be changed at run-time.

- The **Configure** button becomes enabled. Clicking the **Configure** button opens the Model Parameter Configuration dialog box.

The Model Parameter Configuration dialog box lets you remove individual parameters from inlining and declare them to be tunable variables (or global constants). When you declare a parameter tunable, Real-Time Workshop generates a storage declaration that allows the parameter to be interfaced to externally written code. This enables your hand-written code to change the value of the parameter at run-time.

The Model Parameter Configuration dialog box lets you improve overall efficiency by inlining most parameters, while at the same time retaining the flexibility of run-time tuning for selected parameters.

See “Parameter Storage, Interfacing, and Tuning” on page 5-2 for more information on interfacing parameters to externally written code.

Inline parameters also instructs Simulink to propagate constant sample times. Simulink computes the output signals of blocks that have constant sample times once during model startup. This improves performance because such blocks do not compute their outputs at every time step of the model.

You can select the **Inline invariant signals** code generation option (which also places constant values in generated code) only when **Inline parameters** is *on*. See “Inlining Invariant Signals” on page 9-41.

Referenced Models

When a top-level model uses referenced models,

- All referenced models must specify **Inline parameters** to be *on*
- The top-level model can specify **Inline parameters** to be *on* or *off*.

When the top-level model specifies **Inline parameters** to be *on*, you cannot use the Model Parameter Configuration dialog box to tune parameters that are passed to referenced models. To tune such parameters, you must declare them in the referenced model's workspace, and then pass run-time values (or expressions) for them in argument lists specified for each Model block that references that model. See "Using Model Arguments" for details.

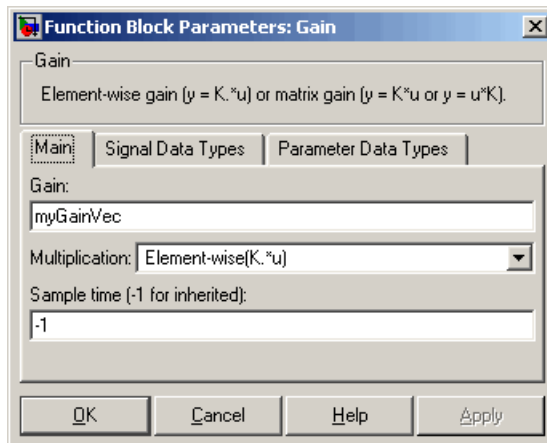
Configuring a Loop Unrolling Threshold

The **Loop unrolling threshold** parameter on the **Optimization** pane determines when a wide signal or parameter should be wrapped into a for loop and when it should be generated as a separate statement for each element of the signal. The default threshold value is 5.

For example, consider the model below:



The gain parameter of the Gain block is the vector myGainVec.



Assume that the loop unrolling threshold value is set to the default, 5.

If myGainVec is declared as

```
myGainVec = [1:10];
```

an array of 10 elements, `myGainVec_P.Gain_Gain[]`, is declared within the `Parameters_model` data structure. The size of the gain array exceeds the loop unrolling threshold. Therefore, the code generated for the Gain block iterates over the array in a for loop, as shown in the following code:

```
{
    int32_T i1;

    /* Gain: '<Root>/Gain' */
    for(i1=0; i1<10; i1++) {
        myGainVec_B.Gain_f[i1] = rtb_foo *
            myGainVec_P.Gain_Gain[i1];
    }
}
```

If `myGainVec` is declared as

```
myGainVec = [1:3];
```

an array of three elements, `myGainVec_P.Gain_Gain[]`, is declared within the `Parameters` data structure. The size of the gain array is below the loop unrolling threshold. The generated code consists of inline references to each element of the array, as in the code below.

```
/* Gain: '<Root>/Gain' */
myGainVec_B.Gain_f[0] = rtb_foo * myGainVec_P.Gain_Gain[0];
myGainVec_B.Gain_f[1] = rtb_foo * myGainVec_P.Gain_Gain[1];
myGainVec_B.Gain_f[2] = rtb_foo * myGainVec_P.Gain_Gain[2];
```

See the Target Language Compiler documentation for more information on loop rolling.

Note When a model includes Stateflow charts or Embedded MATLAB Function blocks, a set of Stateflow optimizations appears on the **Optimization** pane. The settings you make for the Stateflow options also apply to all Embedded MATLAB Function blocks in the model. This is because the Embedded MATLAB Function blocks and Stateflow are built on top of the same technology and share a code base. You do not need a Stateflow license to use Embedded MATLAB Function blocks.

Controlling Memory Allocation for Time Counters

The **Application lifespan (days)** parameter lets you control the allocation of memory for absolute and elapsed time counters. Such counters exist in the code for blocks that use absolute or elapsed time. For a list of such blocks, see Appendix A, “Blocks That Depend on Absolute Time”.

The size of the time counters in generated code is 8, 16, 32, or 64 bits. The size is set automatically to the minimum that can accommodate the duration value specified by **Application lifespan (days)** given the step size specified in the Configuration Parameters **Solver** pane. To minimize the amount of RAM used by time counters, specify a lifespan no longer than necessary, and a step size no smaller than necessary.

An application is guaranteed to be able to run to its specified lifespan. It may be able to run longer, but is not guaranteed to do so. For example, running a model with a step size of one millisecond (0.001 seconds) for one day requires a 32-bit timer, which could continue running without overflow for 49 days more.

To maximize application lifespan, specify **Application lifespan (days)** as `inf`. This value allocates 64 bits (two `uint32` words) for each timer. Using 64 bits to store timing data would allow a model with a step size of 0.001 microsecond (10E-09 seconds) to run for more than 500 years, which would rarely be required. 64-bit counters do not violate the usual Real-Time Workshop length limitation of 32 bits because the value of a time counter never provides the value of a signal, state, or parameter.

For information about the allocation and operation of absolute and elapsed time counters, see Chapter 15, “Timing Services”. For information about asynchronous timing, see “Using Timers in Asynchronous Tasks” on page 16-27. For information about the effect of the **Application lifespan (days)** parameter on simulation, see “Application lifespan (days)” in the Simulink documentation.

Optimizing Code Resulting from Floating-Point to Integer Conversions

The **Remove code from floating-point to integer conversions that wraps out-of-range values** option in the **Integer and fixed-point** section of the **Optimization** pane causes Real-Time Workshop to remove code that ensures that execution of the generated code produces the same results as simulation when out-of-range conversions occur. This reduces the size and increases the speed of the generated code at the cost of potentially producing results that do not match simulation in the case of out-of-range values.

Note Enabling this option affects code generation results only for out-of-range values and cannot cause code generation results to differ from simulation results for in-range values.

Consider selecting this option if code efficiency is critical to your application and the following conditions are true for at least one block in the model:

- Computing the block's outputs or parameters involves converting floating-point data to integer or fixed-point data.
- The block's **Saturate on integer overflow** option is disabled.

The following code shows the code generated for a conversion with the **Remove code from floating-point to integer conversions that wraps out-of-range values** option disabled:

```
_fixptlowering0 = (rtb_Switch[i1] + 9.0) / 0.09375;
_fixptlowering1 = fmod(_fixptlowering0 >= 0.0 ? floor(_fixptlowering0) :
    ceil(_fixptlowering0), 4.2949672960000000E+009);
if(_fixptlowering1 < -2.1474836480000000E+009) {
    _fixptlowering1 += 4.2949672960000000E+009;
} else if(_fixptlowering1 >= 2.1474836480000000E+009) {
    _fixptlowering1 -= 4.2949672960000000E+009;
}
cg_in_0_20_0[i1] = (int32_T)_fixptlowering1;
```


The code generator applies the `fmod` function to handle out-of-range conversion results.

The code generated when you select the optimization option follows:

```
cg_in_0_20_0[i1] = (int32_T)((rtb_Switch[i1] + 9.0) / 0.09375);
```

Optimization Dependencies

Several parameters available on the **Optimization** pane have dependencies on settings of other options. The following table summarizes the dependencies.

Option	Dependencies?	Dependency Details
Block reduction	No	
Conditional input branch execution	No	
Implement logic signals as boolean data (versus double)	Yes	Disable for models created with a version of Simulink that supports only signals of type double
Signal storage reuse	No	
Inline parameters	Yes	Disable for referenced models in a model reference hierarchy
Application lifespan (days)	No	
Parameter structure (ERT targets only)	Yes	Enabled by Inline parameters
Enable local block outputs	Yes	Enabled by Signal storage reuse
Reuse block outputs	Yes	Enabled by Signal storage reuse
Ignore integer downcasts in folded expressions	No	
Inline invariant signals	Yes	Enabled by Inline parameters
Eliminate superfluous temporary variables (Expression folding)	Yes	Enabled by Signal storage reuse
Loop unrolling threshold	No	
Remove root level I/O zero initialization (ERT targets only)	No	
Use memset to initialize floats and doubles to 0.0 (ERT targets only)	No	

Option	Dependencies?	Dependency Details
Remove internal state zero initialization (ERT targets only)	No	
Optimize initialization code for model reference (ERT targets only)	Yes	Disable if model includes an enabled subsystem <i>and</i> the model is referred to from another model with a Model block
Remove code from floating-point to integer conversions that wrap out-of-range values	No	
Remove code that protects against division arithmetic exceptions (ERT targets only)	No	

Writing S-Functions for Real-Time Workshop Code Generation

Introduction (p. 10-3)	Describes various approaches to writing S-functions for Real-Time Workshop code generation
Writing Noninlined S-Functions (p. 10-9)	Explains the noninlined approach to writing S-functions for code generation
Writing Wrapper S-Functions (p. 10-11)	Explains how to create S-functions that serve as wrappers for existing code
Writing Fully Inlined S-Functions (p. 10-22)	Explains the inlined approach to writing S-functions for the Real-Time Workshop code generator
Using the Legacy Code Tool to Automate the Generation of Files for Fully Inlined S-Functions (p. 10-24)	Explains how to use the Legacy Code Tool to automatically generate fully inlined S-functions and other necessary files to generate code for models that use such S-functions
Writing Fully Inlined S-Functions with the mdlRTW Routine (p. 10-27)	Explains how to use the mdlrtw callback method in an inlined S-function

Writing S-Functions That Support Expression Folding (p. 10-53)

Explains how to realize the efficiencies offered by expression folding at input and output ports in inlined S-functions

Writing S-Functions That Specify Sample Time Inheritance Rules (p. 10-69)

Explains how to write S-functions that use sample time

Writing S-Functions That Support Code Reuse (p. 10-71)

Explains how to create S-functions that are compatible with the Real-Time Workshop subsystem code reuse feature

Writing S-Functions for Multirate Multitasking Environments (p. 10-72)

Explains how to handle rate-grouped tasks in multirate, port-based sample time S-functions

Integrating C and C++ Code (p. 10-80)

Explains options for integrating S-functions written in C with generated C++ code or S-functions written in C++ with generated C code

Build Support for S-Functions (p. 10-81)

Discusses options for adding S-functions to the Real-Time Workshop build process

Introduction

In this section...
“About S-Functions” on page 10-3
“Additional Information” on page 10-4
“Classes of Problems Solved by S-Functions” on page 10-4
“Types of S-Functions” on page 10-5
“Basic Files Required for Implementation” on page 10-7

About S-Functions

This chapter describes how to create S-functions that work seamlessly with Real-Time Workshop code generation. It begins with basic concepts and concludes with an example of how to create a highly optimized direct-index lookup table S-Function block.

This chapter assumes that you understand these concepts:

- Level 2 S-functions
- Target Language Compiler (TLC) scripting
- How the Real-Time Workshop software generates and builds C/C++ code

Note When this chapter refers to actions performed by the Target Language Compiler, including parsing, caching, creating buffers, and so on, the name Target Language Compiler is spelled out fully. When referring to code written in the Target Language Compiler syntax, this chapter uses the abbreviation TLC.

Note The guidelines presented in this chapter are for Real-Time Workshop users. Even if you do not currently use the Real-Time Workshop code generator, you should follow the practices presented in this chapter when writing S-functions, especially if you are creating general-purpose S-functions.

Additional Information

See the Target Language Compiler documentation and other Real-Time Workshop documentation for more information on the code generation process.

See “Inlining S-Functions” in the Target Language Compiler documentation for additional information on inlining S-functions.

Classes of Problems Solved by S-Functions

S-functions help solve various kinds of problems you might face when working with the Simulink and Real-Time Workshop products. These problems include

- Extending the set of algorithms (blocks) provided by the Simulink and Real-Time Workshop products
- Interfacing legacy (hand-written) code with the Simulink and Real-Time Workshop products
- Interfacing to hardware through device driver S-functions
- Generating highly optimized code for embedded systems
- Verifying code generated for a subsystem as part of a Simulink simulation

S-functions are written using an application program interface (API) that allows you to implement generic algorithms in the Simulink environment with a great deal of flexibility. This flexibility cannot always be maintained when you use S-functions with the Real-Time Workshop code generator. For example, it is not possible to access the MATLAB workspace from an S-function that is used with the code generator. However, using the techniques presented in this chapter, you can create S-functions for most applications that work with the Real-Time Workshop generated code.

Although S-functions provide a generic and flexible solution for implementing complex algorithms in Simulink, the underlying API incurs overhead in terms of memory and computation resources. Most often the additional resources are acceptable for real-time rapid prototyping systems. In many cases, though, additional resources are unavailable in real-time embedded applications. You can minimize memory and computational requirements by using the Target Language Compiler technology provided with the Real-Time Workshop product to inline your S-functions. If you are producing an S-function for existing code, consider using the Simulink Legacy Code Tool.

Types of S-Functions

The implementation of S-functions changes based on your requirements. This chapter discusses the typical problems that you may face and how to create S-functions for applications that need to work with the Simulink and Real-Time Workshop products. These are some (informally defined) common situations:

- 1 “I’m not concerned with efficiency. I just want to write one version of my algorithm and have it work in the Simulink and Real-Time Workshop products automatically.”
- 2 “I have a lot of hand-written code that I need to interface. I want to call my function from the Simulink and Real-Time Workshop products in an efficient manner.”

or said another way:

“I want to create a block for my blockset that will be distributed throughout my organization. I’d like it to be very maintainable with efficient code. I’d like my algorithm to exist in one place but work with both the Simulink and Real-Time Workshop products.”

- 3 “I want to implement a highly optimized algorithm in the Simulink and Real-Time Workshop products that looks like a built-in block and generates very efficient code.”

The MathWorks has adopted terminology for these different requirements. Respectively, the situations described above map to this terminology:

- 1 Noninlined S-function
- 2 Wrapper S-function
- 3 Fully inlined S-function

Noninlined S-Functions

A noninlined S-function is a C or C++ MEX S-function that is treated identically by Simulink and Real-Time Workshop. In general, you implement your algorithm once according to the S-function API. Simulink and Real-Time

Workshop call the S-function routines (for example, mdlOutputs) at the appropriate points during model execution.

Additional memory and computation resources are required for each instance of a noninlined S-Function block. However, this routine of incorporating algorithms into Simulink and Real-Time Workshop is typical during the prototyping phase of a project where efficiency is not important. The advantage gained by forgoing efficiency is the ability to change model parameters and structures rapidly.

Writing a noninlined S-function does not involve any TLC coding. Noninlined S-functions are the default case for the Real-Time Workshop build process in the sense that once you build a MEX S-function in your model, there is no additional preparation prior to clicking **Build** in the **Real-Time Workshop** pane of the Configuration Parameters dialog box for your model.

Some restrictions exist concerning the names and locations of noninlined S-function files when generating makefiles. See “Writing Noninlined S-Functions” on page 10-9.

Wrapper S-Functions

A wrapper S-function is ideal for interfacing hand-written code or a large algorithm that is encapsulated within a few procedures. In this situation, usually the procedures reside in modules that are separate from the MEX S-function. The S-function module typically contains a few calls to your procedures. Because the S-function module does not contain any parts of your algorithm, but only calls your code, it is referred to as a *wrapper S-function*.

In addition to the MEX S-function wrapper, you need to create a TLC wrapper that complements your S-function. The TLC wrapper is similar to the S-function wrapper in that it contains calls to your algorithm.

Fully Inlined S-Functions

For S-functions to work correctly in the Simulink environment, a certain amount of overhead code is necessary. When the Real-Time Workshop software generates code from models that contain S-functions (without *sfunction.tlc* files), it embeds some of this overhead code in the generated code. If you want to optimize your real-time code and eliminate some of the

overhead code, you must *inline* (or embed) your S-functions. This involves writing a TLC (*sfunction.tlc*) file that eliminates all overhead code from the generated code. The Target Language Compiler processes *sfunction.tlc* files to define how to inline your S-function algorithm in the generated code.

Note The term *inline* should not be confused with the C++ *inline* keyword. In MathWorks terminology, inline means to specify a text string in place of the call to the general S-function API routines (for example, `mdlOutputs`). For example, when a TLC file is used to inline an S-function, the generated code contains the appropriate C/ C++ code that would normally appear within the S-function routines and the S-function itself has been removed from the build process.

A fully inlined S-function builds your algorithm (block) into Simulink and Real-Time Workshop in a manner that is indistinguishable from a built-in block. Typically, a fully inlined S-function requires you to implement your algorithm twice: once for Simulink (C/C++ MEX S-function) and once for Real-Time Workshop (TLC file). The complexity of the TLC file depends on the complexity of your algorithm and the level of efficiency you're trying to achieve in the generated code. TLC files vary from simple to complex in structure.

The Simulink Legacy Code Tool can automate the generation of a fully inlined S-function and a corresponding TLC file based on information that you register in a Legacy Code Tool data structure. For more information, see “Integrating Existing C Functions into Simulink® Models with the Legacy Code Tool” in the Simulink Writing S-Functions documentation and “Using the Legacy Code Tool to Automate the Generation of Files for Fully Inlined S-Functions” on page 10-24.

Basic Files Required for Implementation

This section briefly describes what files and functions you need to create noninlined, wrapper, and fully inlined S-functions.

- Noninlined S-functions require the C or C++ MEX S-function source code (*sfunction.c* or *sfunction.cpp*).

- Wrapper S-functions that inline a call to your algorithm (your C/C++ function) require an *sfunction.tlc* file.
- Fully inlined S-functions also require an *sfunction.tlc* file. Fully inlined S-functions produce the optimal code for a parameterized S-function. This is an S-function that operates in a specific mode dependent upon fixed S-function parameters that do not change during model execution. For a given operating mode, the *sfunction.tlc* file specifies the exact code that is generated to implement the algorithm for that mode. For example, the direct-index lookup table S-function at the end of this chapter contains two operating modes — one for evenly spaced *x*-data and one for unevenly spaced *x*-data.

Fully inlined S-functions might require the placement of the `mdlRTW` routine in your S-function MEX-file *sfunction.c* or *sfunction.cpp*. The `mdlRTW` routine lets you place information in *model.rtw*, the record file that specifies a model, and which Real-Time Workshop invokes the Target Language Compiler to process prior to executing *sfunction.tlc* when generating code.

Including a `mdlRTW` routine is useful when you want to introduce nontunable parameters into your TLC file. Such parameters are generally used to determine which operating mode is active in a given instance of the S-function. Based on this information, the TLC file for the S-function can generate highly efficient, optimal code for that operating mode.

Writing Noninlined S-Functions

In this section...

“About Noninlined S-Functions” on page 10-9

“Noninlined S-Function Parameter Type Limitations” on page 10-9

About Noninlined S-Functions

Noninlined S-functions are identified by the *absence* of an `sfunction.tlc` file for your S-function. The filename varies depending on your platform. For example, on a 32-bit Windows system, the file name would be `sfunction.mexw32.`. Type `mexext` in the MATLAB Command Window to see which extension your system uses.

When you place a noninlined S-function in a model, the code generator supports only the following MATLAB API functions:

- `mxGetEps`
- `mxGetInf`
- `mxGetM`
- `mxGetN`
- `mxGetNaN`
- `mxGetPr`
- `mxGetScalar`
- `mxGetString`
- `mxIsEmpty`
- `mxIsFinite`
- `mxIsInf`

Noninlined S-Function Parameter Type Limitations

Parameters to noninlined S-functions can be of the following types only:

- Double precision

- Characters in scalars, vectors, or 2-D matrices

For more flexibility in the type of parameters you can supply to S-functions or the operations in the S-function, inline your S-function and consider using an mdlRTW S-function routine.

Use of other functions from the MATLAB `matrix.h` API or other MATLAB APIs, such as `mex.h` and `mat.h`, is not supported. If you call unsupported APIs from an S-function source file, compiler errors occur. See the file `matlabroot/rtw/c/src/rt_matrix.h(.c)` for details on supported MATLAB API functions.

If you use `mxGetPr` on an empty matrix, the function does not return `NULL`; rather, it returns a random value. Therefore, you should protect calls to `mxGetPr` with `mxIsEmpty`.

Writing Wrapper S-Functions

In this section...

“About Wrapper S-Functions” on page 10-11

“MEX S-Function Wrapper” on page 10-11

“TLC S-Function Wrapper” on page 10-16

“The Inlined Code” on page 10-21

About Wrapper S-Functions

This section describes how to create S-functions that work seamlessly with Simulink and Real-Time Workshop using the *wrapper* concept. This section begins by describing how to interface your algorithms in Simulink by writing MEX S-function wrappers (*sfunction.mex*). It finishes with a description of how to direct the code generator to insert your algorithm into the generated code by creating a TLC S-function wrapper (*sfunction.tlc*).

MEX S-Function Wrapper

Creating S-functions using an S-function wrapper allows you to insert C/C++ code algorithms in Simulink and Real-Time Workshop with little or no change to your original C/C++ function. A *MEX S-function wrapper* is an S-function that calls code that resides in another module. In effect, the wrapper binds your code to Simulink. A *TLC S-function wrapper* is a TLC file that specifies how the code generator should call your code (the same code that was called from the C-MEX S-function wrapper).

Note A MEX S-function wrapper must only be used in the version of MATLAB in which the wrapper is created.

Suppose you have an algorithm (that is, a C function) called `my_alg` that resides in the file `my_alg.c`. You can integrate `my_alg` into Simulink by creating a MEX S-function wrapper (for example, `wrapsfcn.c`). Once this is done, Simulink can call `my_alg` from an S-Function block. However, the Simulink S-function contains a set of empty functions that Simulink

requires for various API-related purposes. For example, although only `mdlOutputs` calls `my_alg`, Simulink calls `mdlTerminate` as well, even though this S-function routine performs no action.

You can integrate `my_alg` into generated code (that is, embed the call to `my_alg` in the generated code) by creating a TLC S-function wrapper (for example, `wrapsfcn.tlc`). The advantage of creating a TLC S-function wrapper is that the empty function calls can be eliminated and the overhead of executing the `mdlOutputs` function and then the `my_alg` function can be eliminated.

Wrapper S-functions are useful when you are creating new algorithms that are procedural in nature or when you are integrating legacy code into Simulink. However, if you want to create code that is

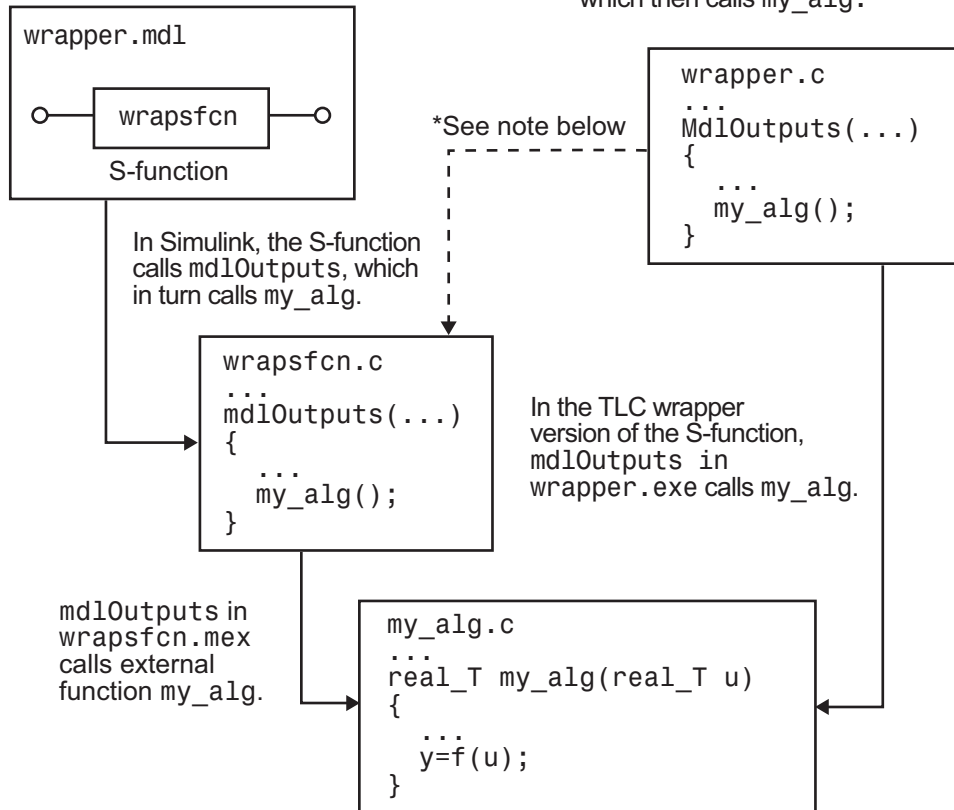
- Interpretive in nature in Simulink (that is, highly parameterized by operating modes)
- Heavily optimized (that is, no extra tests to decide what mode the code is operating in)

then you must create a *fully inlined TLC file* for your S-function.

The next figure shows the wrapper S-function concept.

Simulink

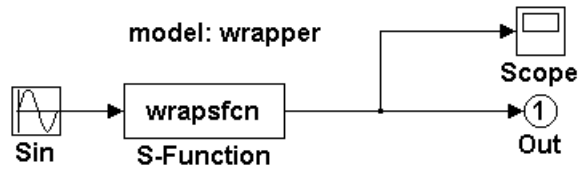
Place the name of your s-function in the S-Function block's dialog box.



*The dotted line is the path taken if the S-function does not have a TLC wrapper file. If there is no TLC wrapper file, the generated code calls mdlOutputs.

Using an S-function wrapper to import algorithms in your Simulink model means that the S-function serves as an interface that calls your C/C++ algorithms from mdlOutputs. S-function wrappers have the advantage that you can quickly integrate large standalone C/C++ programs into your model without having to make changes to the code.

The following sample model includes an S-function wrapper.



There are two files associated with the `wrapsfcn` block, the S-function wrapper and the C/C++ code that contains the algorithm. The S-function wrapper code for `wrapsfcn.c` appears below. The first three statements do the following:

- 1** Defines the name of the S-function (what you enter in the Simulink S-function block dialog).
- 2** Specifies that the S-function is using the level 2 format.
- 3** Provides access to the `SimStruct` data structure, which contains pointers to data used during simulation and code generation and defines macros that store data in and retrieve data from the `SimStruct`.

For more information, see “Templates for C S-Functions” in the Simulink documentation.

```
#define S_FUNCTION_NAME wrapsfcn
#define S_FUNCTION_LEVEL 2
#include "simstruc.h"

extern real_T my_alg(real_T u); /* Declare my_alg as extern */

/*
 * mdlInitializeSizes - initialize the sizes array
 */
static void mdlInitializeSizes(SimStruct *S)
{

    ssSetNumSFcnParams( S, 0); /*number of input arguments*/

    if (!ssSetNumInputPorts(S, 1)) return;
    ssSetInputPortWidth(S, 0, 1);
```

```

        ssSetInputPortDirectFeedThrough(S, 0, 1);

        if (!ssSetNumOutputPorts(S,1)) return;
        ssSetOutputPortWidth(S, 0, 1);

        ssSetNumSampleTimes( S, 1);
    }

    /*
    * mdlInitializeSampleTimes - indicate that this S-function runs
    * at the rate of the source (driving block)
    */
    static void mdlInitializeSampleTimes(SimStruct *S)
    {
        ssSetSampleTime(S, 0, INHERITED_SAMPLE_TIME);
        ssSetOffsetTime(S, 0, 0.0);
    }

    /*
    * mdlOutputs - compute the outputs by calling my_alg, which
    * resides in another module, my_alg.c
    */
    static void mdlOutputs(SimStruct *S, int_T tid)
    {
        InputRealPtrsType uPtrs = ssGetInputPortRealSignalPtrs(S,0);
        real_T          *y      = ssGetOutputPortRealSignal(S,0);
        *y = my_alg(*uPtrs[0]); /* Call my_alg in mdlOutputs */
    }

    /*
    * mdlTerminate - called when the simulation is terminated.
    */
    static void mdlTerminate(SimStruct *S)
    {
    }

#ifdef MATLAB_MEX_FILE /* Is this file being compiled as a MEX-file? */
#include "simulink.c" /* MEX-file interface mechanism */
#else
#include "cg_sfun.h" /* Code generation registration function */
#endif

```

```
#endif
```

The S-function routine `mdlOutputs` contains a function call to `my_alg`, which is the C function containing the algorithm that the S-function performs. This is the code for `my_alg.c`:

```
#ifdef MATLAB_MEX_FILE
#include "tmwtypes.h"
#else
#include "rtwtypes.h"
#endif
real_T my_alg(real_T u)
{
    return(u * 2.0);
}
```

See the section “Header Dependencies When Interfacing Legacy/Custom Code with Generated Code” on page 2-85 in the Real-Time Workshop documentation for more information.

The wrapper S-function `wrapsfcn` calls `my_alg`, which computes `u * 2.0`. To build `wrapsfcn.mex`, use the following command:

```
mex wrapsfcn.c my_alg.c
```

TLC S-Function Wrapper

This section describes how to inline the call to `my_alg` in the `mdlOutputs` section of the generated code. In the above example, the call to `my_alg` is embedded in the `mdlOutputs` section as

```
*y = my_alg(*uPtrs[0]);
```

When you are creating a TLC S-function wrapper, the goal is to embed the same type of call in the generated code.

It is instructive to look at how the code generator executes S-functions that are not inlined. A noninlined S-function is identified by the absence of the file `sfunction.tlc` and the existence of `sfunction.mex`. When generating code for a noninlined S-function, Real-Time Workshop generates a call to

mdlOutputs through a function pointer that, in this example, then calls `my_alg`.

The wrapper example contains one S-function, `wrapsfcn.mex`. You must compile and link an additional module, `my_alg`, with the generated code. To do this, specify

```
set_param('wrapper/S-Function','SFunctionModules','my_alg')
```

Code Overhead for Noninlined S-Functions

The code generated when using `grt.tlc` as the system target file *without* `wrapsfcn.tlc` is

```
<Generated code comments for wrapper model with noninlined wrapsfcn S-function>
```

```
#include <math.h>
#include <string.h>
#include "wrapper.h"
#include "wrapper.prm"

/* Start the model */
void mdlStart(void)
{
    /* (no start code required) */
}

/* Compute block outputs */
void mdlOutputs(int_T tid)
{
    /* Sin Block: <Root>/Sin */
    rtB.Sin = rtP.Sin.Amplitude *
        sin(rtP.Sin.Frequency * ssGetT(rtS) + rtP.Sin.Phase);

    /* Level2 S-Function Block: <Root>/S-Function (wrapsfcn) */
    {
        /* Noninlined S-functions create a SimStruct object and
        * generate a call to S-function routine mdlOutputs
        */
        SimStruct *rts = ssGetSFunction(rtS, 0);
```

```
        sfcnOutputs(rts, tid);
    }

    /* Output Block: <Root>/Out */
    rtY.Out = rtB.S_Function;
}

/* Perform model update */
void mdlUpdate(int_T tid)
{
    /* (no update code required) */
}

/* Terminate function */
void mdlTerminate(void)
{
    /* Level2 S-Function Block: <Root>/S-Function (wrapsfcn) */
    {
        /* Noninlined S-functions require a SimStruct object and
         * the call to S-function routine mdlTerminate
         */
        SimStruct *rts = ssGetSFunction(rts, 0);
        sfcnTerminate(rts);
    }
}

#include "wrapper.reg"

/* [EOF] wrapper.c */
```

In addition to the overhead outlined above, the `wrapper.reg` generated file contains the initialization of the `SimStruct` for the wrapper S-Function block. There is one child `SimStruct` for each S-Function block in your model. You can significantly reduce this overhead by creating a TLC wrapper for the S-function.

How to Inline

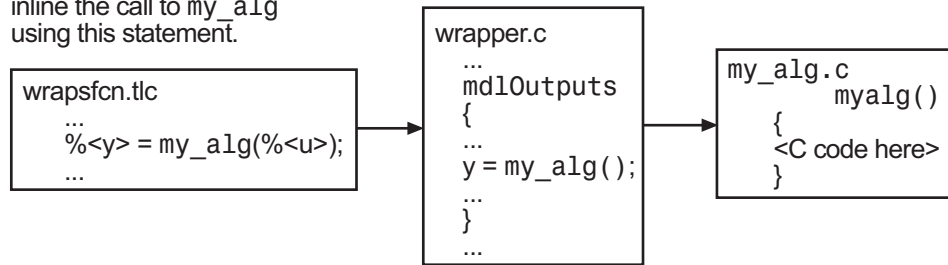
The generated code makes the call to your S-function, `wrapsfcn.c`, in `mdlOutputs` by using this code:

```
SimStruct *rts = ssGetSFunction(rts, 0);
sfcnOutputs(rts, tid);
```

This call has computational overhead associated with it. First, Simulink creates a `SimStruct` data structure for the S-Function block. Second, the code generator constructs a call through a function pointer to execute `mdlOutputs`, then `mdlOutputs` calls `my_alg`. By inlining the call to your C/C++ algorithm, `my_alg`, you can eliminate both the `SimStruct` and the extra function call, thereby improving the efficiency and reducing the size of the generated code.

Inlining a wrapper S-function requires an `sfunction.tlc` file for the S-function (see the Target Language Compiler documentation for details). The TLC file must contain the function call to `my_alg`. The following figure shows the relationships between the algorithm, the wrapper S-function, and the `sfunction.tlc` file.

The `wrapsfcn.tlc` file tells Real-Time Workshop how to inline the call to `my_alg` using this statement.



To inline this call, you have to place your function call in an `sfunction.tlc` file with the same name as the S-function (in this example, `wrapsfcn.tlc`). This causes the Target Language Compiler to override the default method of placing calls to your S-function in the generated code.

This is the `wrapsfcn.tlc` file that inlines `wrapsfcn.c`.

```
%% File      : wrapsfcn.tlc
%% Abstract:
%%      Example inlined tlc file for S-function wrapsfcn.c
%%
```

```

%implements "wrapsfcn" "C"

%% Function: BlockTypeSetup =====
%% Abstract:
%%      Create function prototype in model.h as:
%%      "extern real_T my_alg(real_T u);"
%%
%function BlockTypeSetup(block, system) void
    %openfile buffer
        extern real_T my_alg(real_T u); /* This line is placed in wrapper.h */
    %closefile buffer
    %<LibCacheFunctionPrototype(buffer)>
%endfunction %% BlockTypeSetup

%% Function: Outputs =====
%% Abstract:
%%      y = my_alg( u );
%%
%function Outputs(block, system) Output
    /* %<Type> Block: %<Name> */
    %assign u = LibBlockInputSignal(0, "", "", 0)
    %assign y = LibBlockOutputSignal(0, "", "", 0)
    %% PROVIDE THE CALLING STATEMENT FOR "algorithm"
    %% The following line is expanded and placed in mdlOutputs within wrapper.c
    %<y> = my_alg(%<u>);

%endfunction %% Outputs

```

The first section of this code inlines the wrapsfcn S-Function block and generates the code in C:

```

%implements "wrapsfcn" "C"

```

The next task is to tell the code generator that the routine my_alg needs to be declared external in the generated wrapper.h file for any wrapsfcn S-Function blocks in the model. You only need to do this once for all wrapsfcn S-Function blocks, so use the BlockTypeSetup function. In this function, you tell the Target Language Compiler to create a buffer and cache the my_alg as extern in the wrapper.h generated header file.

The final step is the inlining of the call to the function `my_alg`. This is done by the `Outputs` function. In this function, you access the block's input and output and place a direct call to `my_alg`. The call is embedded in `wrapper.c`.

The Inlined Code

The code generated when you inline your wrapper S-function is similar to the default generated code. The `mdlTerminate` function no longer contains a call to an empty function and the `mdlOutputs` function now directly calls `my_alg`.

```
void mdlOutputs(int_T tid)
{
    /* Sin Block: <Root>/Sin */
    rtB.Sin = rtP.Sin.Amplitude *
        sin(rtP.Sin.Frequency * ssGetT(rtS) + rtP.Sin.Phase);

    /* S-Function Block: <Root>/S-Function */
    rtB.S_Function = my_alg(rtB.Sin); /* Inlined call to my_alg */

    /* Output Block: <Root>/Out */
    rtY.Out = rtB.S_Function;
}
```

In addition, `wrapper.reg` no longer creates a child `SimStruct` for the S-function because the generated code is calling `my_alg` directly. This eliminates over 1 K of memory usage.

Writing Fully Inlined S-Functions

Continuing the example of the previous section, you could eliminate the call to `my_alg` entirely by specifying the explicit code (that is, `2.0 * u`) in `wrapsfcn.tlc`. This is referred to as a *fully inlined S-function*. While this can improve performance, if you are working with a large amount of C/C++ code, this can be a lengthy task. In addition, you now have to maintain your algorithm in two places, the C/C++ S-function itself and the corresponding TLC file. However, the performance gains might outweigh the disadvantages. To inline the algorithm used in this example, in the Outputs section of your `wrapsfcn.tlc` file, instead of writing

```
%<y> = my_alg(%<u>);
```

use

```
%<y> = 2.0 * %<u>;
```

This is the code produced in `mdlOutputs`:

```
void mdlOutputs(int_T tid)
{
    /* Sin Block: <Root>/Sin */
    rtB.Sin = rtP.Sin.Amplitude *
        sin(rtP.Sin.Frequency * ssGetT(rtS) + rtP.Sin.Phase);

    /* S-Function Block: <Root>/S-Function */
    rtB.S_Function = 2.0 * rtB.Sin; /* Explicit embedding of algorithm */

    /* Outport Block: <Root>/Out */
    rtY.Out = rtB.S_Function;
}
```

The Target Language Compiler has replaced the call to `my_alg` with the algorithm itself.

Multiport S-Function Example

A more advanced multiport inlined S-function example exists in `matlabroot/simulink/src/sfun_multiport.c` and

`matlabroot/toolbox/simulink/blocks/tlc_c/sfun_multiport.tlc`.

This S-function demonstrates how to create a fully inlined TLC file for an S-function that contains multiple ports. You might find that looking at this example helps you to understand fully inlined TLC files.

Using the Legacy Code Tool to Automate the Generation of Files for Fully Inlined S-Functions

In this section...

“Legacy Code Tool and Code Generation” on page 10-24

“Generating File for Code Generation Support” on page 10-25

“Addressing Dependencies on Files in Different Locations” on page 10-25

“Deploying Generated S-Functions for Simulation and Code Generation” on page 10-26

Legacy Code Tool and Code Generation

The Simulink Legacy Code Tool provides a way to automatically generate fully inlined C MEX S-functions for legacy or custom code that is optimized for embedded components such as device drivers and lookup tables, that call existing C or C++ code. In addition, you can use the tool to

- Compile and build the generated S-function for simulation
- Generate a masked S-Function block that is configured to call the existing external code

If you want to include such S-functions in models for which you intend to generate code, you must use the tool to generate a TLC block file for the generated S-function. The TLC block file specifies how the generated code for a model calls the existing C code.

If the S-function depends on files in directories other than the directory containing the S-function dynamically loadable executable file and you want to maintain those dependencies for building a model that includes the S-function, you need the tool to also generate an `rtwmakecfg.m` file for the S-function. For example, for some applications, such as custom targets, it might be preferable to locate files in a target-specific location. The Real-Time Workshop build process looks for the generated `rtwmakecfg.m` file in the same directory as the S-function’s dynamically loadable executable and calls the `rtwmakecfg` function if the file is found.

For background information and to get started using the Legacy Code Tool, see “Integrating Existing C Functions into Simulink® Models with the Legacy Code Tool” in the Simulink Writing S-Functions documentation.

Generating File for Code Generation Support

Before you generate code for a model that includes an S-function generated by the Legacy Code Tool, you must generate a TLC block file for the S-function. Code generation fails otherwise.

To generate the TLC block file, call the `legacy_code` function with `'sfcn_tlc_generate'` as the first argument and the name of the Legacy Code Tool data structure as the second argument.

```
legacy_code('sfcn_tlc_generate', lct_spec);
```

Consider the example in “Example of Integrating Existing C Functions into Simulink® Models with the Legacy Code Tool” in the Simulink Writing S-Functions documentation. To generate code for the model shown at the end of that example (`LCT_example`), you must first enter the following command:

```
legacy_code('sfcn_tlc_generate', def);
```

Addressing Dependencies on Files in Different Locations

By default, the Legacy Code Tool assumes that all files on which an S-function depends reside in the same directory as the S-function’s dynamically loadable executable file. If your S-function depends on files that reside elsewhere and you are using the Real-Time Workshop template makefile build process, you must generate an `rtwmakecfg.m` file for the S-function. For example, it is likely that you need to generate this file if your Legacy Code Tool data structure defines compilation resources as pathnames.

To generate the `rtwmakecfg.m` file, call the `legacy_code` function with `'rtwmakecfg_generate'` as the first argument and the name of the Legacy Code Tool data structure as the second argument.

```
legacy_code('rtwmakecfg_generate', lct_spec);
```

If you use multiple registration files in the same directory and generate an S-function for each file with a single call to `legacy_code`, as explained in “Handling Multiple Registration Files” in the Simulink Writing S-Functions documentation, the call to `legacy_code` that specifies `'rtwmakecfg_generate'` must be common to all registration files.

For example, if `defs` is defined as an array of Legacy Code Tool structures, you call `legacy_code` with `'rtwmakecfg_generate'` once.

```
defs = [defs1(:);defs2(:);defs3(:)];  
legacy_code('rtwmakecfg_generate', defs);
```

For more information, see “Build Support for S-Functions” on page 10-81.

Deploying Generated S-Functions for Simulation and Code Generation

You can deploy the S-functions that you generate with the Legacy Code Tool for use by others. To deploy an S-function for simulation and code generation, you need to share the following files:

- Registration file
- Compiled dynamically loadable executable
- TLC block file
- `rtwmakecfg.m` file
- All header, source, and include files on which the generated S-function depends

Users of the deployed files might need to:

- Add the directory that contains the S-function files to the MATLAB path before using them in Simulink.
- Regenerate the `rtwmakecfg.m` file if the Legacy Code Tool data structure registers any required files as absolute paths and the location of the files changes.

Writing Fully Inlined S-Functions with the mdlRTW Routine

In this section...

“About S-Functions and mdlRTW” on page 10-27

“S-Function RTWdata” on page 10-28

“The Direct-Index Lookup Table Algorithm” on page 10-29

“The Direct-Index Lookup Table Example” on page 10-30

About S-Functions and mdlRTW

You can inline more complex S-functions that use the S-function `mdlRTW` routine. The purpose of the `mdlRTW` routine is to provide the code generation process with more information about how the S-function is to be inlined, by creating a parameter record of a nontunable parameter for use with a TLC file. The `mdlRTW` routine does this by placing information in the `model.rtw` file. The `mdlRTW` function is described in the text file `matlabroot/simulink/src/sfunmpl_doc.c`.

As an example of how to use the `mdlRTW` function, this section discusses the steps you must take to create a direct-index lookup S-function. Lookup tables are collections of ordered data points of a function. Typically, these tables use some interpolation scheme to approximate values of the associated function between known data points. To incorporate the example lookup table algorithm in Simulink, the first step is to write an S-function that executes the algorithm in `mdlOutputs`. To produce the most efficient code, the next step is to create a corresponding TLC file to eliminate computational overhead and improve the performance of the lookup computations.

For your convenience, Simulink provides support for two general-purpose lookup 1-D and 2-D algorithms. You can use these algorithms as they are or create a custom lookup table S-function to fit your requirements. This section demonstrates how to create a 1-D lookup S-function, `sfun_directlook.c`, and its corresponding inlined `sfun_directlook.tlc` file. (See the Target Language Compiler documentation for more details on the Target Language Compiler.) This 1-D direct-index lookup table example demonstrates the following concepts that you need to know to create your own custom lookup tables:

- Error checking of S-function parameters
- Caching of information for the S-function that doesn't change during model execution
- How to use the `mdlRTW` function to customize Real-Time Workshop generated code to produce the optimal code for a given set of block parameters
- How to generate an inlined TLC file for an S-function in a combination of the fully inlined form and/or the wrapper form

S-Function RTWdata

There is a property of blocks called `RTWdata`, which can be used by the Target Language Compiler when inlining an S-function. `RTWdata` is a structure of strings that you can attach to a block. It is saved with the model and placed in the `model.rtw` file when generating code. For example, this set of MATLAB commands,

```
mydata.field1 = 'information for field1';  
mydata.field2 = 'information for field2';  
set_param(gcf, 'RTWdata', mydata)  
get_param(gcf, 'RTWdata')
```

produces this result:

```
ans =  
  
    field1: 'information for field1'  
    field2: 'information for field2'
```

Inside the `model.rtw` file for the associated S-Function block is this information.

```
Block {  
    Type "S-Function"  
    RTWdata {  
        field1 "information for field1"  
        field2 "information for field2"  
    }  
}
```


The Direct-Index Lookup Table Algorithm

The 1-D lookup table block provided in the Simulink library uses interpolation or extrapolation when computing outputs. This extra accuracy is not needed in all situations. In this example, you create a lookup table that directly indexes the output vector (y -data vector) based on the current input (x -data) point.

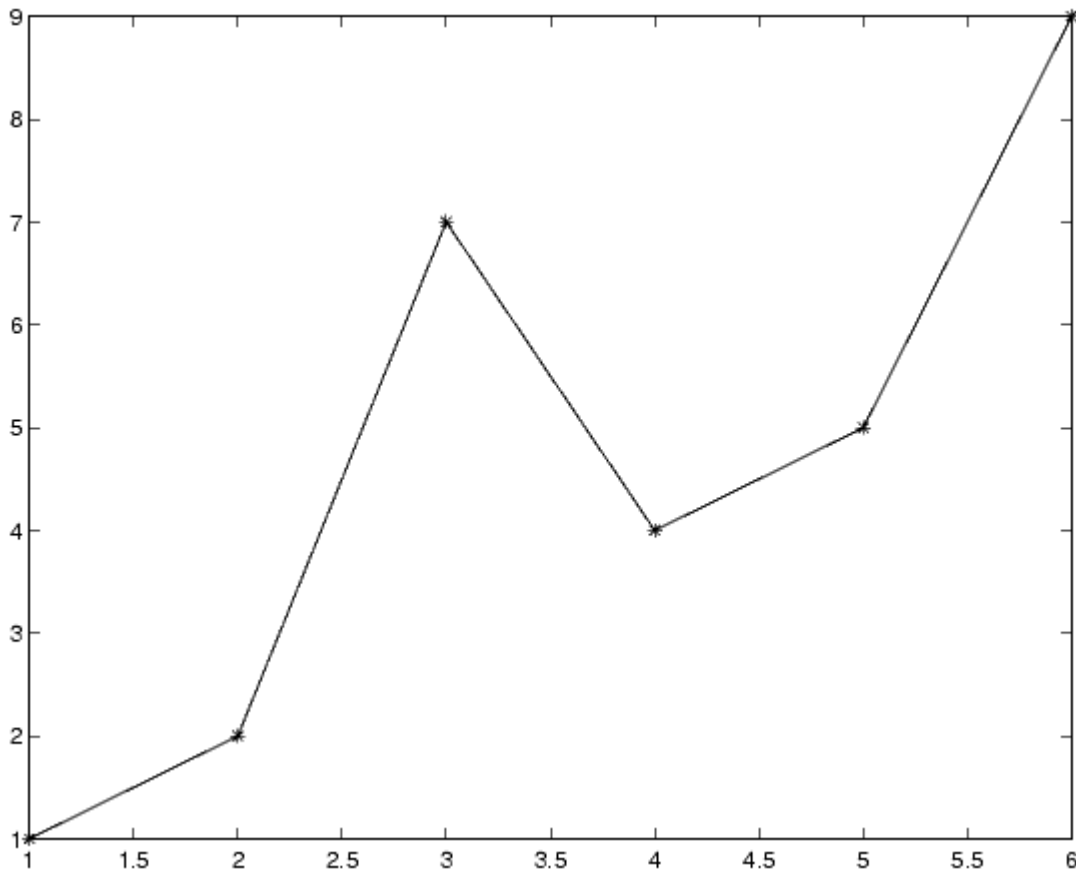
This direct 1-D lookup example computes an approximate solution $p(x)$ to a partially known function $f(x)$ at $x=x_0$, given data point pairs (x,y) in the form of an x -data vector and a y -data vector. For a given data pair (for example, the i 'th pair), $y_i = f(x_i)$. It is assumed that the x -data values are monotonically increasing. If x_0 is outside the range of the x -data vector, the first or last point is returned.

The parameters to the S-function are

`XData`, `YData`, `XEvenlySpaced`

`XData` and `YData` are double vectors of equal length representing the values of the unknown function. `XDataEvenlySpaced` is a scalar, 0.0 for false and 1.0 for true. If the `XData` vector is evenly spaced, `XDataEvenlySpaced` is 1.0 and more efficient code is generated.

The following graph shows how the parameters `XData=[1:6]` and `YData=[1,2,7,4,5,9]` are handled. For example, if the input (x -value) to the S-Function block is 3, the output (y -value) is 7.



The Direct-Index Lookup Table Example

This section shows how to improve the lookup table by inlining a direct-index S-function with a TLC file. This direct-index lookup table S-function does not require a TLC file. Here the example uses a TLC file for the direct-index lookup table S-function to reduce the code size and increase efficiency of the generated code.

Implementation of the direct-index algorithm with inlined TLC file requires the S-function main module, *matlabroot/simulink/src/sfun_directlook.c*,

and a corresponding `matlabroot/simulink/src/lookup_index.c` module. The `lookup_index.c` module contains the `GetDirectLookupIndex` function that is used to locate the index in the `XData` for the current `x` input value when the `XData` is unevenly spaced. The `GetDirectLookupIndex` routine is called from both the S-function and the generated code. Here the example uses the wrapper concept for sharing C/C++ code between Simulink MEX-files and the generated code.

If the `XData` is evenly spaced, then both the S-function main module and the generated code contain the lookup algorithm (not a call to the algorithm) to compute the `y`-value of a given `x`-value, because the algorithm is short. This demonstrates the use of a fully inlined S-function for generating optimal code.

The inlined TLC file, which either performs a wrapper call or embeds the optimal C/C++ code, is `matlabroot/toolbox/simulink/blocks/tlc_c/sfun_directlook.tlc` (see the example in “mdlRTW Usage” on page 10-32).

Error Handling

In this example, the `mdlCheckParameters` routine verifies that

- The new parameter settings are correct.
- `XData` and `YData` are vectors of the same length containing real finite numbers.
- `XDataEvenlySpaced` is a scalar.
- The `XData` vector is a monotonically increasing vector and evenly spaced if needed.

The `mdlInitializeSizes` function explicitly calls `mdlCheckParameters` after it verifies that the number of parameters passed to the S-function is correct. After Simulink calls `mdlInitializeSizes`, it then calls `mdlCheckParameters` whenever you change the parameters or there is a need to reevaluate them.

User Data Caching

The `mdlStart` routine shows how to cache information that does not change during the simulation (or while the generated code is executing). The example caches the value of the `XDataEvenlySpaced` parameter in `UserData`, a field of

the `SimStruct`. The following line in `mdlInitializeSizes` tells Simulink to disallow changes to `XDataEvenlySpaced`.

```
ssSetSFcnParamTunable(S, iParam, SS_PRM_NOT_TUNABLE);
```

During execution, `mdlOutputs` accesses the value of `XDataEvenlySpaced` from `UserData` rather than calling the `mxGetPr` MATLAB API function. This increases performance.

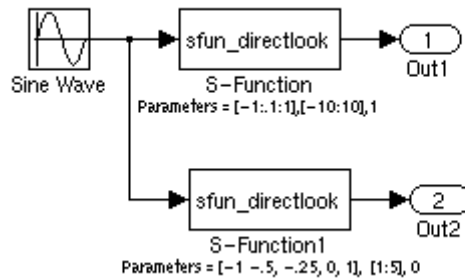
mdlRTW Usage

The Real-Time Workshop code generator calls the `mdlRTW` routine while generating the `model.rtw` file. To produce optimal code for your Simulink model, you can add information to the `model.rtw` file about the mode in which your S-Function block is operating.

The following example adds parameter settings to the `model.rtw` file. The parameter settings do not change during execution. In this case, the `XDataEvenlySpaced` S-function parameter cannot change during execution (`ssSetSFcnParamTunable` was specified as false (0) for it in `mdlInitializeSizes`). The example writes it out as a parameter setting (`XSpacing`) using the function `ssWriteRTWParamSettings`.

Because `xData` and `yData` are registered as run-time parameters in `mdlSetWorkWidths`, the code generator handles writing to the `model.rtw` file automatically.

Before examining the S-function and the inlined TLC file, consider the generated code for the following model.



The model uses evenly spaced XData in the top S-Function block and unevenly spaced XData in the bottom S-Function block. When creating this model, you need to specify the following for each S-Function block.

```
set_param('sfun_directlook_ex/S-Function','SFunctionModules','lookup_index')
set_param('sfun_directlook_ex/S-Function1','SFunctionModules','lookup_index')
```

This informs the Real-Time Workshop build process that the module `lookup_index.c` is needed when creating the executable.

When generating code for this model, the Real-Time Workshop product uses the S-function's `mdlRTW` method to generate a `model.rtw` file with the value `EvenlySpaced` for the `XSpacing` parameter for the top S-Function block, and the value `UnEvenlySpaced` for the `XSpacing` parameter for the bottom S-Function block. The TLC-file uses the value of `XSpacing` to determine what algorithm to include in the generated code. The generated code contains the lookup algorithm when the XData is evenly spaced, but calls the `GetDirectLookupIndex` routine when the XData is unevenly spaced. The generated `model.c` or `model.cpp` code for the lookup table example model is

```
/*
 * sfun_directlook_ex.c
 *
 * Real-Time Workshop code generation for Simulink model
 * "sfun_directlook_ex.mdl".
 *
 * Model Version          : 1.2
```

```
* Real-Time Workshop version : 6.0 (R14) 06-Apr-2004
* C source code generated on : Fri Apr 09 09:15:12 2004
*/

#include "sfun_directlook_ex.h"
#include "sfun_directlook_ex_private.h"

/* External output (root outports fed by signals with auto storage) */
ExternalOutputs_sfun_directlook_ex sfun_directlook_ex_Y;

/* Real-time model */
rtModel_sfun_directlook_ex sfun_directlook_ex_M;
rtModel_sfun_directlook_ex *sfun_directlook_ex_M = &sfun_directlook_ex_M;

/* Model output function */
static void sfun_directlook_ex_output(int_T tid)
{

    /* local block i/o variables */

    real_T rtb_SFunction_h;
    real_T rtb_temp1;

    /* Sin: '<Root>/Sine Wave' */
    rtb_temp1 = sfun_directlook_ex_P.SineWave_Amp *
        sin(sfun_directlook_ex_P.SineWave_Freq * sfun_directlook_ex_M->Timing.t[0] +
            sfun_directlook_ex_P.SineWave_Phase) + sfun_directlook_ex_P.SineWave_Bias;

    /* Code that is inlined for the top S-function block in the
     * sfun_directlook_ex model
     */
    /* S-Function Block: <Root>/S-Function */
    {
        const real_T *xData = &sfun_directlook_ex_P.SFunction_XData[0];
        const real_T *yData = &sfun_directlook_ex_P.SFunction_YData[0];
        real_T spacing = xData[1] - xData[0];

        if ( rtb_temp1 <= xData[0] ) {
            rtb_SFunction_h = yData[0];
        } else if ( rtb_temp1 >= yData[20] ) {
```

```

        rtb_SFunction_h = yData[20];
    } else {
        int_T idx = (int_T)( ( rtb_temp1 - xData[0] ) / spacing );
        rtb_SFunction_h = yData[idx];
    }
}

/* Outport: '<Root>/Out1' */
sfun_directlook_ex_Y.Out1 = rtb_SFunction_h;

/* Code that is inlined for the bottom S-function block in the
 * sfun_directlook_ex model
 */
/* S-Function Block: <Root>/S-Function1 */
{
    const real_T *xData = &sfun_directlook_ex_P.SFunction1_XData[0];
    const real_T *yData = &sfun_directlook_ex_P.SFunction1_YData[0];
    int_T idx;

    idx = GetDirectLookupIndex(xData, 5, rtb_temp1);
    rtb_temp1 = yData[idx];
}

/* Outport: '<Root>/Out2' */
sfun_directlook_ex_Y.Out2 = rtb_temp1;
}

/* Model update function */
static void sfun_directlook_ex_update(int_T tid)
{
    /* Update absolute time for base rate */

    if(++sfun_directlook_ex_M->Timing.clockTick0)
    ++sfun_directlook_ex_M->Timing.clockTickH0;
    sfun_directlook_ex_M->Timing.t[0] = sfun_directlook_ex_M->Timing.clockTick0 *
        sfun_directlook_ex_M->Timing.stepSize0 +
        sfun_directlook_ex_M->Timing.clockTickH0 *
        sfun_directlook_ex_M->Timing.stepSize0 * 0x10000;
}

```

```

{
  /* Update absolute timer for sample time: [0.1s, 0.0s] */

  if(!(++sfun_directlook_ex_M->Timing.clockTick1))
  ++sfun_directlook_ex_M->Timing.clockTickH1;
  sfun_directlook_ex_M->Timing.t[1] = sfun_directlook_ex_M->Timing.clockTick1
    * sfun_directlook_ex_M->Timing.stepSize1 +
    sfun_directlook_ex_M->Timing.clockTickH1 *
    sfun_directlook_ex_M->Timing.stepSize1 * 0x10000;
}
}
...

```

matlabroot/simulink/src/sfun_directlook.c

```

/*
 * File      : sfun_directlook.c
 * Abstract:
 *
 * Direct 1-D lookup. Here we are trying to compute an approximate
 * solution, p(x) to an unknown function f(x) at x=x0, given data point
 * pairs (x,y) in the form of a x data vector and a y data vector. For a
 * given data pair (say the i'th pair), we have y_i = f(x_i). It is
 * assumed that the x data values are monotonically increasing. If the
 * x0 is outside of the range of the x data vector, then the first or
 * last point will be returned.
 *
 * This function returns the "nearest" y0 point for a given x0. No
 * interpolation is performed.
 *
 * The S-function parameters are:
 *   XData          - double vector
 *   YData          - double vector
 *   XDataEvenlySpacing - double scalar 0 (false) or 1 (true)
 *   The third parameter cannot be changed during simulation.
 *
 * To build:
 *   mex sfun_directlook.c lookup_index.c
 *

```



```
* Copyright 1990-2004 The MathWorks, Inc.
* $Revision: 1.1.4.78 $
*/

#define S_FUNCTION_NAME  sfun_directlook
#define S_FUNCTION_LEVEL 2

#include <math.h>
#include "simstruc.h"
#include <float.h>

/* use utility function IsRealVect() */
#if defined(MATLAB_MEX_FILE)
#include "sfun_slutils.h"
#endif

/*=====
 * Build checking *
 *=====*/
#if !defined(MATLAB_MEX_FILE)
/*
 * This file cannot be used directly with Real-Time Workshop. However,
 * this S-function does work with Real-Time Workshop via
 * the Target Language Compiler technology. See
 * matlabroot/toolbox/simulink/blocks/tlc_c/sfun_directlook.tlc
 * for the C version
 */
# error This_file_can_be_used_only_during_simulation_inside_Simulink
#endif

/*=====
 * Defines *
 *=====*/

#define XVECT_PIDX      0
#define YVECT_PIDX      1
#define XDATAEVENLYSPACED_PIDX 2
#define NUM_PARAMS      3
```

```

#define XVECT(S)          ssGetSFcnParam(S,XVECT_PIDX)
#define YVECT(S)          ssGetSFcnParam(S,YVECT_PIDX)
#define XDATAEVENLYSPACED(S) ssGetSFcnParam(S,XDATAEVENLYSPACED_PIDX)

/*=====*/
* misc defines *
/*=====*/
#if !defined(TRUE)
#define TRUE 1
#endif
#if !defined(FALSE)
#define FALSE 0
#endif

/*=====*/
* typedef's *
/*=====*/

typedef struct SFcnCache_tag {
    boolean_T evenlySpaced;
} SFcnCache;

/*=====*/
* Prototype define for the function in separate file lookup_index.c *
/*=====*/
extern int_T GetDirectLookupIndex(const real_T *x, int_T xlen, real_T u);

/*=====*/
* S-function methods *
/*=====*/

#define MDL_CHECK_PARAMETERS          /* Change to #undef to remove function */
#if defined(MDL_CHECK_PARAMETERS) && defined(MATLAB_MEX_FILE)
/* Function: mdlCheckParameters =====
* Abstract:
* This routine will be called after mdlInitializeSizes, whenever

```

```

*   parameters change or get re-evaluated. The purpose of this routine is
*   to verify that the new parameter setting are correct.
*
*   You should add a call to this routine from mdlInitializeSizes
*   to check the parameters. After setting your sizes elements, you should:
*       if (ssGetSFcnParamsCount(S) == ssGetNumSFcnParams(S)) {
*           mdlCheckParameters(S);
*       }
*/
static void mdlCheckParameters(SimStruct *S)
{

    if (!IsRealVect(XVECT(S))) {
        ssSetErrorStatus(S,"1st, X-vector parameter must be a real finite "
            " vector");
        return;
    }

    if (!IsRealVect(YVECT(S))) {
        ssSetErrorStatus(S,"2nd, Y-vector parameter must be a real finite "
            "vector");
        return;
    }

    /*
    * Verify that the dimensions of X and Y are the same.
    */
    if (mxGetNumberOfElements(XVECT(S)) != mxGetNumberOfElements(YVECT(S)) ||
        mxGetNumberOfElements(XVECT(S)) == 1) {
        ssSetErrorStatus(S,"X and Y-vectors must be of the same dimension "
            "and have at least two elements");
        return;
    }

    /*
    * Verify we have a valid XDataEvenlySpaced parameter.
    */
    if (!(!mxIsNumeric(XDATAEVENLYSPACED(S)) &&
        !mxIsLogical(XDATAEVENLYSPACED(S)) ||
        mxIsComplex(XDATAEVENLYSPACED(S)) ||

```

```
        mxGetNumberOfElements(XDATAEVENLYSPACED(S)) != 1) {
            ssSetErrorStatus(S,"3rd, X-evenly-spaced parameter must be logical
scalar");
        }
        return;
    }

    /*
    * Verify x-data is correctly spaced.
    */
    {
        int_T    i;
        boolean_T spacingEqual;
        real_T    *xData = mxGetPr(XVECT(S));
        int_T    numEl = mxGetNumberOfElements(XVECT(S));

        /*
        * spacingEqual is TRUE if user XDataEvenlySpaced
        */
        spacingEqual = (mxGetScalar(XDATAEVENLYSPACED(S)) != 0.0);

        if (spacingEqual) { /* XData is 'evenly-spaced' */
            boolean_T badSpacing = FALSE;
            real_T    spacing = xData[1] - xData[0];
            real_T    space;

            if (spacing <= 0.0) {
                badSpacing = TRUE;
            } else {
                real_T eps = DBL_EPSILON;

                for (i = 2; i < numEl; i++) {
                    space = xData[i] - xData[i-1];
                    if (space <= 0.0 ||
                        fabs(space-spacing) >= 128.0*eps*spacing ){
                        badSpacing = TRUE;
                        break;
                    }
                }
            }
        }
    }
}
```

```

        if (badSpacing) {
            ssSetErrorStatus(S,"X-vector must be an evenly spaced "
                "strictly monotonically increasing vector");
            return;
        }
    } else { /* XData is 'unevenly-spaced' */
        for (i = 1; i < numEl; i++) {
            if (xData[i] <= xData[i-1]) {
                ssSetErrorStatus(S,"X-vector must be a strictly "
                    "monotonically increasing vector");
                return;
            }
        }
    }
}
}
#endif /* MDL_CHECK_PARAMETERS */

/* Function: mdlInitializeSizes =====
 * Abstract:
 * The sizes information is used by Simulink to determine the S-function
 * block's characteristics (number of inputs, outputs, states, and so on).
 */
static void mdlInitializeSizes(SimStruct *S)
{
    ssSetNumSFcnParams(S, NUM_PARAMS); /* Number of expected parameters */

    /*
     * Check parameters passed in, providing the correct number was specified
     * in the S-function dialog box. If an incorrect number of parameters
     * was specified, Simulink will detect the error since ssGetNumSFcnParams
     * and ssGetSFcnParamsCount will differ.
     * ssGetNumSFcnParams - This sets the number of parameters your
     * S-function expects.
     * ssGetSFcnParamsCount - This is the number of parameters entered by
     * the user in the Simulink S-function dialog box.
     */
    #if defined(MATLAB_MEX_FILE)

```

```
if (ssGetNumSFcnParams(S) == ssGetSFcnParamsCount(S)) {
    mdlCheckParameters(S);
    if (ssGetErrorStatus(S) != NULL) {
        return;
    }
} else {
    return; /* Parameter mismatch will be reported by Simulink */
}
#endif

{
    int iParam = 0;
    int nParam = ssGetNumSFcnParams(S);

    for ( iParam = 0; iParam < nParam; iParam++ )
    {
        switch ( iParam )
        {
            case XDATAEVENLYSPACED_PIDX:

                ssSetSFcnParamTunable( S, iParam, SS_PRM_NOT_TUNABLE );
                break;

            default:
                ssSetSFcnParamTunable( S, iParam, SS_PRM_TUNABLE );
                break;
        }
    }
}

ssSetNumContStates(S, 0);
ssSetNumDiscStates(S, 0);

if (!ssSetNumInputPorts(S, 1)) return;
ssSetInputPortWidth(S, 0, DYNAMICALLY_SIZED);
ssSetInputPortDirectFeedThrough(S, 0, 1);

ssSetInputPortOptimOpts(S, 0, SS_REUSABLE_AND_LOCAL);
ssSetInputPortOverWritable(S, 0, TRUE);
```

```

    if (!ssSetNumOutputPorts(S, 1)) return;
    ssSetOutputPortWidth(S, 0, DYNAMICALLY_SIZED);

    ssSetOutputPortOptimOpts(S, 0, SS_REUSABLE_AND_LOCAL);

    ssSetNumSampleTimes(S, 1);

    ssSetOptions(S,
                 SS_OPTION_WORKS_WITH_CODE_REUSE |
                 SS_OPTION_EXCEPTION_FREE_CODE |
                 SS_OPTION_USE_TLC_WITH_ACCELERATOR);

} /* mdlInitializeSizes */

/* Function: mdlInitializeSampleTimes =====
 * Abstract:
 *   The lookup inherits its sample time from the driving block.
 */
static void mdlInitializeSampleTimes(SimStruct *S)
{
    ssSetSampleTime(S, 0, INHERITED_SAMPLE_TIME);
    ssSetOffsetTime(S, 0, 0.0);
    ssSetModelReferenceSampleTimeDefaultInheritance(S);
} /* end mdlInitializeSampleTimes */

/* Function: mdlSetWorkWidths =====
 * Abstract:
 *   Set up the [X,Y] data as run-time parameters
 *   that is, these values can be changed during execution.
 */
#define MDL_SET_WORK_WIDTHS
static void mdlSetWorkWidths(SimStruct *S)
{
    const char_T    *rtParamNames[] = {"XData", "YData"};
    ssRegAllTunableParamsAsRunTimeParams(S, rtParamNames);
}

#define MDL_START                /* Change to #undef to remove function */

```

```

#if defined(MDL_START)
/* Function: mdlStart =====
 * Abstract:
 *   Here we cache the state (true/false) of the XDATAEVENLYSPACED parameter.
 *   We do this primarily to illustrate how to "cache" parameter values (or
 *   information which is computed from parameter values) which do not change
 *   for the duration of the simulation (or in the generated code). In this
 *   case, rather than repeated calls to mxGetPr, we save the state once.
 *   This results in a slight increase in performance.
 */
static void mdlStart(SimStruct *S)
{
    SFcnCache *cache = malloc(sizeof(SFcnCache));

    if (cache == NULL) {
        ssSetErrorStatus(S,"memory allocation error");
        return;
    }

    ssSetUserData(S, cache);

    if (mxGetScalar(XDATAEVENLYSPACED(S)) != 0.0){
        cache->evenlySpaced = TRUE;
    }else{
        cache->evenlySpaced = FALSE;
    }

}
#endif /* MDL_START */

/* Function: mdlOutputs =====
 * Abstract:
 *   In this function, you compute the outputs of your S-function
 *   block. Generally outputs are placed in the output vector, ssGetY(S).
 */
static void mdlOutputs(SimStruct *S, int_T tid)
{
    SFcnCache      *cache = ssGetUserData(S);

```



```

real_T          *xData = mxGetPr(XVECT(S));
real_T          *yData = mxGetPr(YVECT(S));
InputRealPtrsType uPtrs = ssGetInputPortRealSignalPtrs(S,0);
real_T          *y      = ssGetOutputPortRealSignal(S,0);
int_T           ny      = ssGetOutputPortWidth(S,0);
int_T           xLen    = mxGetNumberOfElements(XVECT(S));
int_T           i;

/*
 * When the XData is evenly spaced, we use the direct lookup algorithm
 * to calculate the lookup
 */
if (cache->evenlySpaced) {
    real_T spacing = xData[1] - xData[0];
    for (i = 0; i < ny; i++) {
        real_T u = *uPtrs[i];

        if (u <= xData[0]) {
            y[i] = yData[0];
        } else if (u >= xData[xLen-1]) {
            y[i] = yData[xLen-1];
        } else {
            int_T idx = (int_T)((u - xData[0])/spacing);
            y[i] = yData[idx];
        }
    }
} else {
    /*
     * When the XData is unevenly spaced, we use a bisection search to
     * locate the lookup index.
     */
    for (i = 0; i < ny; i++) {
        int_T idx = GetDirectLookupIndex(xData,xLen,*uPtrs[i]);
        y[i] = yData[idx];
    }
}
} /* end mdlOutputs */

```

```

/* Function: mdlTerminate =====
 * Abstract:
 *   Free the cache which was allocated in mdlStart.
 */
static void mdlTerminate(SimStruct *S)
{
    SFcnCache *cache = ssGetUserData(S);
    if (cache != NULL) {
        free(cache);
    }
} /* end mdlTerminate */

#define MDL_RTW                               /* Change to #undef to remove function */
#if defined(MDL_RTW) && (defined(MATLAB_MEX_FILE) || defined(NRT))
/* Function: mdlRTW =====
 * Abstract:
 *   This function is called when Real-Time Workshop is generating the
 *   model.rtw file. In this routine, you can call the following functions
 *   which add fields to the model.rtw file.
 *
 *   Important! Since this s-function has this mdlRTW method, it is required
 *   to have a correponding .tlc file so as to work with RTW. You will find
 *   the sfun_directlook.tlc in <matlaroot>/toolbox/simulink/blocks/tlc_c/.
 */
static void mdlRTW(SimStruct *S)
{
    /*
     * Write out the spacing setting as a param setting, that is, this cannot be
     * changed during execution.
     */
    {
        boolean_T even = (mxGetScalar(XDATAEVENLYSPACED(S)) != 0.0);

        if (!ssWriteRTWParamSettings(S, 1,
                                     SSWRITE_VALUE_QSTR,
                                     "XSpacing",
                                     even ? "EvenlySpaced" : "UnEvenlySpaced")){

```

```

        return; /* An error occurred which will be reported by Simulink */
    }
}
}
#endif /* MDL_RTW */

/*=====
 * Required S-function trailer *
 *=====*/

#ifdef MATLAB_MEX_FILE /* Is this file being compiled as a MEX-file? */
#include "simulink.c" /* MEX-file interface mechanism */
#else
#include "cg_sfun.h" /* Code generation registration function */
#endif

/* [EOF] sfun_directlook.c */

```

matlabroot/simulink/src/lookup_index.c

```

/* File      : lookup_index.c
 * Abstract:
 *
 *      Contains a routine used by the S-function sfun_directlookup.c to
 *      compute the index in a vector for a given data value.
 *
 *      Copyright 1990-2004 The MathWorks, Inc.
 *      $Revision: 1.1.4.78 $
 */
#include "tmwtypes.h"

/*
 * Function: GetDirectLookupIndex =====
 * Abstract:
 *      Using a bisection search to locate the lookup index when the x-vector
 *      isn't evenly spaced.
 *

```

```

*      Inputs:
*      *x   : Pointer to table, x[0] ...x[xlen-1]
*      xlen : Number of values in xtable
*      u    : input value to look up
*
*      Output:
*      idx  : the index into the table such that:
*             if u is negative
*                 x[idx] <= u < x[idx+1]
*             else
*                 x[idx] < u <= x[idx+1]
*/
int_T GetDirectLookupIndex(const real_T *x, int_T xlen, real_T u)
{
    int_T idx    = 0;
    int_T bottom = 0;
    int_T top    = xlen-1;

    /*
    * Deal with the extreme cases first:
    *
    * i] u <= x[bottom] then idx = bottom
    * ii] u >= x[top] then idx = top-1
    *
    */
    if (u <= x[bottom]) {
        return(bottom);
    } else if (u >= x[top]) {
        return(top);
    }

    /*
    * We have: x[bottom] < u < x[top], onward
    * with search for the appropriate index ...
    */
    for (;;) {
        idx = (bottom + top)/2;
        if (u < x[idx]) {
            top = idx;
        } else if (u > x[idx+1]) {

```

```

        bottom = idx + 1;
    } else {
        /*
        * We have: x[idx] <= u <= x[idx+1], only need
        * to do two more checks and we have the answer
        */
        if (u < 0) {
            /*
            * We want right continuity, that is,
            * if u == x[idx+1]
            * then x[idx+1] <= u < x[idx+2]
            * else x[idx ] <= u < x[idx+1]
            */
            return( (u == x[idx+1]) ? (idx+1) : idx);
        } else {
            /*
            * We want left continuity, that is,
            * if u == x[idx]
            * then x[idx-1] < u <= x[idx ]
            * else x[idx ] < u <= x[idx+1]
            */
            return( (u == x[idx]) ? (idx-1) : idx);
        }
    }
}
} /* end GetDirectLookupIndex */

/* [EOF] lookup_index.c */

```

matlabroot/toolbox/simulink/blocks/tlc_c/sfun_directlook.tlc

```

%% File      : sfun_directlook.tlc
%% Abstract:
%%      Level-2 S-function sfun_directlook block target file.
%%      It is using direct lookup algorithm without interpolation
%%
%% Copyright 1990-2004 The MathWorks, Inc.
%% $Revision: 1.1.4.78 $

```

```

%implements "sfun_directlook" "C"

%% Function: BlockTypeSetup =====
%% Abstract:
%%     Place include and function prototype in the model's header file.
%%
%%function BlockTypeSetup(block, system) void

    %% To add this external function's prototype in the header of the generated
    %% file.
    %%
    %%openfile buffer
    extern int_T GetDirectLookupIndex(const real_T *x, int_T xlen, real_T u);
    %%closefile buffer

    %<LibCacheFunctionPrototype(buffer)>

%endfunction

%% Function: mdlOutputs =====
%% Abstract:
%%     Direct 1-D lookup table S-function example.
%%     Here we are trying to compute an approximate solution, p(x) to an
%%     unknown function f(x) at x=x0, given data point pairs (x,y) in the
%%     form of a x data vector and a y data vector. For a given data pair
%%     (say the i'th pair), we have y_i = f(x_i). It is assumed that the x
%%     data values are monotonically increasing. If the first or last x is
%%     outside of the range of the x data vector, then the first or last
%%     point will be returned.
%%
%%     This function returns the "nearest" y0 point for a given x0.
%%     No interpolation is performed.
%%
%%     The S-function parameters are:
%%         XData
%%         YData
%%         XEvenlySpaced: 0 or 1
%%     The third parameter cannot be changed during execution and is
%%     written to the model.rtw file in XSpacing filed of the SFcnParamSettings

```

```

%%      record as "EvenlySpaced" or "UnEvenlySpaced". The first two parameters
%%      can change during execution and show up in the parameter vector.
%%
%%function Outputs(block, system) Output
/* %<Type> Block: %<Name> */
{
    %assign rollVars = ["U", "Y"]
    %%
    %% Load XData and YData as local variables
    %%
    const real_T *xData = %<LibBlockParameterAddr(XData, "", "", 0)>;
    const real_T *yData = %<LibBlockParameterAddr(YData, "", "", 0)>;
    %assign xDataLen = SIZE(XData.Value, 1)
    %%
    %% When the XData is evenly spaced, we use the direct lookup algorithm
    %% to locate the lookup index.
    %%
    %if SFcnParamSettings.XSpacing == "EvenlySpaced"
        real_T spacing = xData[1] - xData[0];

        %roll idx = RollRegions, lcv = RollThreshold, block, "Roller", rollVars
        %assign u = LibBlockInputSignal(0, "", lcv, idx)
        %assign y = LibBlockOutputSignal(0, "", lcv, idx)
        if ( %<u> <= xData[0] ) {
            %<y> = yData[0];
        } else if ( %<u> >= yData[%<xDataLen-1>] ) {
            %<y> = yData[%<xDataLen-1>];
        } else {
            int_T idx = (int_T)( ( %<u> - xData[0] ) / spacing );
            %<y> = yData[idx];
        }
        %%
        %% Generate an empty line if we are not rolling,
        %% so that it looks nice in the generated code.
        %%
        %if lcv == ""

            %endif
        %endroll
    %else

```

```
%% When the XData is unevenly spaced, we use a bisection search to
%% locate the lookup index.
int_T idx;

%assign xDataAddr = LibBlockParameterAddr(XData, "", "", 0)
%roll idx = RollRegions, lcv = RollThreshold, block, "Roller", rollVars
  %assign u = LibBlockInputSignal(0, "", lcv, idx)
  idx = GetDirectLookupIndex(xData, %<xDataLen>, %<u>);
  %assign y = LibBlockOutputSignal(0, "", lcv, idx)
  %<y> = yData[idx];
  %%
  %% Generate an empty line if we are not rolling,
  %% so that it looks nice in the generated code.
  %%
  %if lcv == ""

  %endif
%endroll
%endif
}
%endfunction
%% EOF: sfun_directlook.tlc
```


Writing S-Functions That Support Expression Folding

In this section...

“Introduction” on page 10-53

“Categories of Output Expressions” on page 10-54

“Acceptance or Denial of Requests for Input Expressions” on page 10-59

“Utilizing Expression Folding in Your TLC Block Implementation” on page 10-63

Introduction

This section describes how you can take advantage of expression folding to increase the efficiency of code generated by your own inlined S-Function blocks, by calling macros provided in the S-Function API. This section assumes that you are familiar with:

- Writing inlined S-functions (see “Overview of S-Functions” in the Simulink Writing S-Functions documentation).
- The Target Language Compiler (see the Target Language Compiler documentation)

The S-Function API lets you specify whether a given S-Function block should nominally accept expressions at a given input port. A block should not always accept expressions. For example, if the address of the signal at the input is used, expressions should not be accepted at that input, because it is not possible to take the address of an expression.

The S-Function API also lets you specify whether an expression can represent the computations associated with a given output port. When you request an expression at a block’s input or output port, Simulink determines whether or not it can honor that request, given the block’s context. For example, Simulink might deny a block’s request to output an expression if the destination block does not accept expressions at its input, if the destination block has an update function, or if there are multiple output destinations.

The decision to honor or deny a request to output an expression can also depend on the category of output expression the block uses (see “Categories of Output Expressions” on page 10-54).

The sections that follow explain

- When and how you can request that a block accept expressions at an input port
- When and how you can request that a block generate expressions at an output port
- The conditions under which Simulink will honor or deny such requests

To take advantage of expression folding in your S-functions, you need to understand when it is appropriate to request acceptance and generation of expressions for specific blocks. It is not necessary for you to understand the algorithm by which Simulink chooses to accept or deny these requests. However, if you want to trace between the model and the generated code, it is helpful to understand some of the more common situations that lead to denial of a request.

Categories of Output Expressions

When you implement a C-MEX S-function, you can specify whether the code corresponding to a block’s output is to be generated as an expression. If the block generates an expression, you must specify that the expression is *constant*, *trivial*, or *generic*.

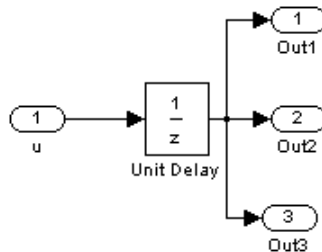
A *constant* output expression is a direct access to one of the block’s parameters. For example, the output of a Constant block is defined as a constant expression because the output expression is simply a direct access to the block’s Value parameter.

A *trivial* output expression is an expression that can be repeated, without any performance penalty, when the output port has multiple output destinations. For example, the output of a Unit Delay block is defined as a trivial expression because the output expression is simply a direct access to the block’s state. Because the output expression involves no computations, it can be repeated more than once without degrading the performance of the generated code.

A *generic* output expression is an expression that should be assumed to have a performance penalty if repeated. As such, a generic output expression is not suitable for repeating when the output port has multiple output destinations. For instance, the output of a Sum block is a generic rather than a trivial expression because it is costly to recompute a Sum block output expression as an input to multiple blocks.

Examples of Trivial and Generic Output Expressions

Consider the following block diagram. The Delay block has multiple destinations, yet its output is designated as a trivial output expression, so that it can be used more than once without degrading the efficiency of the code.



The following code excerpt shows code generated from the Unit Delay block in this block diagram. The three root outputs are directly assigned from the state of the Unit Delay block, which is stored in a field of the global data structure `rtDWork`. Since the assignment is direct, involving no expressions, there is no performance penalty associated with using the trivial expression for multiple destinations.

```
void MdlOutputs(int_T tid)
{
    ...
    /* Outputport: <Root>/Out1 incorporates:
     *   UnitDelay: <Root>/Unit Delay */
    rtY.Out1 = rtDWork.Unit_Delay_DSTATE;

    /* Outputport: <Root>/Out2 incorporates:
     *   UnitDelay: <Root>/Unit Delay */
    rtY.Out2 = rtDWork.Unit_Delay_DSTATE;
```

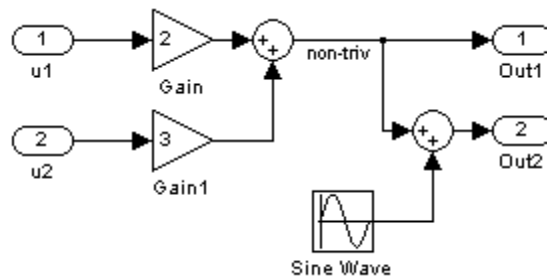
```

/* Output: <Root>/Out3 incorporates:
 *   UnitDelay: <Root>/Unit Delay */
rtY.Out3 = rtDWork.Unit_Delay_DSTATE;

...
}

```

On the other hand, consider the Sum blocks in the following model:



The upper Sum block in the preceding model generates the signal labeled `non_triv`. Computation of this output signal involves two multiplications and an addition. If the Sum block's output were permitted to generate an expression even when the block had multiple destinations, the block's operations would be duplicated in the generated code. In the case illustrated, the generated expressions would proliferate to four multiplications and two additions. This would degrade the efficiency of the program. Accordingly the output of the Sum block is not allowed to be an expression because it has multiple destinations

The code generated for the previous block diagram shows how code is generated for Sum blocks with single and multiple destinations.

The Simulink engine does not permit the output of the upper Sum block to be an expression because the signal `non_triv` is routed to two output destinations. Instead, the result of the multiplication and addition operations is stored in a temporary variable (`rtb_non_triv`) that is referenced twice in the statements that follow, as seen in the code excerpt below.

In contrast, the lower Sum block, which has only a single output destination (Out2), does generate an expression.

```

void MdlOutputs(int_T tid)
{
    /* local block i/o variables */
    real_T rtb_non_triv;
    real_T rtb_Sine_Wave;

    /* Sum: <Root>/Sum incorporates:
    *   Gain: <Root>/Gain
    *   Inport: <Root>/u1
    *   Gain: <Root>/Gain1
    *   Inport: <Root>/u2
    *
    * Regarding <Root>/Gain:
    *   Gain value: rtP.Gain_Gain
    *
    * Regarding <Root>/Gain1:
    *   Gain value: rtP.Gain1_Gain
    */
    rtb_non_triv = (rtP.Gain_Gain * rtU.u1) + (rtP.Gain1_Gain *
rtU.u2);

    /* Output: <Root>/Out1 */
    rtY.Out1 = rtb_non_triv;

    /* Sin Block: <Root>/Sine Wave */

    rtb_Sine_Wave = rtP.Sine_Wave_Amp *
sin(rtP.Sine_Wave_Freq * rtmGetT(rtM_model) +
rtP.Sine_Wave_Phase) + rtP.Sine_Wave_Bias;

    /* Output: <Root>/Out2 incorporates:
    *   Sum: <Root>/Sum1
    */
    rtY.Out2 = (rtb_non_triv + rtb_Sine_Wave);
}

```

Specifying the Category of an Output Expression

The S-Function API provides macros that let you declare whether an output of a block should be an expression, and if so, to specify the category of the expression. The following table specifies when to declare a block output to be a constant, trivial, or generic output expression.

Types of Output Expressions

Category of Expression	When to Use
Constant	Use only if block output is a direct memory access to a block parameter.
Trivial	Use only if block output is an expression that can appear multiple times in the code without reducing efficiency (for example, a direct memory access to a field of the <code>DWork</code> vector, or a literal).
Generic	Use if output is an expression, but not constant or trivial.

You must declare outputs as expressions in the `mdlSetWorkWidthsfunction` using macros defined in the S-Function API. The macros have the following arguments:

- `SimStruct *S`: pointer to the block's `SimStruct`.
- `int idx`: zero-based index of the output port.
- `bool value`: pass in `TRUE` if the port generates output expressions.

The following macros are available for setting an output to be a constant, trivial, or generic expression:

- `void ssSetOutputPortConstantOutputExprInRTW(SimStruct *S, int idx, bool value)`
- `void ssSetOutputPortTrivialOutputExprInRTW(SimStruct *S, int idx, bool value)`

- `void ssSetOutputPortOutputExprInRTW(SimStruct *S, int idx, bool value)`

The following macros are available for querying the status set by any prior calls to the macros above:

- `bool ssGetOutputPortConstantOutputExprInRTW(SimStruct *S, int idx)`
- `bool ssGetOutputPortTrivialOutputExprInRTW(SimStruct *S, int idx)`
- `bool ssGetOutputPortOutputExprInRTW(SimStruct *S, int idx)`

The set of generic expressions is a superset of the set of trivial expressions, and the set of trivial expressions is a superset of the set of constant expressions.

Therefore, when you query an output that has been set to be a constant expression with `ssGetOutputPortTrivialOutputExprInRTW`, it returns `True`. A constant expression is considered a trivial expression, because it is a direct memory access that can be repeated without degrading the efficiency of the generated code.

Similarly, an output that has been configured to be a constant or trivial expression returns `True` when queried for its status as a generic expression.

Acceptance or Denial of Requests for Input Expressions

A block can request that its output be represented in code as an expression. Such a request can be denied if the destination block cannot accept expressions at its input port. Furthermore, conditions independent of the requesting block and its destination blocks can prevent acceptance of expressions.

This section discusses block-specific conditions under which requests for input expressions are denied. For information on other conditions that prevent acceptance of expressions, see “Generic Conditions for Denial of Requests to Output Expressions” on page 10-63.

A block should not be configured to accept expressions at its input port under the following conditions:

- The block must take the address of its input data. It is not possible to take the address of most types of input expressions.
- The code generated for the block references the input more than once (for example, the Abs or Max blocks). This would lead to duplication of a potentially complex expression and a subsequent degradation of code efficiency.

If a block refuses to accept expressions at an input port, then any block that is connected to that input port is not permitted to output a generic or trivial expression.

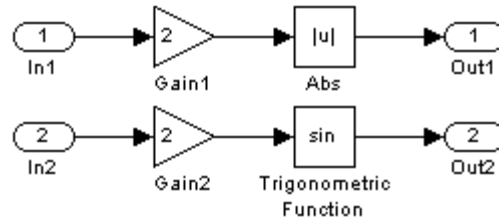
A request to output a constant expression is never denied, because there is no performance penalty for a constant expression, and it is always possible to take the parameter's address.

Example: Acceptance and Denial of Expressions at Block Inputs

This example shows how various built-in blocks handle requests to accept different categories of expressions at their inputs.

The following sample model contains

- Two Gain blocks. Gain blocks request their destination blocks to accept generic expressions.
- An Abs block. This block always denies expressions at its input port. The Abs block code uses the macro `rt_ABS(u)`, which evaluates the input `u` twice. (See the TLC implementation of the Abs block in `matlabroot/rtw/c/tlc/blocks/absval.tlc`.)
- A Trigonometric Function block. This block accepts expressions at its input port.



The Gain1 block's request to output an expression is denied by the Abs block. The Gain2 block's request to output an expression is accepted by the Trigonometric Function block.

The generated code is shown in the code excerpt below. The output of the Gain1 block is stored in the temporary variable `rtb_Gain1`, rather than generating an input expression to the Abs block.

```
void MdlOutputs(int_T tid)
{
  /* local block i/o variables */
  real_T rtb_Gain1;

  /* Gain: '<Root>/Gain1' incorporates:
   *   Inport: '<Root>/In1'
   *
   * Regarding '<Root>/Gain':
   *   Gain value: 2.0
   */
  rtb_Gain1 = rtU.In1 * 2.0;

  /* Output: '<Root>/Out1' incorporates:
   *   Abs: '<Root>/Abs'
   */
  rtY.Out1 = rt_ABS(rtb_Gain1);

  /* Output: '<Root>/Out2' incorporates:
   *   Trigonometry: '<Root>/Trigonometric Function'
   *   Gain: '<Root>/Gain2'
  */
}
```

```
*   Inport: '<Root>/In2'  
*  
*   Regarding '<Root>/Gain2':  
*   Gain value: 2.0  
*/  
rtY.Out2 = sin((2.0 * rtU.In2));  
}
```

Using the S-Function API to Specify Input Expression Acceptance

The S-Function API provides macros that let you

- Specify whether a block input should accept nonconstant expressions (that is, trivial or generic expressions)
- Query whether a block input accepts nonconstant expressions

By default, block inputs do not accept nonconstant expressions.

You should call the macros in your `mdlSetWorkWidths` function. The macros have the following arguments:

- `SimStruct *S`: pointer to the block's `SimStruct`.
- `int idx`: zero-based index of the input port.
- `bool value`: pass in `TRUE` if the port accepts input expressions; otherwise pass in `FALSE`.

The macro available for specifying whether or not a block input should accept a nonconstant expression is as follows:

```
void ssSetInputPortAcceptExprInRTW(SimStruct *S, int portIdx, bool value)
```

The corresponding macro available for querying the status set by any prior calls to `ssSetInputPortAcceptExprInRTW` is as follows:

```
bool ssGetInputPortAcceptExprInRTW(SimStruct *S, int portIdx)
```

Generic Conditions for Denial of Requests to Output Expressions

Even after a specific block requests that it be allowed to generate an output expression, that request can be denied, for generic reasons. These reasons include, but are not limited to

- The output expression is nontrivial, and the output has multiple destinations.
- The output expression is nonconstant, and the output is connected to at least one destination that does not accept expressions at its input port.
- The output is a test point.
- The output has been assigned an external storage class.
- The output must be stored using global data (for example is an input to a merge block or a block with states).
- The output signal is complex.

You do not need to consider these generic factors when deciding whether or not to utilize expression folding for a particular block. However, these rules can be helpful when you are examining generated code and analyzing cases where the expression folding optimization is suppressed.

Utilizing Expression Folding in Your TLC Block Implementation

To take advantage of expression folding, you must modify the TLC block implementation of an inlined S-Function such that it informs Simulink whether it generates or accepts expressions at its

- Input ports, as explained in “Using the S-Function API to Specify Input Expression Acceptance” on page 10-62.
- Output ports, as explained in “Categories of Output Expressions” on page 10-54.

This section discusses required modifications to the TLC implementation.

Expression Folding Compliance

In the `BlockInstanceSetup` function of your S-function, you must ensure that your block registers that it is compliant with expression folding. If you fail to do this, any expression folding requested or allowed at the block's outputs or inputs will be disabled, and temporary variables will be used.

To register expression folding compliance, call the TLC library function

```
%LibBlockSetIsExpressionCompliant (block)
```

You can conditionally disable expression folding at the inputs and outputs of a block by making the call to this function conditionally.

If you have overridden one of the TLC block implementations provided by the Real-Time Workshop product with your own implementation, you should not make the preceding call until you have updated your implementation, as described by the guidelines for expression folding in the following sections.

Outputting Expressions

The `BlockOutputSignal` function is used to generate code for a scalar output expression or one element of a nonscalar output expression. If your block outputs an expression, you should add a `BlockOutputSignal` function. The prototype of the `BlockOutputSignal` is

```
%function BlockOutputSignal(block,system,portIdx,ucv,lcu,idx,retType) void
```

The arguments to `BlockOutputSignal` are as follows:

- `block`: the record for the block for which an output expression is being generated
- `system`: the record for the system containing the block
- `portIdx`: zero-based index of the output port for which an expression is being generated
- `ucv`: user control variable defining the output element for which code is being generated
- `lcu`: loop control variable defining the output element for which code is being generated

- `idx`: signal index defining the output element for which code is being generated
- `retType`: string defining the type of signal access desired:
 - "Signal" specifies the contents or address of the output signal.
 - "SignalAddr" specifies the address of the output signal

The `BlockOutputSignal` function returns an appropriate text string for the output signal or address. The string should enforce the precedence of the expression by using opening and terminating parentheses, unless the expression consists of a function call. The address of an expression can only be returned for a constant expression; it is the address of the parameter whose memory is being accessed. The code implementing the `BlockOutputSignal` function for the Constant block is shown below.

```
%% Function: BlockOutputSignal =====
%% Abstract:
%%     Return the appropriate reference to the parameter. This function *may*
%%     be used by Simulink when optimizing the Block IO data structure.
%%
%function BlockOutputSignal(block,system,portIdx,ucv,lcx,idx,retType) void
    %switch retType
        %case "Signal"
            %return LibBlockParameter(Value,ucv,lcx,idx)
        %case "SignalAddr"
            %return LibBlockParameterAddr(Value,ucv,lcx,idx)
        %default
            %assign errTxt = "Unsupported return type: %<retType>"
            %<LibBlockReportError(block,errTxt)>
    %endswitch
%endfunction
```

The code implementing the `BlockOutputSignal` function for the Relational Operator block is shown below.

```
%% Function: BlockOutputSignal =====
%% Abstract:
%%     Return an output expression. This function *may*
%%     be used by Simulink when optimizing the Block IO data structure.
%%
```

```

%function BlockOutputSignal(block,system,portIdx,ucv,lcx,idx,retType) void
    %switch retType
    %case "Signal"
    %assign logicOperator = ParamSettings.Operator
    %if ISEQUAL(logicOperator, "-=")
    %assign op = "!="
    elseif ISEQUAL(logicOperator, "==") %assign op = "=="
    %else
    %assign op = logicOperator
    %endif
    %assign u0 = LibBlockInputSignal(0, ucv, lcv, idx)
    %assign u1 = LibBlockInputSignal(1, ucv, lcv, idx)
    %return "(%<u0> %<op> %<u1>)"
    %default
    %assign errTxt = "Unsupported return type: %<retType>"
    %<LibBlockReportError(block,errTxt)>
    %endswitch
%endfunction

```

Expression Folding for Blocks with Multiple Outputs

When a block has a single output, the Outputs function in the block's TLC file is called only if the output port is not an expression. Otherwise, the BlockOutputSignal function is called.

If a block has multiple outputs, the Outputs function is called if any output port is not an expression. The Outputs function should guard against generating code for output ports that are expressions. This is achieved by guarding sections of code corresponding to individual output ports with calls to LibBlockOutputSignalIsExpr().

For example, consider an S-Function with two inputs and two outputs, where

- The first output, y0, is equal to two times the first input.
- The second output, y1, is equal to four times the second input.

The Outputs and BlockOutputSignal functions for the S-function are shown in the following code excerpt.

```

%% Function: BlockOutputSignal =====

```

```

%% Abstract:
%%     Return an output expression.  This function *may*
%%     be used by Simulink when optimizing the Block IO data structure.
%%
%function BlockOutputSignal(block,system,portIdx,ucv,lcx,idx,retType) void
%switch retType
%assign u = LibBlockInputSignal(portIdx, ucv, lcx, idx)
%case "Signal"
%if portIdx == 0
%return "(2 * %<u>)"
%elseif portIdx == 1
%return "(4 * %<u>)"
%endif
%default
%assign errTxt = "Unsupported return type: %<retType>"
%<LibBlockReportError(block,errTxt)>
%endswitch
%endfunction
%%
%% Function: Outputs =====
%% Abstract:
%%     Compute output signals of block
%%
%function Outputs(block,system) Output
%assign rollVars = ["U", "Y"]
%roll sigIdx = RollRegions, lcx = RollThreshold, block, "Roller", rollVars
%assign u0 = LibBlockInputSignal(0, "", lcx, sigIdx)
%assign u1 = LibBlockInputSignal(1, "", lcx, sigIdx)
%assign y0 = LibBlockOutputSignal(0, "", lcx, sigIdx)
%assign y1 = LibBlockOutputSignal(1, "", lcx, sigIdx)
%if !LibBlockOutputSignalIsExpr(0)
%<y0> = 2 * %<u0>;
%endif
%if !LibBlockOutputSignalIsExpr(1)
%<y1> = 4 * %<u1>;
%endif
%endroll
%endfunction

```

Comments for Blocks That Are Expression-Folding-Compliant

In the past, all blocks preceded their outputs code with comments of the form

```
/* %<Type> Block: %<Name> */
```

When a block is expression-folding-compliant, the initial line shown above is generated automatically. You should not include the comment as part of the block's TLC implementation. Additional information should be registered using the `LibCacheBlockComment` function.

The `LibCacheBlockComment` function takes a string as an input, defining the body of the comment, except for the opening header, the final newline of a single or multiline comment, and the closing trailer.

The following TLC code illustrates registering a block comment. Note the use of the function `LibBlockParameterForComment`, which returns a string, suitable for a block comment, specifying the value of the block parameter.

```
%openfile commentBuf
$c(*) Gain value: %<LibBlockParameterForComment(Gain)>
%closefile commentBuf
%<LibCacheBlockComment(block, commentBuf)>
```


Writing S-Functions That Specify Sample Time Inheritance Rules

For Simulink to accurately determine whether a model can inherit a sample time, the S-functions in the model need to specify how they use sample times. You can specify this information by calling the macro `ssSetModelReferenceSampleTimeInheritanceRule` from `mdlInitializeSizes` or `mdlSetWorkWidths`. To use this macro:

1 Check whether the S-function calls any of the following macros:

- `ssGetSampleTime`
- `ssGetInputPortSampleTime`
- `ssGetOutputPortSampleTime`
- `ssGetInputPortOffsetTime`
- `ssGetOutputPortOffsetTime`
- `ssGetSampleTimePtr`
- `ssGetInputPortSampleTimeIndex`
- `ssGetOutputPortSampleTimeIndex`
- `ssGetSampleTimeTaskID`
- `ssGetSampleTimeTaskIDPtr`

2 Check for the following in your S-function TLC code:

- `LibBlockSampleTime`
- `CompiledModel.SampleTime`
- `LibBlockInputSignalSampleTime`
- `LibBlockInputSignalOffsetTime`
- `LibBlockOutputSignalSampleTime`
- `LibBlockOutputSignalOffsetTime`

3 Depending on your search results, use `ssSetModelReferenceSampleTimeInheritanceRule` as indicated in the following table.

If...	Use...
None of the macros or functions are present, the S-function does not preclude the model from inheriting a sample time.	<pre>ssSetModelReferenceSampleTimeInheritanceRule (S, USE_DEFAULT_FOR_DISCRETE_INHERITANCE)</pre>
Any of the macros or functions are used for <ul style="list-style-type: none"> • Throwing errors if sample time is inherited, continuous, or constant • Checking <code>ssIsSampleHit</code> • Checking whether sample time is inherited in either <code>mdlSetInputPortSampleTime</code> or <code>mdlSetOutputPortSampleTime</code> before setting 	<pre>ssSetModelReferenceSampleTimeInheritanceRule... (S,USE_DEFAULT_FOR_DISCRETE_INHERITANCE)</pre>
The S-function uses its sample time for computing parameters, outputs, and so on	<pre>ssSetModelReferenceSampleTimeInheritanceRule (S, DISALLOW_SAMPLE_TIME_INHERITANCE)</pre>

Note If an S-function does not set the `ssSetModelReferenceSampleTimeInheritanceRule` macro, by default Simulink assumes that the S-function does not preclude the model containing that S-function from inheriting a sample time. However, Simulink issues a warning indicating that the model includes S-functions for which this macro is not set.

You can use settings on the **Diagnostics/Solver** pane of the Configuration Parameters dialog box or Model Explorer to control how Simulink responds when it encounters S-functions that have unspecified sample time inheritance rules. Toggle the **Unspecified inheritability of sample time** diagnostic to none, warning, or error. The default is warning.

Writing S-Functions That Support Code Reuse

The Real-Time Workshop *code reuse* feature generates code for a subsystem in the form of a single function that is invoked wherever the subsystem occurs in the model (see “Nonvirtual Subsystem Code Generation” on page 4-2). If a subsystem contains S-functions, the S-functions must be compatible with the code reuse feature. Otherwise, the code generator might not generate reusable code from the subsystem or might generate incorrect code.

If you want your S-function to support the subsystem code reuse feature, you must ensure that the S-function meets the following requirements:

- The S-function must be inlined.
- Code generated from the S-function must not use static variables.
- The TLC code that generates the inlined S-function code must not use the `BlockInstanceData` function.
- The S-function must initialize its pointer work vector in `mdlStart` and not before.
- The S-function must not be a sink that logs data to the workspace.
- The S-function must register its parameters as run-time parameters in `mdlSetWorkWidths`. (It must not use `ssWriteRTWParameters` in its `mdlRTW` function for this purpose.)
- The S-function must not be a device driver.

In addition to meeting the preceding requirements, your S-function must set the `SS_OPTION_WORKS_WITH_CODE_REUSE` flag (see the description of `ssSetOptions` in the Simulink Writing S-Function documentation). This flag assures the code generator that your S-function meets the requirements for subsystem code reuse.

Writing S-Functions for Multirate Multitasking Environments

In this section...

“Introduction” on page 10-72

“Rate Grouping Support in S-Functions” on page 10-72

“Creating Multitasking-Safe, Multirate, Port-Based Sample Time S-Functions” on page 10-73

Introduction

S-functions can be used in models with multiple sample rates and deployed in multitasking target environments. Likewise, S-functions themselves can have multiple rates at which they operate. Real-Time Workshop Embedded Coder generates code for multirate multitasking models using an approach called *rate grouping*. In code generated for ERT-based targets, rate grouping generates separate *model_step* functions for the base rate task and each subrate task in the model. Although rate grouping is a code generation feature found in ERT targets only, your S-functions can use it in other contexts when you code them as explained below.

Rate Grouping Support in S-Functions

To take advantage of rate grouping, you must inline your multirate S-functions if you have not done so. You need to follow certain Target Language Compiler protocols to exploit rate grouping. Coding TLC to exploit rate grouping does not prevent your inlined S-functions from functioning properly in GRT. Likewise, your inlined S-functions will still generate valid ERT code even if you do not make them rate-grouping-compliant. If you do so, however, they will generate more efficient code for multirate models.

For instructions and examples of Target Language Compiler code illustrating how to create and upgrade S-functions to generate rate-grouping-compliant code, see “Rate Grouping Compliance and Compatibility Issues” in the Real-Time Workshop Embedded Coder documentation.

For each multirate S-function that is not rate grouping-compliant, Real-Time Workshop issues the following warning when you build:

```
Warning: Real-Time Workshop: Code of output function for multirate block
'<Root>/S-Function' is guarded by sample hit checks rather than being rate
grouped. This will generate the same code for all rates used by the block,
possibly generating dead code. To avoid dead code, you must update the TLC
file for the block.
```

You will also find a comment such as the following in code generated for each noncompliant S-function:

```
/* Because the output function of multirate block
<Root>/S-Function is not rate grouped,
the following code might contain unreachable blocks of code.
To avoid this, you must update your block TLC file. */
```

The words “update function” are substituted for “output function” in these warnings, as appropriate.

Creating Multitasking-Safe, Multirate, Port-Based Sample Time S-Functions

The following instructions show how to support both data determinism and data integrity in multirate S-functions. They do not cover cases where there is no determinism nor integrity. Support for frame-based processing does not affect the requirements.

Note The slow rates must be multiples of the fastest rate. The instructions do not apply when two rates being interfaced are not multiples or when the rates are not periodic.

Rules for Properly Handling Fast-to-Slow Transitions

The rules that multirate S-functions should observe for inputs are

- The input should only be read at the rate that is associated with the input port sample time.
- Generally, the input data is written to DWork, and the DWork can then be accessed at the slower (downstream) rate.

The input can be read at every sample hit of the input rate and written into DWork memory, but this DWork memory cannot then be directly accessed by the slower rate. Any DWork memory that will be read by the slow rate must only be written by the fast rate when there is a *special sample hit*. A special sample hit occurs when both this input port rate and rate to which it is interfacing have a hit. Depending on their requirements and design, algorithms can process the data in several locations.

The rules that multirate S-functions should observe for outputs are

- The output should not be written by any rate other than the rate assigned to the output port, except in the optimized case described below.
- The output should always be written when the sample rate of the output port has a hit.

If these conditions are met, the S-Function block can always safely specify that the input port and output port can both be made local and reusable.

You can include an optimization when little or no processing needs to be done on the data. In such cases, the input rate code can directly write to the output (instead of by using DWork) when there is a special sample hit. If you do this, however, you must declare the output port to be *global* and *not reusable*. This optimization results in one less memcopy but does introduce nonuniform processing requirements on the faster rate.

Whether you use this optimization or not, the most recent input data, as seen by the slower rate, is always the value when both the faster and slower rate had their hits (and possible earlier input data as well, depending on the algorithm). Any subsequent steps by the faster rate and the associated input data updates are not seen by the slower rate until the next hit for the slow rate occurs.

Pseudocode Examples of Fast-to-Slow Rate Transition

The pseudocode below abstracts how you should write your C-mex code to handle fast-to-slow transitions, illustrating with an input rate of 0.1 second driving an output rate of one second. A similar approach can be taken when inlining the code. The block has following characteristics:

- File: `sfun_multirate_zoh.c`, Equation: $y = u(\text{tslow})$
- Input: local and reusable
- Output: local and reusable
- DirectFeedthrough: yes

```
OutputFcn
if (ssIsSampleHit(".1")) {
    if (ssIsSpecialSampleHit("1")) {
        DWork = u;
    }
}
if (ssIsSampleHit("1")) {
    y = DWork;
}
```

An alternative, slightly optimized approach for simple algorithms:

- Input: local and reusable
- Output: global and not reusable because it needs to persist between special sample hits
- DirectFeedthrough: yes

```
OutputFcn
if (ssIsSampleHit(".1")) {
    if (ssIsSpecialSampleHit("1")) {
        y = u;
    }
}
```

Example adding a simple algorithm:

- File: `sfun_multirate_avg.c`; Equation: $y = \text{average}(u)$

- Input: local and reusable
- Output: local and reusable
- DirectFeedthrough: yes

(Assume DWork[0:10] and DWork[mycounter] are initialized to zero)

```
OutputFcn
if (ssIsSampleHit(".1")) {
    /* In general, processing on 'u' could be done here,
       it runs on every hit of the fast rate. */
    DWork[DWork[mycounter]++] = u;
    if (ssIsSpecialSampleHit("1")) {
        /* In general, processing on DWork[0:10] can be done
           here, but it does cause the faster rate to have
           nonuniform processing requirements (every 10th hit,
           more code needs to be run).*/
        DWork[10] = sum(DWork[0:9])/10;
        DWork[mycounter] = 0;
    }
}
if (ssIsSampleHit("1")) {
    /* Processing on DWork[10] can be done here before
       outputting. This code runs on every hit of the
       slower task. */
    y = DWork[10];
}
```

Rules for Properly Handling Slow-to-Fast Transitions

When output rates are faster than input rates, input should only be read at the rate that is associated with the input port sample time, observing the following rules:

- Always read input from the update function.
- Use no special sample hit checks when reading input.
- Write the input to a DWork.

- When there is a special sample hit between the rates, copy the DWork into a second DWork in the output function.
- Write the second DWork to the output at every hit of the output sample rate.

The block can request that the input port be made local but it cannot be set to reusable. The output port can be set to local and reusable.

As in the fast-to-slow transition case, the input should not be read by any rate other than the one assigned to the input port. Similarly, the output should not be written to at any rate other than the rate assigned to the output port.

An optimization can be made when the algorithm being implemented is only required to run at the slow rate. In such cases, only one DWork is needed. The input still writes to the DWork in the update function. When there is a special sample hit between the rates, the output function copies the same DWork directly to the output. You must set the output port to be global and not reusable in this case. This optimization results in one less memcopy operation per special sample hit.

In either case, the data that the fast rate computations operate on is always delayed, that is, the data is from the previous step of the slow rate code.

Pseudocode Examples of Slow-to-Fast Rate Transition

The pseudocode below abstracts what your S-function needs to do to handle slow-to-fast transitions, illustrating with an input rate of one second driving an output rate of 0.1 second. The block has following characteristics:

- File: `sfun_multirate_delay.c`, Equation: $y = u(\text{tslow}-1)$
- Input: Set to local, will be local if output/update are combined (ERT) otherwise will be global. Set to not reusable because input needs to be preserved until the update function runs.
- Output: local and reusable
- DirectFeedthrough: no

```
OutputFcn
if (ssIsSampleHit(".1")) {
    if (ssIsSpecialSampleHit("1")) {
```

```

        DWork[1] = DWork[0];
    }
    y = DWork[1];
}
UpdateFcn
if (ssIsSampleHit("1")) {
    DWork[0] = u;
}

```

An alternative, optimized approach can be used by some algorithms:

- Input: Set to local, will be local if output/update are combined (ERT) otherwise will be global. Set to not reusable because input needs to be preserved until the update function runs.
- Output: global and not reusable because it needs to persist between special sample hits.
- DirectFeedthrough: no

```

OutputFcn
if (ssIsSampleHit(".1")) {
    if (ssIsSpecialSampleHit("1")) {
        y = DWork;
    }
}
UpdateFcn
if (ssIsSampleHit("1")) {
    DWork = u;
}

```

Example adding a simple algorithm:

- File: `sfun_multirate_modulate.c`, Equation: $y = \sin(\text{tfast}) + u(\text{tslow}-1)$
- Input: Set to local, will be local if output/update are combined (an ERT feature) otherwise will be global. Set to not reusable because input needs to be preserved until the update function runs.
- Output: local and reusable
- DirectFeedthrough: no

```
OutputFcn
if (ssIsSampleHit(".1") {
    if (ssIsSpecialSampleHit("1") {
        /* Processing not likely to be done here. It causes
        * the faster rate to have nonuniform processing
        * requirements (every 10th hit, more code needs to
        * be run).*/
        DWork[1] = DWork[0];
    }
    /* Processing done at fast rate */
    y = sin(ssGetTaskTime(".1")) + DWork[1];
}
UpdateFcn
if (ssIsSampleHit("1")) {
    /* Processing on 'u' can be done here. There is a delay of
    one slow rate period before the fast rate sees it.*/
    DWork[0] = u;}
```

Integrating C and C++ Code

Real-Time Workshop includes a variety of mechanisms for integrating generated code with legacy or custom code. A summary of these mechanisms is available in “Integrating Legacy and Custom Code” on page 2-129.

If you need to integrate legacy or custom C code with generated C++ code or vice versa, you must modify your legacy or custom code to be language compatible with the generated code. Options for making the code language compatible include

- Writing or rewriting the legacy or custom code in the same language as the generated code.
- If the generated code is in C++ and your legacy or custom code is in C, for each C function, create a header file that prototypes the function, using the following format:

```
#ifdef __cplusplus
extern "C" {
#endif
int my_c_function_wrapper();
#ifdef __cplusplus
}
#endif
```

The prototype serves as a function wrapper. The value `__cplusplus` is defined if your compiler supports C++ code. The linkage specification `extern "C"` specifies C linkage with no name mangling.

- If the generated code is in C and your legacy or custom code is in C++, include an `extern "C"` linkage specification in each `.cpp` file. For example, the following shows a portion of C++ code in the file `my_func.cpp`:

```
extern "C" {

int my_cpp_function()
{
    ...
}
}
```

Build Support for S-Functions

In this section...
“Introduction” on page 10-81
“Implicit Build Support” on page 10-82
“Specifying Additional Source Files for an S-Function” on page 10-82
“Using TLC Library Functions” on page 10-84
“Using the rtwmakecfg.m API” on page 10-84

Introduction

User-written S-Function blocks provide a powerful way to incorporate legacy and custom code into the Simulink and Real-Time Workshop development environment. In most cases, you should use S-functions to integrate existing code with code generated by Real-Time Workshop. Several approaches to writing S-functions are available as discussed in

- “Writing Noninlined S-Functions” on page 10-9
- “Writing Wrapper S-Functions” on page 10-11
- “Writing Fully Inlined S-Functions” on page 10-22
- “Writing Fully Inlined S-Functions with the mdlRTW Routine” on page 10-27
- “Writing S-Functions That Support Code Reuse” on page 10-71
- “Writing S-Functions for Multirate Multitasking Environments” on page 10-72

S-functions also provide the most flexible and capable way of including build information for legacy and custom code files in the Real-Time Workshop build process.

This section discusses the different ways of adding S-functions to the Real-Time Workshop build process.

Implicit Build Support

When building models with S-functions, Real-Time Workshop automatically adds the appropriate rules, include paths, and source filenames to the generated makefile. For this to occur, the source files (.h, .c, and .cpp) for the S-function must be in the same directory as the S-function MEX-file. Real-Time Workshop propagates this information through the token expansion mechanism of converting a template make file (TMF) to a makefile. The propagation requires the TMF to support the appropriate tokens.

Details of the implicit build support follow:

- If the file *sfcname.h* exists in the same directory as the S-function MEX-file (for example, *sfcname.mexext*), the directory is added to the include path.
- If the file *sfcname.c* or *sfcname.cpp* exists in the same directory as the S-function MEX-file, Real-Time Workshop adds a makefile rule for compiling files from that directory.
- When an S-function is not inlined with a TLC file, Real-Time Workshop must compile the S-function's source file. To determine the name of the source file to add to the list of files to compile, Real-Time Workshop searches for *sfcname.cpp* on the MATLAB path. If the source file is found, Real-Time Workshop adds the source filename to the makefile. If *sfcname.cpp* is not found on the path, Real-Time Workshop adds the filename *sfcname.c* to the makefile, whether or not it is on the MATLAB path.

Note For Simulink to find the MEX-file for simulation and code generation, it must exist on the MATLAB path or be in your current working directory in MATLAB.

Specifying Additional Source Files for an S-Function

If your S-function has additional source file dependencies, you must add the names of the additional modules to the build process. You can do this by specifying the filenames

- In the **S-function modules** field of the S-Function block parameter dialog box
- With the `SFunctionModules` parameter in a call to the `set_param` function

For example, suppose you build your S-function with multiple modules, as in

```
mex sfun_main.c sfun_module1.c sfun_module2.c
```

You can then add the modules to the build process by doing one of the following:

- Specifying `sfun_main`, `sfun_module1`, and `sfun_module2` in the **S-function modules** field in the S-Function block dialog box
- Entering the following command at the MATLAB command prompt:

```
set_param(sfun_block, 'SFunctionModules', 'sfun_module1 sfun_module2')
```

Alternatively, you can define a variable to represent the parameter value.

```
modules = 'sfun_module1 sfun_module2'  
set_param(sfun_block, 'SFunctionModules', modules)
```

Note The **S-function modules** field and `SFunctionModules` parameter do not support complete source file path specifications. To use the parameter, Real-Time Workshop must be able to find the additional source files when executing the makefile. To ensure that Real-Time Workshop can locate the additional files, place them in the same directory as the S-function MEX-file. This will enable you to leverage the implicit build support discussed in “Implicit Build Support” on page 10-82.

For more complicated S-function file dependencies, such as specifying source files in other locations or specifying libraries or object files, use the `rtwmakecfg.m` API, as explained in “Using the `rtwmakecfg.m` API” on page 10-84.

Using TLC Library Functions

If you inline your S-function by writing a TLC file, you can add source filenames to the build process by using the TLC library function `LibAddToModelSources`. For details, see “`LibAddSourceFileCustomSection` (file, builtInSection, newSection)” in the Target Language Compiler documentation.

Note This function does not support complete source file path specifications and assumes Real-Time Workshop can find the additional source files when executing the makefile.

Another useful TLC library function is `LibAddToCommonIncludes`. Use this function in a `#include` statement to include S-function header files in the generated `model.h` header file. For details, see “`LibAddToCommonIncludes`(incFileName)” in the Target Language Compiler documentation.

For more complicated S-function file dependencies, such as specifying source files in other locations or specifying libraries or object files, use the `rtwmakecfg.m` API, as explained in “Using the `rtwmakecfg.m` API” on page 10-84.

Using the `rtwmakecfg.m` API

Real-Time Workshop TMFs provide tokens that let you add the following items to generated makefiles:

- Source directories
- Include directories
- Run-time library names
- Run-time module objects

S-functions can add this information to the makefile by using an `rtwmakecfg.m` M-file function. This function is particularly useful when building a model that contains one or more of your S-Function blocks, such as device driver blocks.

To add information pertaining to an S-function to the makefile,

- 1 Create the M-file function `rtwmakecfg` in a file `rtwmakecfg.m`. Real-Time Workshop associates this file with your S-function based on its directory location. “Creating the `rtwmakecfg.m` M-File Function” on page 10-85 discusses the requirements for the `rtwmakecfg` function and the data it should return.
- 2 Modify your target’s TMF such that it supports macro expansion for the information returned by `rtwmakecfg` functions. “Modifying the TMF” on page 10-88 discusses the required modifications.

After the TLC phase of the build process, when generating a makefile from the TMF, Real-Time Workshop searches for an `rtwmakecfg.m` file in the directory that contains the S-function component. If it finds the file, Real-Time Workshop calls the `rtwmakecfg` function.

Creating the `rtwmakecfg.m` M-File Function

Create the `rtwmakecfg.m` M-file function in the same directory as your S-function component (`sfcname.mexext` on Windows and `sfcname` and a platform-specific extension on UNIX). The function must return a structured array that contains the following fields:

Field	Description
<code>makeInfo.includePath</code>	A cell array that specifies additional include directory names, organized as a row vector. Real-Time Workshop expands the directory names into include instructions in the generated makefile.
<code>makeInfo.sourcePath</code>	A cell array that specifies additional source directory names, organized as a row vector. Real-Time Workshop expands the directory names into make rules in the generated makefile.

Field	Description
<code>makeInfo.sources</code>	A cell array that specifies additional source filenames (C or C++), organized as a row vector. Real-Time Workshop expands the filenames into make variables that contain the source files. You should specify only filenames (with extension). Specify path information with the <code>sourcePath</code> field.
<code>makeInfo.linkLibsObjs</code>	A cell array that specifies additional, fully qualified paths to object or library files against which Real-Time Workshop should link. Real-Time Workshop does not compile the specified objects and libraries. However, it includes them when linking the final executable. This can be useful for incorporating libraries that you do not want Real-Time Workshop to recompile or for which the source files are not available. You might also use this element to incorporate source files from languages other than C and C++. This is possible if you first create a C compatible object file or library outside of the Real-Time Workshop build process.
<code>makeInfo.precompile</code>	A Boolean flag that indicates whether the libraries specified in the <code>rtwmakecfg.m</code> file exist in a specified location (<code>precompile==1</code>) or if the libraries need to be created in the build directory during the Real-Time Workshop build process (<code>precompile==0</code>).
<code>makeInfo.library</code>	A structure array that specifies additional run-time libraries and module objects, organized as a row vector. Real-Time Workshop expands the information into make rules in the generated makefile. See the next table for a list of the library fields.

The `makeInfo.library` field consists of the following elements:

Element	Description
<code>makeInfo.library(n).Name</code>	A character array that specifies the name of the library (without an extension).

Element	Description
makeInfo.library(n).Location	A character array that specifies the directory in which the library is located when precompiled. See the description of makeInfo.precompile in the preceding table for more information. A target can use the TargetPreCompLibLocation parameter to override this value. See “Specifying the Location of Precompiled Libraries” on page 2-113 for details.
makeInfo.library(n).Modules	A cell array that specifies the C or C++ source file base names (without an extension) that comprise the library. Do not include the file extension. The makefile appends the appropriate object extension.

Note The makeInfo.library field must fully specify each library and how to build it. The modules list in the makeInfo.library(n).Modules element cannot be empty. If you need to specify a link-only library, use the makeInfo.linkLibsObjs field instead.

Example:

```

disp(['Running rtwmakecfg from directory: ',pwd]);
makeInfo.includePath = { fullfile(pwd, 'somedir2') };
makeInfo.sourcePath = {fullfile(pwd, 'somedir2'), fullfile(pwd, 'somedir3')};
makeInfo.sources = { 'src1.c', 'src2.cpp'};
makeInfo.linkLibsObjs = { fullfile(pwd, 'somedir3', 'src3.object'),...
                        fullfile(pwd, 'somedir4', 'mylib.library')};

makeInfo.precompile = 1;
makeInfo.library(1).Name = 'myprecompiledlib';
makeInfo.library(1).Location = fullfile(pwd, 'somedir2', 'lib');
makeInfo.library(1).Modules = {'srcfile1' 'srcfile2' 'srcfile3' };

```

Note If a path that you specify in the `rtwmakecfg.m` API contains spaces, Real-Time Workshop does not automatically convert the path to its non-space equivalent. If the build environments you intend to support do not support spaces in paths, use the utility command `rtw_alt_pathname` to convert them as explained in “Enabling Real-Time Workshop to Build When Pathnames Contain Spaces” on page 2-17.

For example:

```
makeInfo.includePath = {rtw_alt_pathname(fullfile(pwd, 'somedir2'))};
```

Modifying the TMF

To expand the information generated by an `rtwmakecfg` function, you must modify the following sections of your target’s TMF:

- Include Path
- Additional Libraries
- Rules

If you use the `ADD_INCLUDES` macro to add include paths, you must also add `ADD_INCLUDES` to the TMF’s `INCLUDE` line.

The example code excerpts below may not be appropriate for your make utility. For additional examples, see the GRT or ERT TMFs located in `matlabroot/rtw/c/grt/*.tmf` or `matlabroot/rtw/c/ert/*.tmf`.

Example — adding directory names to the include path:

```
ADD_INCLUDES = \  
|>START_EXPAND_INCLUDES<| -I|>EXPAND_DIR_NAME<| \  
|>END_EXPAND_INCLUDES<|
```

Example — adding `ADD_INCLUDES` to the `INCLUDES` line:

```
INCLUDES = \  
-I. -I.. $(MATLAB_INCLUDES) $(ADD_INCLUDES) $(USER_INCLUDES)
```

Example — adding library names to the makefile:

```
LIBS =
|>START_PRECOMP_LIBRARIES<|
LIBS += |>EXPAND_LIBRARY_NAME<|.a |>END_PRECOMP_LIBRARIES<|
|>START_EXPAND_LIBRARIES<|
LIBS += |>EXPAND_LIBRARY_NAME<|.a |>END_EXPAND_LIBRARIES<|
```

Example — adding rules to the makefile:

```
: |>START_EXPAND_RULES<|
$(BLD)/%.o: |>EXPAND_DIR_NAME<|/%.c $(SRC)/$(MAKEFILE) rtw_proj.tmw
    @$ (BLANK)
    @echo ### "|>EXPAND_DIR_NAME<|\$*.c"
    $(CC) $(CFLAGS) $(APP_CFLAGS) -o $(BLD)$(DIRCHAR)$*.o
|>EXPAND_DIR_NAME<|$(DIRCHAR)$*.c > $(BLD)$(DIRCHAR)$*.lst
|>END_EXPAND_RULES<|

|>START_EXPAND_LIBRARIES<|MODULES_|>EXPAND_LIBRARY_NAME<| = \
|>START_EXPAND_MODULES<| |>EXPAND_MODULE_NAME<|.o \
|>END_EXPAND_MODULES<|

|>EXPAND_LIBRARY_NAME<|.a : $(MAKEFILE) rtw_proj.tmw
$(MODULES_|>EXPAND_LIBRARY_NAME<|:%.o=$(BLD)/%.o)
    @$ (BLANK)
    @echo ### Creating $@
    $(AR) -r $@
$(MODULES_|>EXPAND_LIBRARY_NAME<|:%.o=$(BLD)/%.o)
|>END_EXPAND_LIBRARIES<|

|>START_PRECOMP_LIBRARIES<|MODULES_|>EXPAND_LIBRARY_NAME<| = \
|>START_EXPAND_MODULES<| |>EXPAND_MODULE_NAME<|.o \
|>END_EXPAND_MODULES<|

|>EXPAND_LIBRARY_NAME<|.a : $(MAKEFILE) rtw_proj.tmw
$(MODULES_|>EXPAND_LIBRARY_NAME<|:%.o=$(BLD)/%.o)
    @$ (BLANK)
    @echo ### Creating $@
    $(AR) -r $@
```

```
$(MODULES_>EXPAND_LIBRARY_NAME<|:%.o=$(BLD)/%.o)  
|>END_PRECOMP_LIBRARIES<|
```

For more information on how to use configuration parameters to control library names and location during the build process, see “Controlling the Location and Naming of Libraries During the Build Process” on page 2-112.

Precompiling S-Function Libraries

You can precompile new or updated S-function libraries (MEX-files) for a model by using the M-file function `rtw_precompile_libs`. Using a specified model and a library build specification, this function builds and places the libraries in a precompiled library directory.

By precompiling S-function libraries, you can optimize system builds. Once your precompiled libraries exist, Real-Time Workshop can omit library compilation from subsequent builds. For models that use numerous libraries, the time savings for build processing can be significant.

To use `rtw_precompile_libs`,

- 1** Set the library file suffix, including the file type extension, based on the platform in use.
- 2** Set the precompiled library directory.
- 3** Define a build specification.
- 4** Issue a call to `rtw_precompile_libs`.

The following procedure explains these steps in more detail.

- 1** Set the library file suffix, including the file type extension, based on the platform in use.

Consider checking for the type of platform in use and then using the `TargetLibSuffix` parameter to set the library suffix accordingly. For example, you might set the suffix to `.a` for a UNIX platform and `_vc.lib` otherwise.

```
if isunix
```

```
        suffix = '.a';
    else
        suffix = '_vc.lib';
    end

    set_param(my_model, 'TargetLibSuffix', suffix);
```

2 Set the precompiled library directory.

Use one of the following methods to set the precompiled library directory.

- Set the `TargetPreCompLibLocation` parameter, as explained in “Specifying the Location of Precompiled Libraries” on page 2-113.
- Set the `makeInfo.precompile` field in an `rtwmakecfg` M-file function.

If you set both `TargetPreCompLibLocation` and `makeInfo.precompile`, the setting for `TargetPreCompLibLocation` takes precedence.

The following command sets the precompiled library directory for model `my_model` to directory `lib` under the current working directory.

```
set_param(my_model, 'TargetPreCompLibLocation', fullfile(pwd, 'lib'));
```

Note If you set both the target directory for the precompiled library files and a target library file suffix, Real-Time Workshop automatically detects whether any precompiled library files are missing while processing builds.

3 Define a build specification.

Set up a structure that defines a build specification. The following table describes fields you can define in the structure. All fields except `rtwmakecfgDirs` are optional.

Field	Description
rtwmakecfgDirs	<p>A cell array of strings that name the directories containing rtwmakecfg files for libraries to be precompiled. The function uses the Name and Location elements of makeInfo.library, as returned by rtwmakecfg, to specify the name and location of the precompiled libraries. If you set the TargetPreCompLibLocation parameter to specify the library directory, that setting overrides the makeInfo.library.Location setting.</p> <p>Note: The specified model must contain blocks that use precompiled libraries specified by the rtwmakecfg files. This is necessary because the TMF-to-makefile conversion generates the library rules only if the libraries are needed.</p>
libSuffix	<p>A string that specifies the suffix, including the file type extension, to be appended to the name of each library (for example, .a or _vc.lib). The string must include a period (.). You must set the suffix with either this field or the TargetLibSuffix parameter. If you specify a suffix with both mechanisms, the TargetLibSuffix setting overrides the setting of this field.</p>
intOnlyBuild	<p>A Boolean flag. When set to true, the flag indicates the libraries are to be optimized such that they are compiled from integer code only. This field applies to ERT targets only.</p>
makeOpts	<p>A string that specifies an option to be included in the rtwMake command line.</p>
addLibs	<p>A cell array of structures that specify libraries to be built that are not specified by an rtwmakecfg function. Each structure must be defined with two fields that are character arrays:</p> <ul style="list-style-type: none"> • libName — the name of the library without a suffix • libLoc — the location for the precompiled library <p>The TMF can specify other libraries and how those libraries are to be built. Use this field if you need to precompile those libraries.</p>

The following commands set up build specification build_spec, which indicates that the files to be compiled are in directory src under the current working directory.


```
build_spec = [];  
build_spec.rtwmakecfgDirs = {fullfile(pwd,'src')};
```

4 Issue a call to `rtw_precompile_libs`.

Issue a call to `rtw_precompile_libs` that specifies the model for which you want to build the precompiled libraries and the build specification. For example:

```
rtw_precompile_libs(my_model,build_spec);
```


S-Function Target

S-functions are an important class of target for which Real-Time Workshop can generate code. The ability to encapsulate a subsystem into an S-function allows you to increase its execution efficiency and shield its internal logic from inspection and modification.

The following sections describe the properties of S-function targets and demonstrate how to generate them. For more details on the structure of S-functions, see the Simulink Writing S-Functions documentation.

Introduction (p. 11-3)	Provides an overview of the S-function target and its applications
Creating an S-Function Block from a Subsystem (p. 11-6)	Explains how to extract a subsystem from a model and use it to generate a reusable S-function component; a step-by-step demonstration
Tunable Parameters in Generated S-Functions (p. 11-12)	Explains how to declare tunable parameters in generated S-functions and how they differ from those in other targets
Automated S-Function Generation (p. 11-15)	Presents step-by-step instructions for automatically generating an S-function from a subsystem
System Target File and Template Makefiles (p. 11-20)	Discusses control files used by the S-function target

Checksums and the S-Function Target (p. 11-21)

Explains how Real-Time Workshop uses checksums during the build process

S-Function Target Limitations (p. 11-22)

Discusses S-function target limitations.

Introduction

In this section...
“S-Function Target Overview” on page 11-3
“Intellectual Property Protection for S-Function in Simulation” on page 11-4
“Required Files for S-Function Deployment” on page 11-4
“Sample Time Propagation in Generated S-Functions” on page 11-5
“Choice of Solver Type” on page 11-5

S-Function Target Overview

Using the S-function target, you can build an S-function component and use it as an S-Function block in another model. The S-function code format used by the S-function target generates code that conforms to the Simulink C MEX S-function application programming interface (API). Applications of this format include

- Conversion of a model to a component. You can generate an S-Function block for a model, *m1*. Then, you can place the generated S-Function block in another model, *m2*. Regenerating code for *m2* does not require regenerating code for *m1*.
- Conversion of a subsystem to a component. By extracting a subsystem to a separate model and generating an S-Function block from that model, you can create a reusable component from the subsystem. See “Creating an S-Function Block from a Subsystem” on page 11-6 for an example of this procedure.
- Speeding up simulation. In many cases, an S-function generated from a model performs more efficiently than the original model.
- Code reuse. You can incorporate multiple instances of one model inside another without replicating the code for each instance. Each instance will continue to maintain its own unique data.

The S-function target generates noninlined S-functions. Within the same release, you can generate an executable from a model that contains generated S-functions by using the generic real-time or real-time malloc targets. This is

not supported when incorporating a generated S-function from one release into a model that you build with a different release.

You can place a generated S-Function block into another model from which you can generate another S-function format. This allows any level of nested S-functions.

You should avoid nesting S-functions in a model or subsystem having the same name as the S-function (possibly several levels apart). In such situations, the S-function can be called recursively. Real-Time Workshop currently does not detect such loops in S-function dependency, which can result in aborting or hanging MATLAB.

To prevent this from happening, you should be sure to name the subsystem or model to be generated as an S-function target uniquely, to avoid duplicating any existing MEX filenames on the MATLAB path.

Intellectual Property Protection for S-Function in Simulation

In addition to the technical applications of the S-function target listed above, you can use the S-function target to protect your designs and algorithms. By generating an S-function from a proprietary model or algorithm, you can share the model's functionality for simulation use without providing the source code. You need only provide the binary MEX-file object to users.

Required Files for S-Function Deployment

To deploy your generated S-Function block for inclusion in other models for simulation, you need only provide the binary MEX-file object that was generated in the current working directory when the S-Function block was created:

```
subsys_sf.mexext
```

where *subsys* is the subsystem name and *mexext* is a platform-dependent MEX-file extension (see *mexext*). For example, `SourceSubsys_sf.mexw32`.

To deploy your generated S-Function block for inclusion in other models for code generation, you must provide all of the files that were generated in the current working directory when the S-Function block was created:

- *subsys_sf.c* or *.cpp*, where *subsys* is the subsystem name (for example, *SourceSubsys_sf.c*)
- *subsys_sf.h*
- *subsys_sf.mexext*, where *mexext* is a platform-dependent MEX-file extension (see *mexext*)
- Subdirectory *subsys_sfcn_rtw* and its contents

Sample Time Propagation in Generated S-Functions

A generated S-Function block can inherit its sample time from the model in which it is placed if certain criteria are met. Six conditions that govern sample time propagation for S-functions and for the S-function code format are described in “Inheriting Sample Times” in the Simulink documentation. These conditions also apply to sample times propagated to Model blocks, and are further discussed in “Inherited Sample Time for Referenced Models” on page 4-40.

Choice of Solver Type

If the model containing the subsystem from which you generate an S-function uses a variable-step solver, the generated S-function contains zero-crossing functions and will work properly only in models that use variable-step solvers.

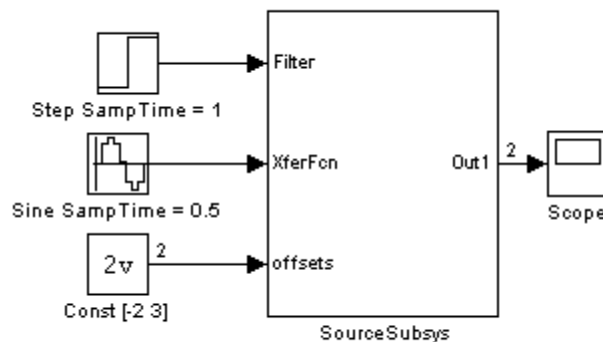
If the model containing the subsystem from which you generate an S-function uses a fixed-step solver, the generated S-function contains no zero-crossing functions and the generated S-function will work properly in models that use variable-step or fixed-step solvers.

Creating an S-Function Block from a Subsystem

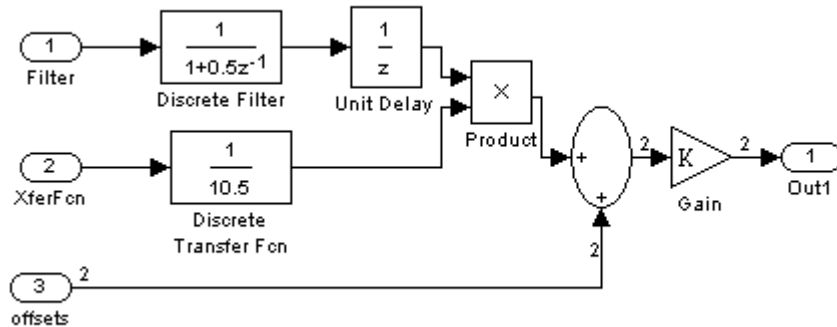
This section demonstrates how to extract a subsystem from a model and generate a reusable S-function component from it.

The next figure shows `SourceModel`, a simple model that inputs signals to a subsystem. The subsequent figure shows the subsystem, `SourceSubsys`. The signals, which have different widths and sample times, are

- A Step block with sample time 1
- A Sine Wave block with sample time 0.5
- A Constant block whose value is the vector [-2 3]



SourceModel



SourceSubsys

The objective is to extract SourceSubsys from the model and build an S-Function block from it, using the S-function target. The S-Function block must perform identically to the subsystem from which it was generated.

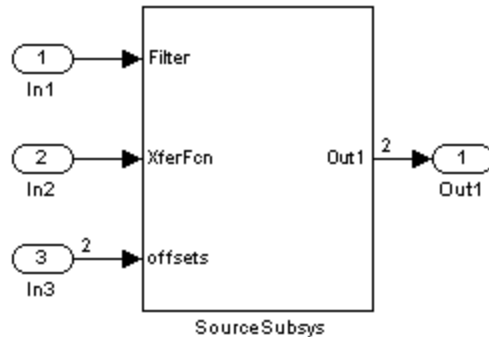
In this model, SourceSubsys inherits sample times and signal widths from its input signals. However, S-Function blocks created from a model using the S-function target will have all signal attributes (such as signal widths or sample times) hard-wired. (The sole exception to this rule concerns sample times, as described in “Sample Time Propagation in Generated S-Functions” on page 11-5.)

In this example, you want the S-Function block to retain the properties of SourceSubsys as it exists in SourceModel. Therefore, before you build the subsystem as a separate S-function component, you must set the inport sample times and widths explicitly. In addition, the solver parameters of the S-function component must be the same as those of the original model. This ensures that the generated S-function component will operate identically to the original subsystem (see “Choice of Solver Type” on page 11-5 for an exception to this rule).

To build SourceSubsys as an S-function component,

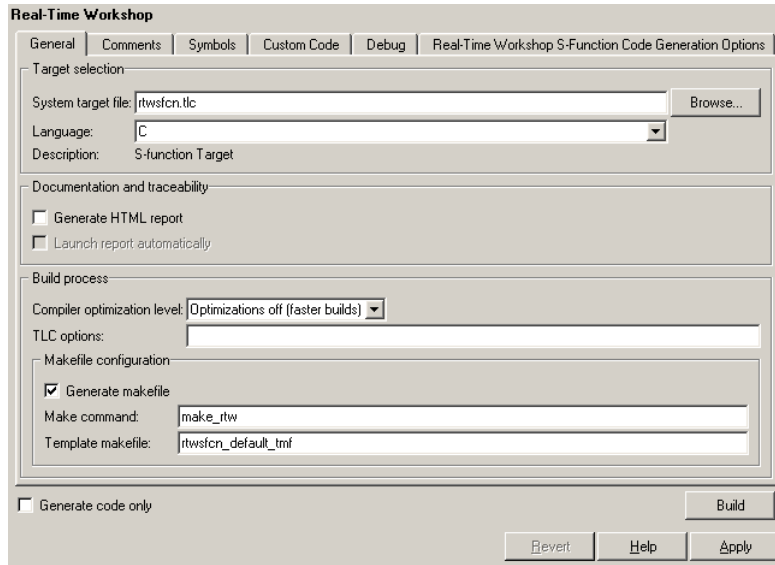
- 1 Create a new model and copy/paste SourceSubsys into the empty window.

- 2 Set the signal widths and sample times of inports inside SourceSubsys such that they match those of the signals in the original model. Inport 1, Filter, has a width of 1 and a sample time of 1. Inport 2, XferFcn, has a width of 1 and a sample time of 0.5. Inport 3, offsets, has a width of 2 and a sample time of 0.5.
- 3 The generated S-Function block should have three inports and one output. Connect inports and an output to SourceSubsys, as shown in the next figure.

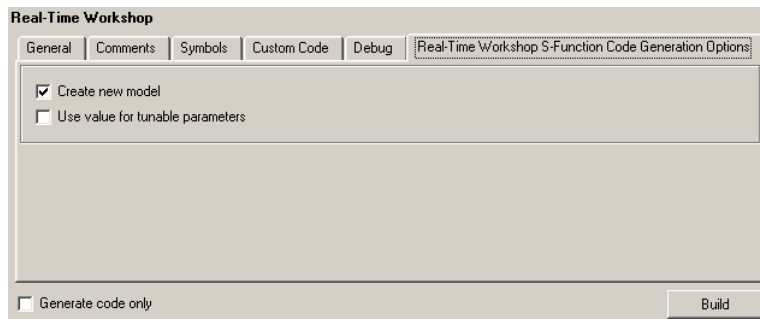


The correct signal widths and sample times are propagated to these ports.

- 4 Set the solver type, mode, and other solver parameters such that they are identical to those of the source model. This is easiest to do if you use Model Explorer.
- 5 In Model Explorer or the Configuration Parameters dialog box, click the **Real-Time Workshop** tab.
- 6 Click **Browse** to open the System Target File Browser.
- 7 In the System Target File Browser, select the S-function target, `rtwsfcn.tlc`, and click **OK**. The **Real-Time Workshop** pane appears as follows.



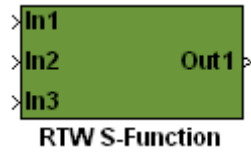
- 8 Select the **Real-Time Workshop S-Function Code Generation Options** tab (in Model Explorer) or pane (in the Configuration Parameters dialog box).
- 9 Make sure that **Create New Model** is selected, as shown in the next figure:



When this option is selected, the build process creates a new model after it builds the S-function component. The new model contains an S-Function block, linked to the S-function component.

Click **Apply** if necessary.

- 10 Save the new model containing your subsystem, for example as `SourceSubsys.mdl`.
- 11 Build the model.
- 12 Real-Time Workshop builds the S-function component in the working directory. After the build, a new model window is displayed.

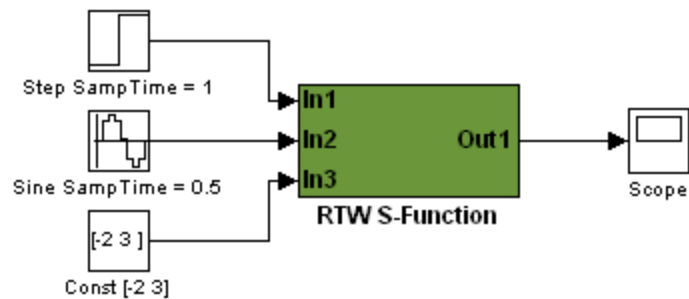


Optionally you can save the generated model, for example as `SourceSubsys_Sfunction.mdl`.

- 13 You can now copy the Real-Time Workshop S-Function block from the new model and use it in other models or in a library.

Note For a list of files required to deploy your S-Function block for simulation or code generation, see “Required Files for S-Function Deployment” on page 11-4.

The next figure shows the S-Function block plugged into the original model. Given identical input signals, the S-Function block will perform identically to the original subsystem.



Generated S-Function Configured Like SourceModel

The speed at which the S-Function block executes is typically faster than the original model. This difference in speed is more pronounced for larger and more complicated models. By using generated S-functions, you can increase the efficiency of your modeling process.

Tunable Parameters in Generated S-Functions

You can use tunable parameters in generated S-functions in two ways:

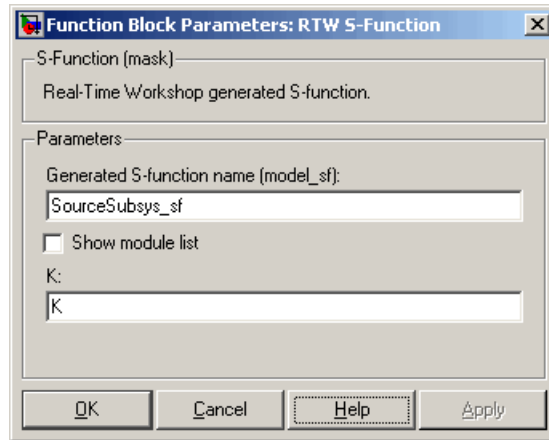
- Use the **Generate S-function** feature (see “Automated S-Function Generation” on page 11-15).
- or
- Use the Model Parameter Configuration dialog box (see “Parameter Storage, Interfacing, and Tuning” on page 5-2) to declare desired block parameters tunable.

Block parameters that are declared tunable with the auto storage class in the source model become tunable parameters of the generated S-function.

These parameters do not become part of a generated *model_P* (formerly *rtP*) parameter data structure, as they would in code generated from other targets. Instead, the generated code accesses these parameters by using MEX API calls such as `mxGetPr` or `mxGetData`. Your code should access these parameters in the same way.

For more information on MEX API calls, see “Writing S-Functions in C” in the Simulink S-function documentation and External Interfaces in the MATLAB online documentation.

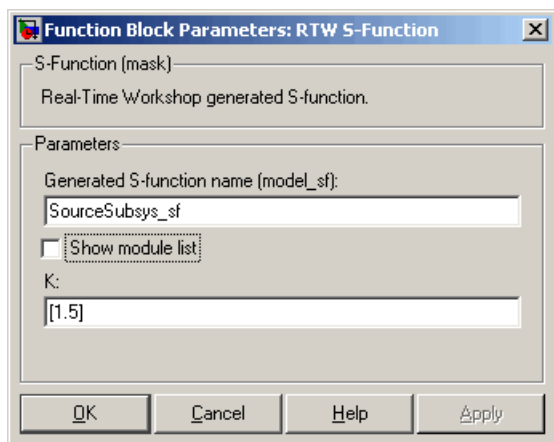
S-Function blocks created by using the S-function target are automatically masked. The mask displays each tunable parameter in an edit field. By default, the edit field displays the parameter by variable name, as in the following example.



You can choose to display the value of the parameter rather than its variable name by selecting **Use Value for Tunable Parameters** in the **Options** section.



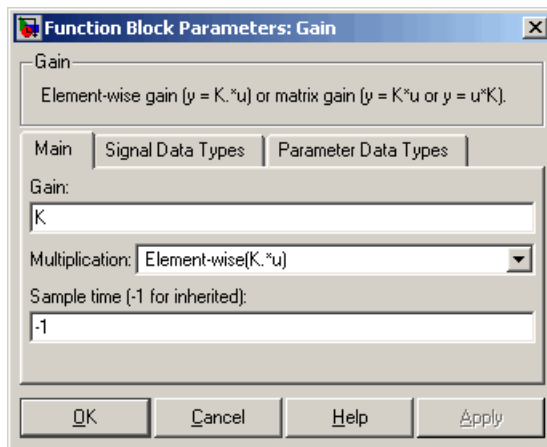
When this option is chosen, the value of the variable (at code generation time) is displayed in the edit field, as in the following example.



Automated S-Function Generation

The **Generate S-function** feature automates the process of generating an S-function from a subsystem. In addition, the **Generate S-function** feature presents a display of parameters used within the subsystem, and lets you declare selected parameters tunable.

As an example, consider SourceSubsys, the same subsystem illustrated in the previous example, “Creating an S-Function Block from a Subsystem” on page 11-6. The objective is to automatically extract SourceSubsys from the model and build an S-Function block from it, as in the previous example. In addition, the gain factor of the Gain block should be set within SourceSubsys to the workspace variable K (as illustrated in the next figure) and declare K as a tunable parameter.



To auto-generate an S-function from SourceSubsys with tunable parameter K,

- 1 Click the SourceSubsys subsystem to select it.
- 2 Select **Generate S-function** from the **Real-Time Workshop** submenu of the **Tools** menu. This menu item is enabled when a subsystem is selected in the current model.

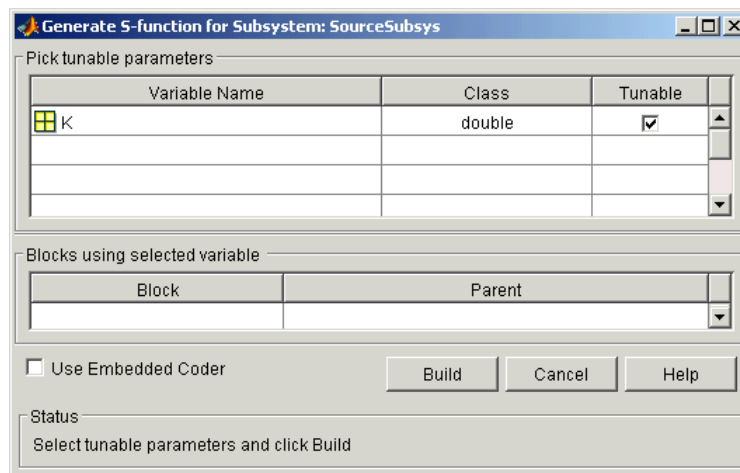
Alternatively, you can right-click the subsystem and select **Real-Time Workshop > Generate S-Function** from the subsystem block's context menu.

- 3** The **Generate S-function** window is displayed (see the next figure). This window shows all variables (or data objects) that are referenced as block parameters in the subsystem, and lets you declare them as tunable.

The upper pane of the window displays three columns:

- **Variable Name:** name of the parameter.
- **Class:** If the parameter is a workspace variable, its data type is shown. If the parameter is a data object, its name and class is shown
- **Tunable:** Lets you select tunable parameters. To declare a parameter tunable, select the check box. In the next figure, the parameter K is declared tunable.

When you select a parameter in the upper pane, the lower pane shows all the blocks that reference the parameter, and the parent system of each such block.

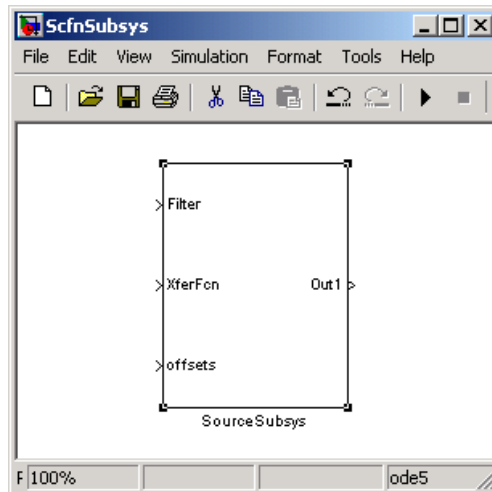


Generate S-Function Window

- 4** If you have installed Real-Time Workshop Embedded Coder, the **Use Embedded Coder** check box is available, as shown above. Otherwise, it is

grayed out. When **Use Embedded Coder** is selected, the build process generates a wrapper S-function by using Real-Time Workshop Embedded Coder. See “Automatic S-Function Wrapper Generation” in the Real-Time Workshop Embedded Coder documentation for more information.

- 5 After selecting tunable parameters, click the **Build** button. This initiates code generation and compilation of the S-function, using the S-function target. The **Create New Model** option is automatically enabled.
- 6 The build process displays status messages in the MATLAB Command Window. When the build completes, the tunable parameters window closes, and a new untitled model window opens.



- 7 The model window contains an S-Function block with the same name as the subsystem from which the block was generated (in this example, SourceSubsys). Optionally, you can save the generated model containing the generated block.
- 8 The generated code for the S-Function block is stored in the current working directory. The following files are written to the top level directory:
 - *subsys_sf.c* or *.cpp*, where *subsys* is the subsystem name (for example, SourceSubsys_sf.c)
 - *subsys_sf.h*

- *subsys_sf.mexext*, where *mexext* is a platform-dependent MEX-file extension (for example, *SourceSubsys_sf.mexw32*)

The source code for the S-function is written to the subdirectory *subsys_sfcn_rtw*. The top-level *.c* or *.cpp* file is a stub file that simply contains an include directive that you can use to interface other C/C++ code to the generated code.

Note For a list of files required to deploy your S-Function block for simulation or code generation, see “Required Files for S-Function Deployment” on page 11-4.

- 9 The generated S-Function block has inports and outports whose widths and sample times correspond to those of the original model.

The following code, from the *mdlOutputs* routine of the generated S-function code (in *SourceSubsys_sf.c*), shows how the tunable variable *K* is referenced by using calls to the MEX API.

```
static void mdlOutputs(SimStruct *S, int_T tid)
...

/* Gain: '<S1>/Gain' incorporates:
 * Sum: '<S1>/Sum'
 */
rtb_Gain_n[0] = (rtb_Product_p + (((const
    real_T**)ssGetInputPortSignalPtrs(S, 2))[0]))) * (*(real_T
    *) (mxGetData(K(S))));
rtb_Gain_n[1] = (rtb_Product_p + (((const
    real_T**)ssGetInputPortSignalPtrs(S, 2))[1]))) * (*(real_T
    *) (mxGetData(K(S))));
```

Notes

- In automatic S-function generation, the **Use Value for Tunable Parameters** option is always set to its default value (off).
 - A MEX S-function wrapper must only be used in the version of MATLAB in which the wrapper is created.
-

System Target File and Template Makefiles

In this section...
“Introduction” on page 11-20
“System Target File” on page 11-20
“Template Makefiles” on page 11-20

Introduction

This section describes the target file and template makefiles are provided for use with the S-function target.

System Target File

- `rtwsfcn.tlc`

Template Makefiles

- `rtwsfcn_bc.tmf` — Borland C
- `rtwsfcn_lcc.tmf` — Lcc compiler
- `rtwsfc_unix.tmf` — UNIX host
- `rtwsfcn_vc.tmf` — Visual C
- `rtwsfcn_watc.tmf` — Watcom C

Checksums and the S-Function Target

Real-Time Workshop creates a checksum for a Simulink model and uses the checksum during the build process for code reuse, model reference, and external mode features.

Real-Time Workshop calculates a model's checksum by

- 1 Calculating a checksum for each subsystem in the model. A subsystem's checksum is the combination of properties (data type, complexity, sample time, port dimensions, and so forth) of the subsystem's blocks.
- 2 Combining the subsystem checksums and other model-level information.

An S-function can add additional information, not captured during the block property analysis, to a checksum by calling the function `ssSetChecksumVal`. For the S-Function target, the value that gets added to the checksum is the checksum of the model or subsystem from which the S-function is generated.

Real-Time Workshop applies the subsystem and model checksums as follows:

- Code reuse — If two subsystems in a model have the same checksum, Real-Time Workshop generates code for one function only.
- Model reference — If the current model checksum matches the checksum when the model was built, Real-Time Workshop does not rebuild submodels.
- External mode — If the current model checksum does not match the checksum of the code that is running on the target, Real-Time Workshop generates an error.

S-Function Target Limitations

In this section...

“Run-Time Parameters and S-Function Compatibility Diagnostics” on page 11-22

“Goto and From Block Limitations” on page 11-22

“Building and Updating Limitations” on page 11-24

“Unsupported Blocks” on page 11-24

Run-Time Parameters and S-Function Compatibility Diagnostics

If you set the **S-function upgrades needed** option on the **Diagnostics > Compatibility** pane of the Configuration Parameters dialog box to warning or error, Real-Time Workshop reports that an upgrade is needed for any S-function you create with the **Generate S-function** feature. This is because the S-function target does not register run-time parameters. Run-time parameters are only supported for inlined S-Functions and the generated S-Function supports features that prevent it from being inlined (for example, it can call or contain other noninlined S-functions).

You can work around this limitation by setting the **S-function upgrades needed** option to none. Alternatively, if you have a Real-Time Workshop Embedded Coder license, select the **Use Embedded Coder** option on the **Generate S-function for Subsystem** dialog box and generate an ERT S-function. In this case, you do not receive the upgrade messages. However, you cannot include ERT S-functions inside other generated S-functions recursively.

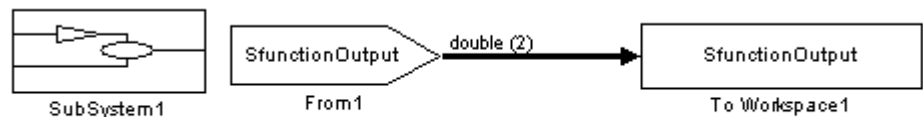
Goto and From Block Limitations

When using the S-function target, Real-Time Workshop restricts I/O to correspond to the root model's Inport and Outport blocks (or the Inport and Outport blocks of the Subsystem block from which the S-function target was generated). No code is generated for Goto or From blocks.

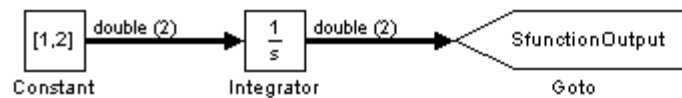
To work around this restriction, create your model and subsystem with the required Inport and Outport blocks, instead of using Goto and From blocks to pass data between the root model and subsystem. In the model that incorporates the generated S-function, you would then add needed Goto and From blocks.

Example Before Work Around

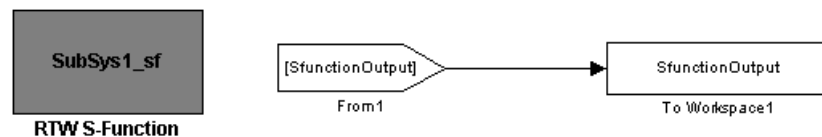
- Root model with a From block and subsystem, Subsystem1



- Subsystem1 with a Goto Block, which has global visibility and passes its input to the From block in the root model

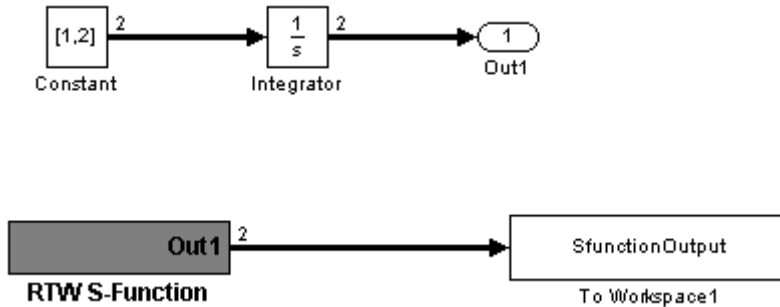


- Subsystem1 replaced with an S-function generated with the S-Function target — a warning results when you run the model because the generated S-function does not implement the Goto block



Example After Work Around

An Outport block replaces the GoTo block in Subsystem1. When you plug the generated S-function into the root model, its output connects directly to the To Workspace block.



Building and Updating Limitations

The following limitations apply to building and regenerating S-function targets:

- You cannot build models that contain Model blocks using the Real-Time Workshop S-function target. This also means that you cannot build a subsystem module by right-clicking (or by using **Tools > Real-Time Workshop > Build subsystem**) if the subsystem contains Model blocks. This restriction applies only to GRT S-functions, not to ERT S-functions.
- If you modify the model that generated an S-Function block, Real-Time Workshop does not automatically rebuild models containing the generated S-Function block. This is in contrast to the practice of automatically rebuilding models referenced by Model blocks when they are modified (depending on the Model Reference **Rebuild options** configuration setting).
- Handwritten S-functions without corresponding TLC files must contain exception-free code. For more information on exception-free code, see “Exception Free Code” in the Writing S-Functions Simulink documentation.

Unsupported Blocks

The S-function format does not support the following built-in blocks:

- MATLAB Fcn block
- S-Function blocks containing any of the following:
 - M-file S-functions (unless you supply a TLC file for C code generation)
 - Fortran S-functions (unless you supply a TLC file for C code generation)
 - C/C++ MEX S-functions that call into MATLAB
- Scope block
- To Workspace block

Running Rapid Simulations

Introduction (p. 12-2)	Introduces the RSim target, its applications, and dependencies on Simulink
General Rapid Simulation Workflow (p. 12-5)	Shows the general workflow for preparing and running rapid simulations
Identifying Your Rapid Simulation Requirements (p. 12-7)	Lists questions that will help you identify rapid simulation requirements
Configuring Inport Blocks to Provide Rapid Simulation Source Data (p. 12-9)	Explains how to configure Inport blocks so they can be used for providing rapid simulation source data
Configuring and Building a Model for Rapid Simulation (p. 12-10)	Explains how to configure a model for rapid simulation
Setting Up Rapid Simulation Input Data (p. 12-14)	Discusses options for and explains how to set up rapid simulation input data
Programming Scripts for Batch and Monte Carlo Simulations (p. 12-25)	Explains how you can use scripts to run batch and Monte Carlo simulations
Running Rapid Simulations (p. 12-26)	Discusses the different ways you can run rapid simulations
Rapid Simulation Target Limitations (p. 12-40)	Lists rapid simulation target limitations

Introduction

In this section...
“About Rapid Simulation” on page 12-2
“Licensing Protocols for Simulink Solvers in RSim Executables” on page 12-3
“Rapid Simulation Performance” on page 12-4

About Rapid Simulation

After you create a model, you can use the Real-Time Workshop rapid simulation (RSim) target to characterize the model's behavior. The RSim target executable that results from the build process is for non-real-time execution on your host computer. The executable is highly optimized for simulating models of hybrid dynamic systems, including models that use variable-step solvers and zero-crossing detection. The speed of the generated code makes the RSim target ideal for batch or Monte Carlo simulations.

Use the RSim target to generate an executable that runs fast, standalone simulations. You can repeat simulations with varying data sets, interactively or programmatically with scripts, without rebuilding the model. This can accelerate the characterization and tuning of model behavior and code generation testing.

Using command-line options, you can

- Define parameter values and input signals in one or more MAT-files that you can load and reload at the start of simulations without rebuilding your model
- Redirect logging data to one or more MAT-files that you can then analyze and compare
- Control simulation time
- Specify external mode options

Licensing Protocols for Simulink Solvers in RSim Executables

The RSim target supports variable-step solvers by linking the generated code with the Simulink solver module (a shared library). When this RSim executable runs, it accesses proprietary Simulink variable-step solver technology. To do so, the executable checks out a Simulink license for the duration of execution.

RSim executables that do not use the Simulink solver module (for example, RSim executables built for a fixed-step model using a Real-Time Workshop fixed-step solver) do not require a license.

The RSim executable looks in the default locations for the license file:

- UNIX: *matlabroot*/etc/license.dat
- PC: *matlabroot*\bin\win32\license.dat

Here, *matlabroot* is the location used when you built the RSim executable. If the RSim executable is unable to locate the license file (this can happen, for example, if you run this executable on another machine, where *matlabroot* is no longer valid), it displays the following error message and exits:

```
Error checking out SIMULINK license.

Cannot find license file
The license files (or server network addresses) attempted are
listed below. Use LM_LICENSE_FILE to use a different license
file, or contact your software provider for a license file.
Feature:          SIMULINK
Filename:         /apps/matlab/etc/license.dat
License path:    /abbs/matlab/etc/license.dat
FLEXlm error: -1,359. System Error: 2 "No such file or directory"
For further information, refer to the FLEXlm End User Manual,
available at "www.globetrotter.com".
Error: Unable to check out Simulink license
Error terminating RSIM Engine: License check failed
```

Note You can point the RSim executable to a different license file by setting the environment variable `LM_LICENSE_FILE`. The location pointed to by that variable will override the default location compiled into the RSim executable.

If the RSim executable is unable to check out a Simulink license (this would happen, for example, if all Simulink licenses are currently checked out), or has other errors when checking out a Simulink license, it displays a detailed error message (similar to the one above) returned by the FLEXlm API and exits.

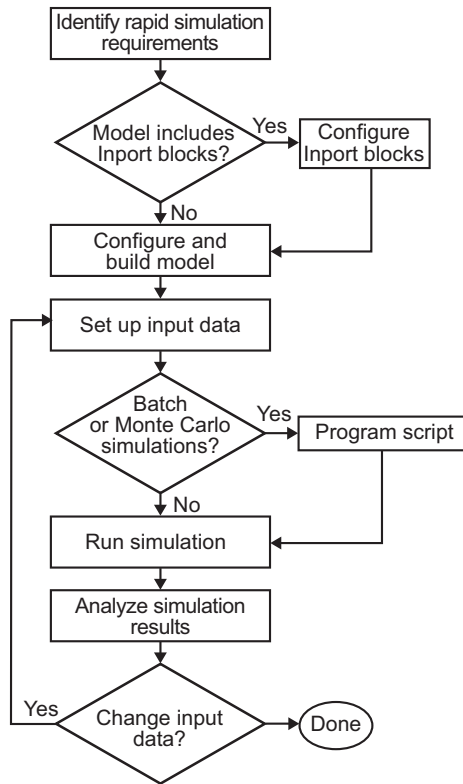
Rapid Simulation Performance

The performance advantage gained from rapid simulation varies. Larger simulations achieve speed improvements of up to 10 times faster than standard Simulink simulations. Some models might not show any noticeable improvement in simulation speed. To determine the speed difference for your model, time your standard Simulink simulation and compare the results with a rapid simulation.

General Rapid Simulation Workflow

Like other stages of Model-Based Design, characterization and tuning of model behavior is an iterative process as shown in the general workflow diagram in the next figure. The following steps summarize tasks in the workflow.

- 1** Identify your rapid simulation requirements.
- 2** Configure Inport blocks that will provide input source data for rapid simulations.
- 3** Configure the model for rapid simulation.
- 4** Set up simulation input data.
- 5** Run the rapid simulations.



Identifying Your Rapid Simulation Requirements

The first step to setting up a rapid simulation is to identify your simulation requirements.

Question...	For More Information, See...
For how long do you want simulations to run?	“Configuring and Building a Model for Rapid Simulation” on page 12-10
Are there any solver requirements? Do you expect to use the same solver for which the model is configured for your rapid simulations?	“Configuring and Building a Model for Rapid Simulation” on page 12-10
Will your rapid simulations need to accommodate flexible custom code interfacing? Or, do your simulations need to retain storage class settings?	“Configuring and Building a Model for Rapid Simulation” on page 12-10
Will you be running simulations with multiple data sets?	“Setting Up Rapid Simulation Input Data” on page 12-14
Will the input data consist of global parameters, signals, or both?	“Setting Up Rapid Simulation Input Data” on page 12-14
What type of source blocks provide input data to the model — From File, Inport, From Workspace?	“Setting Up Rapid Simulation Input Data” on page 12-14
Will the model’s parameter vector (<i>model_P</i>) be used as input data?	“Creating a MAT-File That Includes a Model’s Parameter Structure” on page 12-15
What is the data type of the input parameters and signals?	“Setting Up Rapid Simulation Input Data” on page 12-14
Will the source data consist of one variable or multiple variables?	“Setting Up Rapid Simulation Input Data” on page 12-14
Does the input data include tunable parameters?	“Creating a MAT-File That Includes a Model’s Parameter Structure” on page 12-15

Question...	For More Information, See...
Do you need to gain access to tunable parameter information — model checksum and parameter data types, identifiers, and complexity?	“Creating a MAT-File That Includes a Model’s Parameter Structure” on page 12-15
Will you have a need to vary the simulation stop time for simulation runs?	“Configuring and Building a Model for Rapid Simulation” on page 12-10 and “Overriding a Model’s Simulation Stop Time” on page 12-29
Do you want to set a time limit for the simulation? Consider setting a time limit if your model experiences frequent zero crossings and has a small minor step size.	“Setting a Clock Time Limit for a Rapid Simulation” on page 12-29
Do you need to preserve the output of each simulation run?	“Specifying a New Output Filename for a Simulation” on page 12-38 and “Specifying New Output Filenames for To File Blocks” on page 12-39
Do you expect to run the simulations interactively or in batch mode?	“Programming Scripts for Batch and Monte Carlo Simulations” on page 12-25

Configuring Inport Blocks to Provide Rapid Simulation Source Data

You can use Inport blocks as a source of input data for rapid simulations. To do so, you must configure the blocks such that they can import data from external MAT-files. By default, the Inport block inherits parameter settings from downstream blocks. In most cases, to import data from an external MAT-file, you need to explicitly set the following parameters to match the source data in the MAT-file.

- **Main > Interpolate data**
- **Signal Specification > Port dimensions**
- **Signal Specification > Data type**
- **Signal Specification > Signal type**

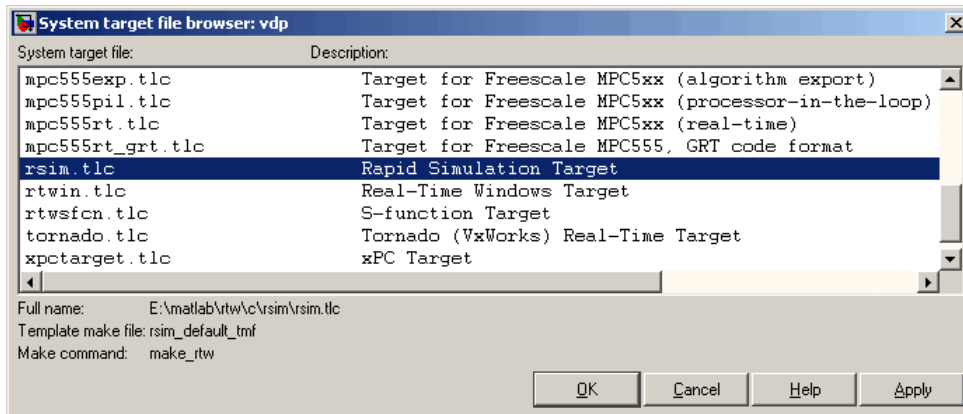
If you do not have control over the model content, you might need to modify the data in the MAT-file to conform to what the model expects for input. Characteristics of the input data and specifications of the Inport block that receives the data must match.

For details on adjusting these parameters and on creating a MAT-file for use with an Inport block, see “Creating a MAT-File for an Inport Block” on page 12-19. For descriptions of the preceding block parameters, see the description of the Inport block in the Simulink documentation.

Configuring and Building a Model for Rapid Simulation

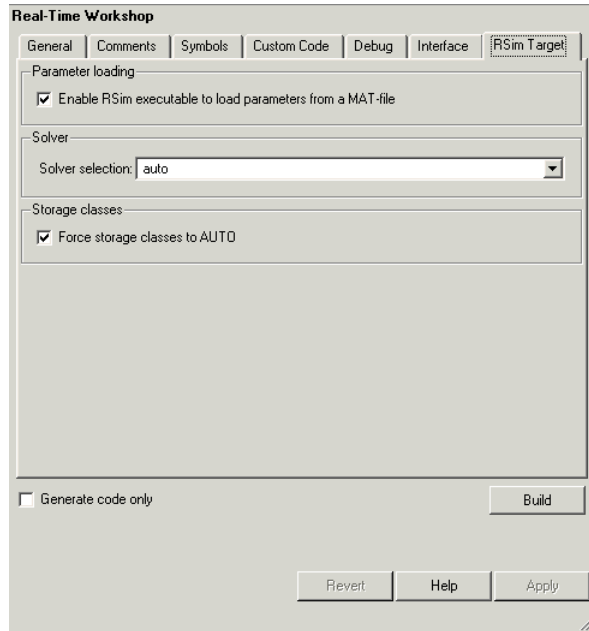
After you identify your rapid simulation requirements, configure the model for rapid simulation.

- 1 Open the Configuration Parameters dialog box.
- 2 Click **Real-Time Workshop**.
- 3 On the **Real-Time Workshop** pane, click **Browse**. Real-Time Workshop displays the System Target File Browser.
- 4 Select `rsim.tlc` (Rapid Simulation Target) and click **OK**.



Real-Time Workshop populates the **Make command** and **Template makefile** fields on the **Real-Time Workshop** pane with default settings and adds the **RSim Target** tab or node under **Real-Time Workshop**.

- 5 Click **RSim Target** to view the **RSim Target** pane.



- 6 Set the RSim target configuration parameters to your rapid simulation requirements.

If You Want to...	Then...
Generate code that allows the RSim executable to load parameters from a MAT-file	Select Enable RSim executable to load parameters from a MAT-file (default).
Let the target choose a solver based on the solver already configured for the model.	Set Solver selection to auto (default). Real-Time Workshop uses a built-in solver if a fixed-step solver is specified on the Solver pane or calls the Simulink solver module (a shared library) if a variable-step solver is specified. When the executable includes the Simulink solver module, it checks out a Simulink license at run-time as explained in “Licensing Protocols for Simulink Solvers in RSim Executables” on page 12-3.

If You Want to...	Then...
Explicitly instruct the target to use a fixed-step solver	Set Solver selection to Use RTW fixed-step solvers. A fixed-step solver must be specified on the Solver pane of the Configuration Parameters dialog box.
Explicitly instruct the target to use a variable-step solver	Set Solver selection to Use Simulink solver module. A variable-step solver must be specified on the Solver pane of the Configuration Parameters dialog box. When the executable includes the Simulink solver module, it checks out a Simulink license at run-time as explained in “Licensing Protocols for Simulink Solvers in RSim Executables” on page 12-3.
Force all storage classes to Auto for flexible custom code interfacing	Select Force storage classes to AUTO (default).
Retain storage class settings, such as ExportedGlobal or ImportedExtern, due to application requirements	Clear Force storage classes to AUTO .

- 7** Set up data import and export options. In the **Save to Workspace** section of the **Data Import/Export** pane, select the **Time**, **States**, **Outputs**, and **Final States** options, as needed. By default, Real-Time Workshop saves simulation logging results to a file named *model.mat*. For more information, see “Importing and Exporting Simulation Data” in the Simulink documentation.
- 8** If appropriate for your simulations, set up external mode communications on the **Real-Time Workshop > Interface** pane. See Chapter 6, “External Mode” for details.
- 9** Return to the **Real-Time Workshop** pane and click **Build**. Real-Time Workshop builds a highly optimized executable that you can run on your host computer with varying data without rebuilding.

See “Supported Third-Party Compilers” in Getting Started, “Choosing and Configuring a Compiler” on page 2-19, and “Template Makefiles and Make

Options” on page 2-10 for additional information on compilers that are compatible with Real-Time Workshop.

Setting Up Rapid Simulation Input Data

In this section...

“Introduction” on page 12-14

“Creating a MAT-File That Includes a Model’s Parameter Structure” on page 12-15

“Creating a MAT-File for a From File Block” on page 12-19

“Creating a MAT-File for an Inport Block” on page 12-19

Introduction

The format and setup of input data for a rapid simulation depends on your requirements.

If the Input Data Source Is...	Then...
The model’s global parameter vector (<i>model_P</i>)	Use the <code>rsimgetrtp</code> function to get the vector content and then save it to a MAT-file
The model’s global parameter vector and you want a mapping between the vector and tunable parameters	Use the <code>rsimgetrtp</code> function with the <code>AddTunableParamInfo</code> option to get the model’s global parameter structure and then save it to a MAT-file
Provided by a From File block	Create a MAT-file that a From File block can read
Provided by an Inport block	Create a MAT-file that adheres to one of the three data file formats that the Inport block can read
Provided by a From Workspace block	Create structure variables in the MATLAB workspace

The RSim target requires that MAT-files used as input for From File and Inport blocks contain data. The grt target inserts MAT-file data directly into the generated code, which is then compiled and linked as an executable. In contrast, RSim allows you to replace data sets for each successive simulation.

A MAT-file containing From File or Inport block data must be present if any From File or Inport blocks exist in your model.

Creating a MAT-File That Includes a Model's Parameter Structure

To create a MAT-file that includes a model's global parameter structure (*model_P*),

- 1 Get the structure by calling the function `rsimgetrtp`.
- 2 Save the parameter structure to a MAT-file.

If you want to run simulations over varying data sets, consider converting the parameter structure to a cell array and saving the parameter variations to a single MAT-file.

Getting the Parameter Structure for a Model

Get the global parameter structure (*model_P*) for a model by calling the function `rsimgetrtp`.

```
param_struct = rsimgetrtp('model', option)
```

Argument	Description
<i>model</i>	The model for which you are running the rapid simulations.
<i>option</i>	The parameter-value pair 'AddTunableParamInfo' 'value', where 'value' can be 'on' or 'off'. If you set the parameter to 'on', Real-Time Workshop extracts tunable parameter information from the specified model and returns it to <i>param_struct</i> .

The `rsimgetrtp` function forces an update diagram action for the specified model and returns a structure that contains the following fields:

Field	Description
<code>modelChecksum</code>	A four-element vector that encodes the structure of the model. Real-Time Workshop uses the checksum to check whether the structure of the model has changed since the RSim executable was generated. If you delete or add a block, and then generate a new <code>model_P</code> vector, the new checksum no longer matches the original checksum. The RSim executable detects this incompatibility in parameter vectors and exits to avoid returning incorrect simulation results. If the model structure changes, you must regenerate the code for the model.
<code>parameters</code>	A structure that contains the model's global parameters.

If you specify 'AddTunableParamInfo' 'on', Real-Time Workshop creates and then deletes `model.rtw` from your current working directory and includes the following fields for each parameter in the parameter structure:

Field	Description
<code>dataTypeName</code>	The name of the parameter's data type, for example, <code>double</code>
<code>dataTypeID</code>	An internal data type identifier that Real-Time Workshop uses
<code>complex</code>	The value 0 if real and 1 if complex

To use the `AddTunableParamInfo` option, inline parameters must be enabled.

Real-Time Workshop reports a tunable fixed-point parameter according to its stored value. For example, an `sfix(16)` parameter value of 1.4 with a scaling of 2^{-8} has a value of 358 as an `int16`.

In the following example, `rsimgetrtp` returns the parameter structure for the demo model `rtwdemo_rsimtf` to `param_struct`.

```
param_struct = rsimgetrtp('rtwdemo_rsimtf')

param_struct =
```

```
modelChecksum: [1.7165e+009 3.0726e+009 2.6061e+009 2.3064e+009]
parameters: [1x1 struct]
```

Saving the Parameter Structure to a MAT-File

After you issue a call to `rsimgetrtp`, save the return value of the function call to a MAT-file. Using a command-line option, you can then specify that MAT-file as input for rapid simulations.

The following example saves the parameter structure returned for `rtwdemo_rsimtf` to the MAT-file `myrsimdemo.mat`.

```
save myrsimdemo.mat param_struct;
```

For information on using command-line options to specify required files, see “Running Rapid Simulations” on page 12-26.

Converting the Parameter Structure for Running Simulations on Varying Data Sets

If you might have a need to use rapid simulations to test changes to specific parameters, you can do so if you convert the model’s parameter structure to a cell array. You can then access a specific parameter by using the `@` operator to specify the index for a specific parameter in the file.

To convert the structure to a cell array,

- 1 Save the parameters vector of the structure returned by `rsimgetrtp` to a temporary variable. The following example saves the parameter vector to temporary variable `p`.

```
param_struct = rsimgetrtp('rtwdemo_rsimtf');
p = param_struct.parameters;
```

- 2 Convert the structure to a cell array.

```
param_struct.parameters = [];
```

- 3 Assign the saved contents of the temporary variable to the original structure name as an element of the cell array.

```
param_struct.parameters{1} = p;
```

```
param_struct.parameters{1}

ans =

    dataTypeName: 'double'
    dataTypeId: 0
    complex: 0
    dtTransIdx: 0
    values: [-140 -4900 0 4900]
```

- 4** Make a copy of the cell array to preserve the original parameter values.

```
param_struct.parameters{2} = param_struct.parameters{1};
param_struct.parameters{2}

ans =

    dataTypeName: 'double'
    dataTypeId: 0
    complex: 0
    dtTransIdx: 0
    values: [-140 -4900 0 4900]
```

For a subsequent data set, increment the array index.

- 5** Modify any combination of the parameter values.

```
param_struct.parameters{2}.values=[-150 -5000 0 4950];
```

- 6** Repeat steps 4 and 5 for each parameter data set you want to use as input to a rapid simulation of the model.
- 7** Save the cell array representing the parameter structure to a MAT-file.

```
save rtwdemo_rsintf.mat param_struct;
```

“Changing Block Parameters for an RSim Simulation” on page 12-37 explains how to specify each data set when you run the simulations.

Creating a MAT-File for a From File Block

You can use a MAT-file as the input data source for a From File block. The format of the data in the MAT-file must match the matrix format expected by that block.

To create such a MAT-file,

- 1 Create a matrix in the workspace that consists of two or more rows. The first row must contain monotonically increasing time points. Other rows contain data points that correspond to the time point in that column. The time and data points must be data of type double.

For example:

```
t=[0:0.1:2*pi]';  
Ina1=[2*sin(t) 2*cos(t)];  
Ina2=sin(2*t);  
Ina3=[0.5*sin(3*t) 0.5*cos(3*t)];  
var_matrix=[t Ina1 Ina2 Ina3]';
```

For more information on setting up the input data, see the description of the From File block in the Simulink documentation.

- 2 Save the matrix to a MAT-file.

The following example saves the matrix `var_matrix` to the MAT-file `myrsimdemo.mat`.

```
save myrsimdemo.mat var_matrix;
```

Using a command-line option, you can then specify that MAT-file as input for rapid simulations.

Creating a MAT-File for an Inport Block

You can use a MAT-file as the input data source for an Inport block.

The format of the data in the MAT-file must adhere to one of the three column-based formats listed in the following table. The table lists the formats in order from least flexible to most flexible.

Format	Description
Single time/data matrix	<ul style="list-style-type: none"> • Least flexible. • One variable. • Two or more <i>columns</i>. Number of columns must equal the sum of the dimensions of all root Inport blocks plus 1. First column must contain monotonically increasing time points. Other columns contain data points that correspond to the time point in a given row. • Data of type double. <p>For an example, see Single time/data matrix in step 4 below. For more information, see “Importing Data Arrays” in the Simulink documentation.</p>

Format	Description
Signal-and-time structure	<ul style="list-style-type: none"> • More flexible than the single time/data matrix format. • One variable. • Must contain two top-level fields: <code>time</code> and <code>signals</code>. The <code>time</code> field contains a <i>column</i> vector of the simulation times. The <code>signals</code> field contains an array of substructures, each of which corresponds to an Inport block. The substructure index corresponds to the Inport block number. Each <code>signals</code> substructure must contain a field named <code>values</code>. The <code>values</code> field must contain an array of inputs for the corresponding Inport block, where each input corresponds to a time point specified by the <code>time</code> field. • If the <code>time</code> field is set to an empty value, clear the check box for the Inport block Interpolate data parameter. • No data type limitations, but must match Inport block settings. <p>For an example, see Signal-and-time structure in step 4 below. For more information on this format, see “Importing Data Structures” in the Simulink documentation.</p>

Format	Description
Per-port structure	<ul style="list-style-type: none"> • Most flexible • Multiple variables. Number of variables must equal the number of Inport blocks. • Consists of a separate structure-with-time or structure-without-time for each Inport block. Each Inport block's data structure has only one signals field. To use this format, enter the names of the structures in the Input text field as a comma-separated list, in1, in2,..., inN, where in1 is the data for your model's first port, in2 for the second port, and so on. • Each variable can have a different time vector. • If the time field is set to an empty value, clear the checkbox for the Inport block Interpolate data parameter. • No data type limitations, but must match Inport block settings. • To save multiple variables to the same data file, you must save them in the order expected by the model, using the -append option. <p>For an example, see Per-port structure in step 4 below. For more information, see "Importing Data Structures" in the Simulink documentation.</p>

The supported formats and the following procedure are illustrated in `rtwdemo_rsim_i`.

To create a MAT-file for an Inport block,

- 1** Choose one of the preceding data file formats.
- 2** If necessary, update Inport block parameter settings and specifications to match specifications of the data you expect to be supplied by the MAT-file.

By default, the Inport block inherits parameter settings from downstream blocks. In most cases, to import data from an external MAT-file, you need to explicitly set the following parameters to match the source data in the MAT-file.

- **Main > Interpolate data**

- **Signal Specification > Port dimensions**
- **Signal Specification > Data type**
- **Signal Specification > Signal type**

If you choose to use a structure format for workspace variables and the time field is empty, you must clear **Interpolate data** or modify the field such that it is set to a non-empty value. Interpolation requires time data.

For descriptions of the preceding block parameters, see the description of the Inport block in the Simulink documentation.

- 3** Build an RSim executable for the model. During the build process, Real-Time Workshop creates and calculates a structural checksum for the model and embeds it in the generated executable. The RSim target uses the checksum to verify that data being passed into the model is consistent with what model's executable expects.
- 4** Create the MAT-file that is to provide the source data for the rapid simulations. Generally, you can create the MAT-file from a workspace variable. Using the specifications in the format comparison table above, create the workspace variables for your simulations.

An example of each format follows:

Single time/data matrix

```
t=[0:0.1:2*pi]';  
Ina1=[2*sin(t) 2*cos(t)];  
Ina2=sin(2*t);  
Ina3=[0.5*sin(3*t) 0.5*cos(3*t)];  
var_matrix=[t Ina1 Ina2 Ina3];
```

Signal-and-time structure

```
t=[0:0.1:2*pi]';  
var_single_struct.time=t;  
var_single_struct.signals(1).values(:,1)=2*sin(t);  
var_single_struct.signals(1).values(:,2)=2*cos(t);  
var_single_struct.signals(2).values=sin(2*t);  
var_single_struct.signals(3).values(:,1)=0.5*sin(3*t);  
var_single_struct.signals(3).values(:,2)=0.5*cos(3*t);
```

```
v=[var_single_struct.signals(1).values...
var_single_struct.signals(2).values...
var_single_struct.signals(3).values];
```

Per-port structure

```
t=[0:0.1:2*pi]';
Inb1.time=t;
Inb1.signals.values(:,1)=2*sin(t);
Inb1.signals.values(:,2)=2*cos(t);
t=[0:0.2:2*pi]';
Inb2.time=t;
Inb2.signals.values(:,1)=sin(2*t);
t=[0:0.1:2*pi]';
Inb3.time=t;
Inb3.signals.values(:,1)=0.5*sin(3*t);
Inb3.signals.values(:,2)=0.5*cos(3*t);
```

- 5 Save the workspace variables to a MAT-file.

Single time/data matrix

The following example saves the workspace variable `var_matrix` to the MAT-file `rsim_i_matrix.mat`.

```
save rsim_i_matrix.mat var_matrix;
```

Signal-and-time structure

The following example saves the workspace structure variable `var_single_struct` to the MAT-file `rsim_i_single_struct.mat`.

```
save rsim_i_single_struct.mat var_single_struct;
```

Per-port structure

To ensure correct ordering of data when saving per-port structure variables to a single MAT-file, use the save command's `-append` option. Be sure to append the data in the order that the model expects it.

The following example saves the workspace variables `Inb1`, `Inb2`, and `Inb3` to MAT-file `rsim_i_multi_struct.mat`.

```
save rsim_i_multi_struct.mat Inb1;  
save rsim_i_multi_struct.mat Inb2 -append;  
save rsim_i_multi_struct.mat Inb3 -append;
```

The save command does not preserve the order in which you specify your workspace variables in the command line when saving data to a MAT-file. For example, if you specify the variables `v1`, `v2`, and `v3`, in that order, in a save command, MATLAB does not preserve the order of the variable data in the MAT-file. The order of the variables in the MAT-file could be `v2 v1 v3`.

Using a command-line option, you can then specify the MAT-files as input for rapid simulations.

Programming Scripts for Batch and Monte Carlo Simulations

The RSim target is intended for batch simulations in which parameters and input signals vary for multiple simulations. New output filenames allow you to run new simulations without overwriting prior simulation results. You can set up a series of simulations to run by creating a .bat file for use under Microsoft Windows.

Create a file for Windows with any text editor and execute it by typing the filename, for example, mybatch, where the name of the text file is mybatch.bat.

```
rtwdemo_rsimtf -f rtwdemo_rsimtf.mat=run1.mat -o results1.mat -s 10.0
rtwdemo_rsimtf -f rtwdemo_rsimtf.mat=run2.mat -o results2.mat -s 10.0
rtwdemo_rsimtf -f rtwdemo_rsimtf.mat=run3.mat -o results3.mat -s 10.0
rtwdemo_rsimtf -f rtwdemo_rsimtf.mat=run4.mat -o results4.mat -s 10.0
```

In this case, batch simulations run using four sets of input data in files run1.mat, run2.mat, and so on. The RSim executable saves the data to the files specified with the -o option.

The variable names containing simulation results in each of the files are identical. Therefore, loading consecutive sets of data without renaming the data once it is in the MATLAB workspace results in overwriting the prior workspace variable with new data. If you want to avoid overwriting, you can copy the result to a new MATLAB variable before loading the next set of data.

You can also write M-file scripts to create new signals and new parameter structures, as well as to save data and perform batch runs using the bang command (!).

For details on running simulations and available command-line options, see “Running Rapid Simulations” on page 12-26. For an example of a rapid simulation batch script, see the demo rtwdemo_rsim_batch_script.

Running Rapid Simulations

In this section...
“Introduction” on page 12-26
“Requirements for Running Rapid Simulations” on page 12-28
“Setting a Clock Time Limit for a Rapid Simulation” on page 12-29
“Overriding a Model’s Simulation Stop Time” on page 12-29
“Reading the Parameter Vector into a Rapid Simulation” on page 12-30
“Specifying New Signal Data File for a From File Block” on page 12-31
“Specifying Signal Data File for an Inport Block” on page 12-33
“Changing Block Parameters for an RSim Simulation” on page 12-37
“Specifying a New Output Filename for a Simulation” on page 12-38
“Specifying New Output Filenames for To File Blocks” on page 12-39

Introduction

An advantage of using the RSim target is the ability to build a model once and run multiple simulations to study effects of varying parameter settings and input signals. You can run a simulation directly from your operating system command line, redirect the command from the MATLAB command line by using the bang (!) character, or execute commands from a script.

Operating System Command Line

```
rtwdemo_rsimtf
```

MATLAB Command Line

```
!rtwdemo_rsimtf
```

The following table lists ways you can use RSim target command-line options to control a simulation.

To...	Use...
Display a help message listing options	<code>model -h</code>
Time out after n clock time seconds, where n is a positive integer value	<code>model -L n</code>
Run the simulation until the time value <i>stoptime</i> is reached	<code>model -tf stoptime</code> or <code>model -s stoptime</code>
Run in verbose mode	<code>model -v</code>
Load new solver options (for example, Solver, RelTol, and AbsTol)	<code>model -S solveroptions.mat</code>
Read input data for a From File block from a MAT-file other than the MAT-file used for the previous simulation	<code>model -f oldfilename.mat=newfilename.mat</code>
Read input data for an Inport block from a MAT-file	<code>model -i filename.mat</code>
Read a parameter vector from file <i>filename.mat</i>	<code>model -p filename.mat</code>
Write MAT-file logging data to a MAT-file other than the MAT-file used for the previous simulation	<code>model -t oldfilename.mat=newfilename.mat</code>
Write MAT-file logging data to file <i>filename.mat</i>	<code>model -o filename.mat</code>
Wait for Simulink to start the model in external mode	<code>model -w</code>
Override the default TCP port (17725) for external mode	<code>model -port TCPport</code>

The following sections use the `rtwdemo_rsimtf` demo in examples to illustrate the use of some of these options. In each case, the example assumes you have already done the following:

- Created or changed to a working directory.
- Opened the demo.

- Copied the data file
`matlabroot/toolbox/rtw/rtwdemos/rsimdemos/rtwdemo_rsim_tfddata.mat`
to your working directory.

Requirements for Running Rapid Simulations

- On Solaris platforms, to run an RSim executable generated for a model that uses variable-step solvers in a separate shell, define the `LD_LIBRARY_PATH` environment variable such that it provides the path to the MATLAB installation directory, as follows:

```
% setenv LD_LIBRARY_PATH /apps/matlab/bin/so164:$LD_LIBRARY_PATH
```

- On Linux platforms, to run an RSim executable, define the `LD_LIBRARY_PATH` environment variable such that it provides the path to the MATLAB installation directory, as follows:

```
% setenv LD_LIBRARY_PATH /matlab/sys/os/glnx86:$LD_LIBRARY_PATH
```

- On the Mac OS X platform, to run RSim target executables, you must define the environment variable `DYLD_LIBRARY_PATH` such that it includes the directories `bin/mac` and `sys/os/mac` under the MATLAB installation directory. For example, if you installed MATLAB under `/MATLAB`, add `/MATLAB/bin/mac` and `/MATLAB/sys/os/mac` to the definition for `DYLD_LIBRARY_PATH`.
- You can run an Rsim executable on another computer on which MATLAB is not installed, without using Simulink. To do this the fixed-step solver must be used, and the following library files must be present in the working directory. The file extension may vary, depending on your platform.

```
dsp_rt.mexw32  
icudt241.mexw32  
icuin24.mexw32  
icuiO24.mexw32  
icuuc24.mexw32  
libmat.mexw32  
libmx.mexw32  
libut.mexw32  
libz.mexw32  
msvc71.mexw32
```



```
msvcr71.mexw32
```

- You can remotely run an Rsim executable that uses variable-step solvers, but to do so the executable must check out a Simulink license. It is not necessary to include the above mentioned library files.

Setting a Clock Time Limit for a Rapid Simulation

If a model experiences frequent zero crossings and the model's minor step size is small, consider setting a time limit for a rapid simulation. To set a time limit, specify the `-L` option with a positive integer value. The simulation aborts after running for the specified amount of clock time. For example,

```
!rtwdemo_rsimg -L 20
```

After the executable runs for 20 seconds, the program terminates and one of the following messages appears:

Windows

```
Exiting program, time limit exceeded  
Logging available data ...
```

UNIX

```
** Received SIGALRM (Alarm) signal @ Fri Jul 25 15:43:23 2003  
** Exiting model 'vdp' @ Fri Jul 25 15:43:23 2003
```

You do not need to do anything to your model or to its Real-Time Workshop configuration to use this option.

Overriding a Model's Simulation Stop Time

By default, a rapid simulation runs until the simulation time reaches the time specified for the model in the **Solver** pane of the Configuration Parameters dialog box. You can override the model's simulation stop time by using the `-s` or `-tf` option. For example, the following simulation runs until it reaches 6.0 seconds.

```
!rtwdemo_rsimg -s 6.0
```

The RSim target stops and logs output data using MAT-file data logging rules.

If the model includes a From File block, the end of the simulation is regulated by the stop time setting specified in the **Solver** pane of the Configuration Parameters dialog box or with the RSim target option `-s` or `-tf`. The values in the block's time vector are ignored. However, if the simulation time exceeds the endpoints of the time and signal matrix (that is, if the final time is greater than the final time value of the data matrix), the signal data is extrapolated to the final time value.

Reading the Parameter Vector into a Rapid Simulation

To read the model's parameter vector into a rapid simulation, you must first create a MAT-file that includes the parameter structure as explained in "Creating a MAT-File That Includes a Model's Parameter Structure" on page 12-15. You can then specify the MAT-file in the command line with the `-p` option.

For example:

- 1 Build an RSim executable for the demo `rtwdemo_rsimtf`.
- 2 Modify parameters in your model and save the parameter structure.

```
param_struct = rsimgetrtp('rtwdemo_rsimtf');  
save myrsimdata.mat param_struct
```

- 3 Run the executable with the new parameter set.

```
!rtwdemo_rsimtf -p myrsimdata.mat  
  
** Starting model 'rtwdemo_rsimtf' @ Tue Dec 27 12:30:16 2005  
** created rtwdemo_rsimtf.mat **
```

- 4 Load workspace variables and plot the simulation results by entering the following commands.

```
load myrsimdata.mat  
plot(rt_yout)
```

Specifying New Signal Data File for a From File Block

If your model's input data source is a From File block, you can feed the block with input data during simulation from a single MAT-file or you can change the MAT-file from one simulation to the next. Each MAT-file must adhere to the format explained in “Creating a MAT-File for a From File Block” on page 12-19.

To change the MAT-file after an initial simulation, you specify the executable with the `-f` option and an `oldfile.mat=newfile.mat` parameter, as shown in the following example.

- 1 Set some parameters in the MATLAB workspace. For example:

```
w = 100;  
theta = 0.5;
```

- 2 Build an RSim executable for the demo `rtwdemo_rsimgtf`.

- 3 Run the executable.

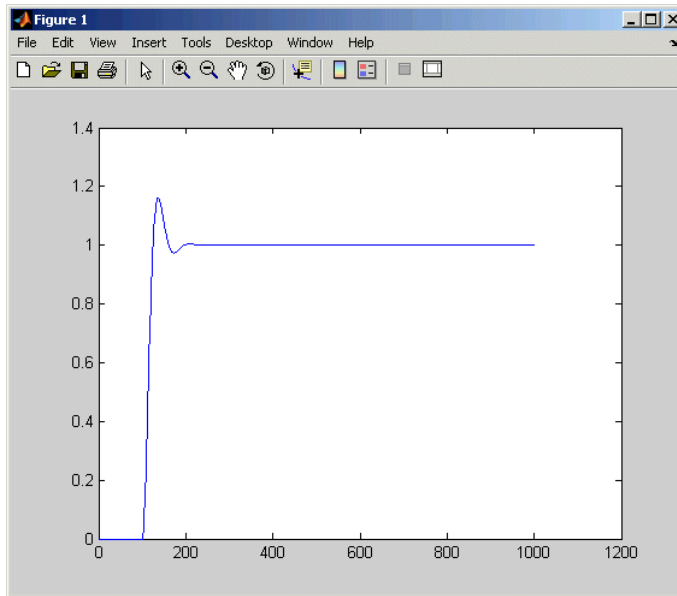
```
!rtwdemo_rsimgtf
```

The RSim executable runs a set of simulations and creates output MAT-files containing the specific simulation result.

- 4 Load the workspace variables and plot the simulation results by entering the following commands:

```
load rtwdemo_rsimgtf.mat  
plot(rt_yout)
```

The resulting plot shows simulation results based on default input data.



- 5** Create a new data file, `newfrom.mat`, that includes the following data:

```
t=[0:.001:1];  
u=sin(100*t.*t);  
tu=[t;u];  
save newfrom.mat tu;
```

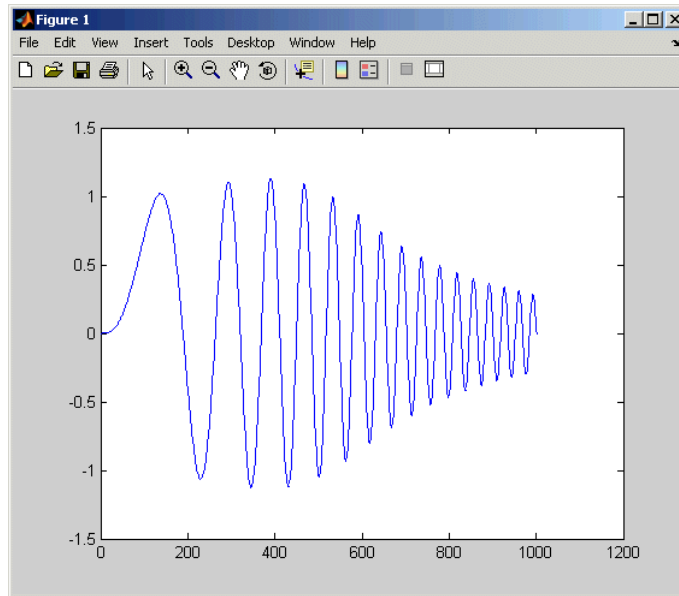
- 6** Run a rapid simulation with the new data by using the `-f` option to replace the original file, `rsim_tfdata.mat`, with `newfrom.mat`.

```
!rtwdemo_rsimtf -f rsim_tfdata.mat=newfrom.mat
```

- 7** Load the data and plot the new results by entering the following commands:

```
load rtwdemo_rsimtf.mat  
plot(rt_yout)
```

The next figure shows the resulting plot.



From File blocks require input data of type double. If you need to import signal data of a data type other than double, use an Inport block (see “Creating a MAT-File for an Inport Block” on page 12-19) or a From Workspace block with the data specified as a structure.

Workspace data must be in the format

```
variable.time
variable.signals.values
```

If you have more than one signal, use the following format.

```
variable.time
variable.signals(1).values
variable.signals(2).values
```

Specifying Signal Data File for an Inport Block

If your model’s input data source is an Inport block, you can feed the block with input data during simulation from a single MAT-file or you can change the MAT-file from one simulation to the next. Each MAT-file must adhere to

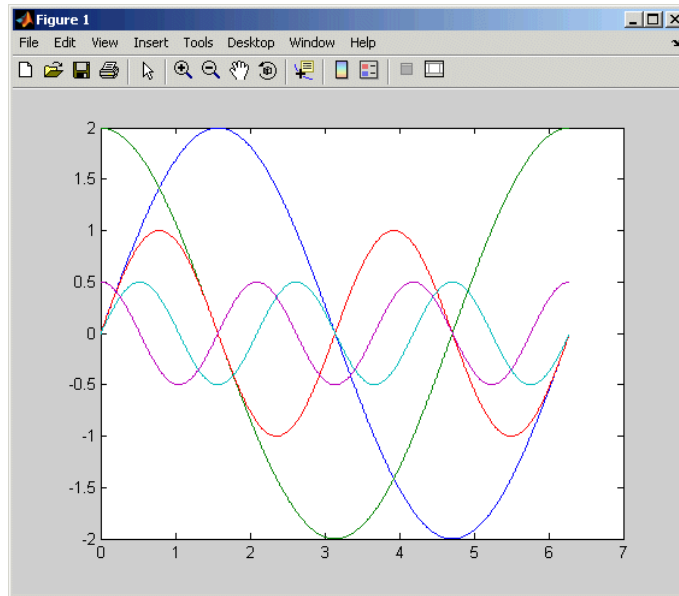
one of the three formats explained in “Creating a MAT-File for an Inport Block” on page 12-19.

To specify the MAT-file after a simulation, you specify the executable with the `-i` option and the name of the MAT-file that contains the input data. For example:

- 1 Open the model `rtwdemo_rsim_i`.
- 2 Check the Inport block parameter settings. The following Inport block parameter settings and specifications of the data you specify for the workspace variables must match settings in the MAT-file, as indicated in “Configuring Inport Blocks to Provide Rapid Simulation Source Data” on page 12-9:
 - **Main > Interpolate data**
 - **Signal Specification > Port dimensions**
 - **Signal Specification > Data type**
 - **Signal Specification > Signal type**
- 3 Build the model.
- 4 Set up the input signals. For example:

```
t=[0:0.01:2*pi]';  
s1=[2*sin(t) 2*cos(t)];  
s2=sin(2*t);  
s3=[0.5*sin(3*t) 0.5*cos(3*t)];  
plot(t, [s1 s2 s3])
```

The following plot appears.



- 5** Prepare the MAT-file by using one of the three available file formats discussed in “Creating a MAT-File for an Inport Block” on page 12-19. The following example defines a signal-and-time structure in the workspace and names it `var_single_struct`.

```
t=[0:0.1:2*pi]';
var_single_struct.time=t;
var_single_struct.signals(1).values(:,1)=2*sin(t);
var_single_struct.signals(1).values(:,2)=2*cos(t);
var_single_struct.signals(2).values=sin(2*t);
var_single_struct.signals(3).values(:,1)=0.5*sin(3*t);
var_single_struct.signals(3).values(:,2)=0.5*cos(3*t);
v=[var_single_struct.signals(1).values...
var_single_struct.signals(2).values...
var_single_struct.signals(3).values];
```

- 6** Save the workspace variable `var_single_struct` to MAT-file `rsim_i_single_struct`.

```
save rsim_i_single_struct.mat var_single_struct;
```

- 7** Run a rapid simulation with the input data by using the `-i` option. Load and plot the results.

```
!rtwdemo_rsim_i -i rsim_i_single_struct.mat

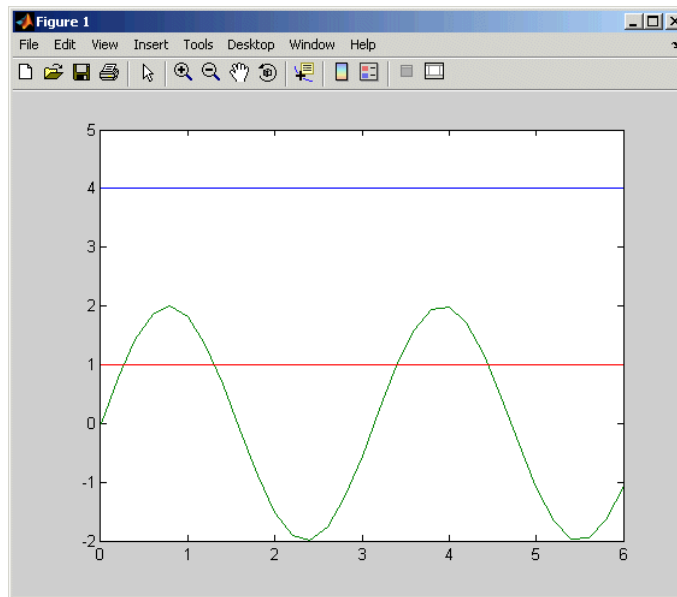
** Starting model 'rtwdemo_rsim_i' @ Tue Dec 27 14:01:20 2005
*** rsim_i_single_struct.mat is successfully loaded! ***
** created rtwdemo_rsim_i.mat **

** Execution time = 0.2683734753333333sload rsim_i_single_struct.mat;
```

- 8** Load and plot the results.

```
load rtwdemo_rsim_i.mat
plot(rt_tout, rt_yout);
```

The following plot appears.



Changing Block Parameters for an RSim Simulation

As explained in “Creating a MAT-File That Includes a Model’s Parameter Structure” on page 12-15, after you alter one or more parameters in a Simulink block diagram, you can extract the parameter vector, `model_P`, for the entire model. You can then save the parameter vector, along with a model checksum, to a MAT-file. This MAT-file can be read directly by the standalone RSim executable, allowing you to replace the entire parameter vector or individual parameter values, for running studies of variations of parameter values representing coefficients, new data for input signals, and so on.

The RSim target allows you to alter any model parameter, including parameters that include *side-effects* functions. An example of a side-effects function is a simple Gain block that includes the following parameter entry in a dialog box:

```
gain value:  2 * a
```

In general, Real-Time Workshop evaluates side-effects functions before generating code. The generated code for this example retains only one memory location entry, and the dependence on parameter `a` is no longer visible in the generated code. The RSim target overcomes the problem of handling side-effects functions by replacing the entire parameter structure, `model_P`. You must create this new structure by using the `rsimgetrtp` function and then saving it in a MAT-file, as explained in “Creating a MAT-File That Includes a Model’s Parameter Structure” on page 12-15.

RSim can read the MAT-file and replace the entire `model_P` structure whenever you need to change one or more parameters, without recompiling the entire model.

For example, assume that you changed one or more parameters in your model, generated the new `model_P` vector, and saved `model_P` to a new MAT-file called `mymatfile.mat`. To run the same `rtwdemo_rsimtf` model and use these new parameter values, use the `-p` option as shown in the following example:

```
!rtwdemo_rsimtf -p mymatfile.mat
load rtwdemo_rsimtf
plot(rt_yout)
```

If you have converted the parameter structure to a cell array for running simulations on varying data sets, as discussed in “Converting the Parameter Structure for Running Simulations on Varying Data Sets” on page 12-17, you must add an *@n* suffix to the MAT-file specification, where *n* is the element of the cell array that contains the specific input you want to use for the simulation.

The following example converts `param_struct` to a cell array, changes parameter values, saves the changes to MAT-file `mymatfile.mat`, and then runs the executable using the parameter values in the second element of the cell array as input.

```
param_struct = rsimgetrtp('rtwdemo_rsimtf');
p = param_struct.parameters;
param_struct.parameters = [];
param_struct.parameters{1} = p;
param_struct.parameters{1}

ans =

    dataTypeName: 'double'
    dataTypeId: 0
    complex: 0
    dtTransIdx: 0
    values: [-140 -4900 0 4900]
param_struct.parameters{2} = param_struct.parameters{1};
param_struct.parameters{2}.values = [-150 -5000 0 4950];
save mymatfile.mat param_struct;
!rtwdemo_rsimtf -p mymatfile.mat@2 -o rsim2.mat
```

Specifying a New Output Filename for a Simulation

If you have specified any of the **Save to Workspace** options — **Time**, **States**, **Outputs**, or **Final States** — on the **Data Import/Export** pane of the Configuration Parameters dialog box, the default is to save simulation logging results to the file `model.mat`. For example, the demo `rtwdemo_rsimtf` normally saves data to `rtwdemo_rsimtf.mat`, as follows:

```
!rtwdemo_rsimtf
created rtwdemo_rsimtf.mat
```

You can specify a new output filename for data logging by using the `-o` option when you run an executable.

```
!rtwdemo_rsimtf -o rsim1.mat
```

In this case, the set of parameters provided at the time of code generation, including any From File block data, is run.

Specifying New Output Filenames for To File Blocks

In much the same way as you can specify a new system output filename, you can also provide new output filenames for data saved from one or more To File blocks. To do this, specify the original filename at the time of code generation with a new name as shown in the following example:

```
!rtwdemo_rsimtf -t rtwdemo_rsimtf_data.mat=mynewsimdata.mat
```

In this case, assume that the original model wrote data to the output file `rtwdemo_rsimtf_data.mat`. Specifying a new filename forces RSim to write to the file `mynewsimdata.mat`. This technique allows you to avoid overwriting an existing simulation run.

Rapid Simulation Target Limitations

The RSim target is subject to the following limitations:

- The RSim target does not support algebraic loops.
- The RSim target does not support MATLAB function blocks.
- The RSim target does not support noninlined M-file, Fortran, or Ada S-functions.
- If an RSim build includes referenced models (by using Model blocks), these models must be set up to use fixed-step solvers for code to be generated for them. The top model, however, can use a variable-step solver as long as all blocks in the referenced models are discrete.
- In certain cases, changing block parameters can result in structural changes to your model that change the model checksum. An example of such a change would be changing the number of delays in a DSP simulation. In such cases, you must regenerate the code for the model.
- Variable-step solver support for RSim is not available on Windows platforms when you use the following compilers:
 - Watcom C/C++ compiler
 - Borland C/C++ compiler

Targeting Tornado for Real-Time Applications

Resources for Tornado Applications (p. 13-2)	Describes resources provided by The MathWorks and Wind River Systems for creating VxWorks real-time applications
Tornado Application Architecture (p. 13-4)	Discusses the hardware, software, code modules, processes, and tasks that comprise a Real-Time Workshop Tornado target VxWorks application
Installing the Tornado Software (p. 13-10)	Provides some MathWorks-specific information you will need when installing Tornado software
Implementing a Tornado Application (p. 13-12)	Discusses the design and implementation of a VxWorks real-time application using Real-Time Workshop
Building the Application (p. 13-21)	Describes how to use Real-Time Workshop to build a real-time application that runs under VxWorks
Automatic Download and Execution (p. 13-21)	Describes what happens after the build process if you have specified automatic downloading
Manual Download and Execution (p. 13-22)	Describes techniques for manually downloading compiled files and starting program execution

Resources for Tornado Applications

In this section...
“Introduction” on page 13-2
“Tornado Environment” on page 13-2
“Tornado Target” on page 13-3
“VxWorks Block Library” on page 13-3

Introduction

This section describes resources provided by The MathWorks and Wind River Systems, Inc., for converting a Simulink model to a real-time VxWorks application.

Tornado Environment

Tornado is an integrated development and real-time execution environment that is available from Wind River Systems, Inc. You can use Tornado to develop an application on a host system, download the application to a real-time processor, and run the application, optionally monitoring its activities and changing its parameters. Tornado has many UNIX-like features and runs on a variety of host systems and real-time processors. Tornado includes

- **Application building tools:** Compiler, Linker, Make utility, Archive utility
- **Interactive development tools:** Editor, Debugger, Browser, Configuration tool, Command shell
- **VxWorks:** A high-performance real-time operating system
- **StethoScope:** An optional data acquisition and graphical monitoring tool

The *Tornado User's Guide*, and other Tornado documentation give complete information about Tornado. This chapter does not repeat information that is available in the Tornado documentation.

Tornado Target

To support the Tornado environment, Real-Time Workshop provides the *Tornado target*, which you can use to convert a Simulink model to code that works with Tornado tools, runs under VxWorks, and can be monitored by Tornado StethoScope, or monitored and tuned with Simulink external mode. See Chapter 6, “External Mode” for information about Simulink external mode.

VxWorks Block Library

The *VxWorks block library* (vxlib1) is part of the Real-Time Workshop library. You can access the VxWorks library by opening the Simulink Library Browser, expanding the **Real-Time Workshop** entry, and clicking **VxWorks**. Alternatively, type vxlib1 at the MATLAB prompt.

The blocks in the VxWorks library allow you to model and generate code for asynchronous event handling, including servicing hardware-generated interrupts, maintenance of timers, asynchronous read and write operations, and spawning asynchronous tasks under VxWorks. See Chapter 16, “Asynchronous Support” for a detailed description of the blocks in the VxWorks library.

Note The older Interrupt Templates library (vxlib) is obsolete. It is provided only to allow models created prior to Real-Time Workshop 6.0 to continue to operate. If you have models that use vxlib blocks, you should change them to use vxlib1 blocks.

Tornado Application Architecture

In this section...

“Hardware Architecture” on page 13-4

“Software Architecture” on page 13-5

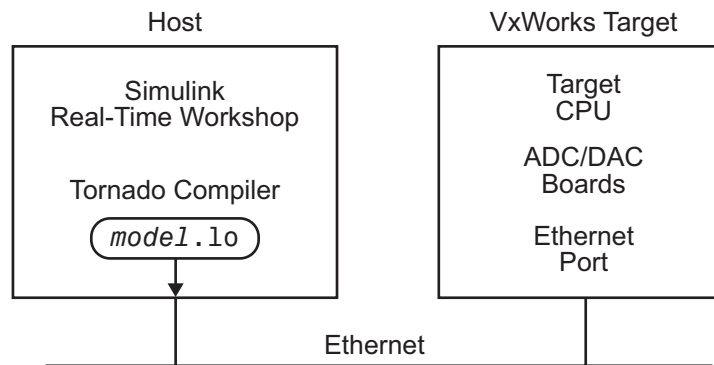
“Module Architecture” on page 13-6

“Host Processes” on page 13-6

“VxWorks Tasks” on page 13-7

Hardware Architecture

In a typical VxWorks-based real-time system, the hardware consists of a UNIX or PC host running Simulink and Real-Time Workshop, connected by Ethernet to a VxWorks CPU. The chassis containing the VxWorks CPU may also contain I/O boards with A/D and D/A converters to communicate with external hardware. The next figure shows the arrangement.



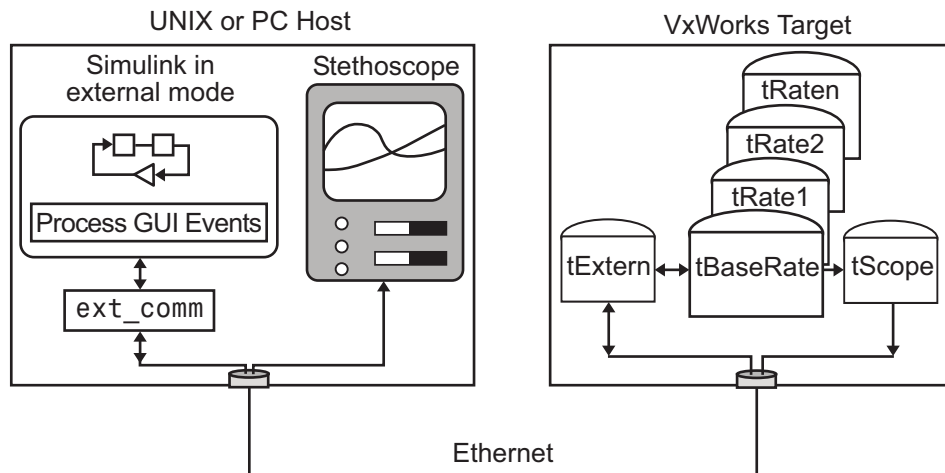
In this figure and the following sections, the VxWorks CPU and associated I/O boards are called the *VxWorks target*. Be careful not to confuse the VxWorks target with the Tornado target. The former is hardware; the latter is a software specification that Real-Time Workshop uses to convert a Simulink model to a VxWorks application.

Software Architecture

The real-time code is compiled on the UNIX or PC host using the cross-compiler supplied with the VxWorks package. The object file (*model.1o*) output from the Real-Time Workshop program builder is downloaded to the VxWorks target over the Ethernet connection using the Tornado WindSh command.

The real-time program executes on the VxWorks target, and interfaces with external hardware using the I/O devices installed on the target. If you have configured the program appropriately, you can monitor it using StethoScope, or monitor it and change its parameters using Simulink external mode. StethoScope and Simulink execute on the host workstation, and use tasks on the VxWorks target to handle communication.

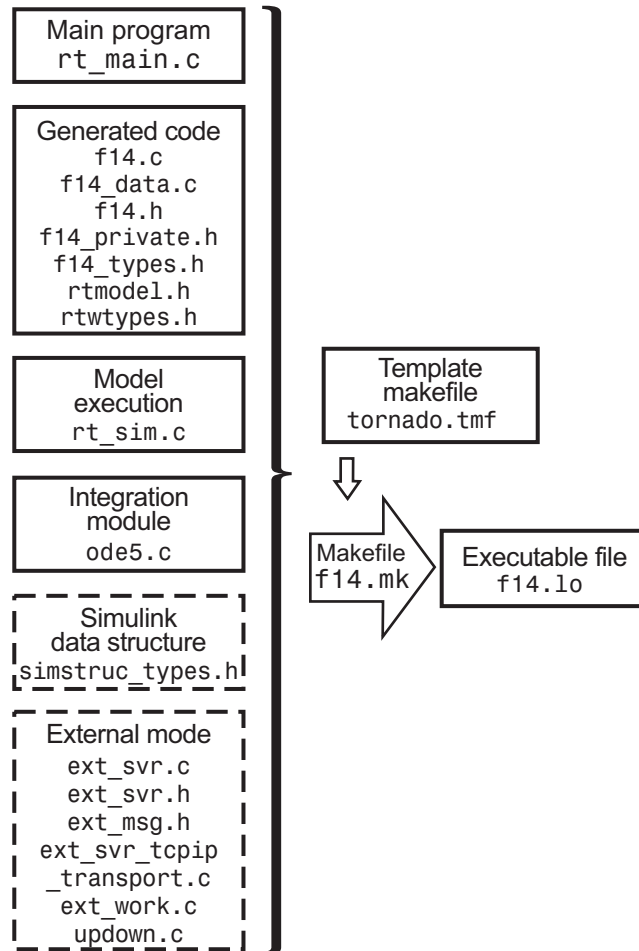
This figure shows the structure of a VxWorks application. The figure shows both StethoScope and Simulink, but only one of them can be used with a given compiled image. To switch to the other interface, you must rebuild with appropriate options, then redownload and restart the program. See “Setting Target-Specific Options” on page 13-15 for more information.



The real-time program creates VxWorks tasks to run on the real-time system, and to communicate with Simulink if the program uses Simulink external mode. StethoScope creates its own tasks to collect data.

Module Architecture

This figure shows the code modules used to build a VxWorks real-time program for the f14 example model. Dashed boxes indicate optional modules, such as those that implement external mode.



Host Processes

Various processes can run on the host side to implement Tornado tools and Simulink capabilities, and optionally to communicate with the real-time

program over the Internet. The host processes that communicate with the real-time program depend on whether you use StethoScope or Simulink external mode.

- If you use StethoScope, the StethoScope user interface module runs on the host. This module communicates with the real-time program running on the VxWorks target to retrieve model data and plot time histories.
- If you use Simulink external mode, and change a parameter in the block diagram, Simulink calls the external link MEX-file to download any new parameter values to the real-time program.

VxWorks Tasks

Various tasks run on the VxWorks target. Some execute the real-time program, while others are optional and provide communication with the host.

Execution Tasks

You can run the real-time program in either single-tasking or multitasking mode. The code for both modes is located in

```
matlabroot/rtw/c/tornado/rt_main.c
```

Real-Time Workshop compiles and links `rt_main.c` with the model code during the build process. When the real-time program begins execution, `rt_main.c` starts tasks for single-tasking or multitasking if they are not already running.

Single-Tasking. By default, the model is run as one task, `tSingleRate`. This might actually provide the best performance (highest base sample rate) depending on the model.

The `tSingleRate` task runs at the base rate of the model and executes all necessary code for the slower sample rates. Execution of the `tSingleRate` task is normally blocked by a call to the VxWorks `semTake` routine. When a clock interrupt occurs, the interrupt service routine calls the `semGive` routine, which causes the `semTake` call to return. Once enabled, the `tSingleRate` task executes the model code for one time step. The loop then waits at the top by again calling `semTake`.

For more information about the `semTake` and `semGive` routines, refer to the *VxWorks Reference Manual*. By default, it runs at a relatively high priority (30), which allows it to execute without interruption from background system activity.

Multitasking. Optionally, the model can run as multiple tasks, one for each sample rate in the model.

- `tBaseRate` — This task executes the components of the model code run at the base (highest) sample rate. By default, it runs at a relatively high priority (30), which allows it to execute without interruption from background system activity.
- `tRate n` — The program also spawns a separate task for each additional sample rate in the system. These additional tasks are named `tRate1`, `tRate2`, ..., `tRate n` , where n is the slowest sample rate in the system. The priority of each additional task is one lower than its predecessor (`tRate1` has a lower priority than `tBaseRate`).

Communication Tasks

You can optionally monitor and change the parameters of the executing real-time program using either `StethoScope` or `Simulink` external mode, but not both with the same compiled image.

StethoScope Tasks. To enable real-time data collection and display, `StethoScope` runs one or more `VxWorks` tasks, such as `tScopeDaemon` and `tScopeLink`. In single-tasking mode, `tSingleRate` collects signals; in multitasking mode, `tBaseRate` collects them. Both perform the collection on every base time step. When idle time exists because the model is waiting for the next time step, a `StethoScope` task sends the data to the host for display. For more about `StethoScope` tasks, see the `VxWorks` documentation.

External Mode Tasks. To enable changing model parameters and collecting data for display, Simulink external mode runs the VxWorks task tExtern. The source code for tExtern is located in *matlabroot/rtw/c/src/ext_svr.c*. The tExtern task implements the server side of a socket stream connection that accepts data transferred between Simulink and the real-time program. The task runs at a lower priority than the lowest priority model task. To tune parameters, tExtern waits for a message to arrive from Simulink. When a message arrives, tExtern retrieves it and modifies the specified parameters accordingly.

Installing the Tornado Software

In this section...
“Introduction” on page 13-10
“Installing and Configuring Tornado” on page 13-10
“Connecting to the VxWorks Target” on page 13-10
“Verifying the Tornado Installation” on page 13-11

Introduction

Before you can use Tornado with Simulink and Real-Time Workshop to create VxWorks applications, you must perform some installation, configuration, and verification steps. See the Tornado documentation for instructions on all aspects of Tornado installation and configuration. This section provides additional information specific to Simulink and Real-Time Workshop.

Installing and Configuring Tornado

The first step is to install and configure Tornado on your host and target hardware. If you want to use Simulink external mode with your VxWorks program, you must configure your VxWorks kernel to support sockets by including the `INCLUDE_NET_INIT`, `INCLUDE_NET_SHOW`, and `INCLUDE_NETWORK` options in your VxWorks image.

Connecting to the VxWorks Target

After completing the installation process, you are ready to connect the host workstation to the VxWorks target. The first step is ensuring that the Tornado registry (`wtxregd`) is running. Typically, it is configured to start running by the host operating system automatically at reboot. However, it can also be started interactively.

Next, start the target server. This server provides communication between the Tornado tools on the host and the agent on the VxWorks target. You can do this from within the Tornado development environment. On Windows, you can use a command shell to enter:

```
tgtsvr target_network_name -A -V
```

Additional options might be required, such as `-c` for the VxWorks core image location.

You may need to enter a routing table entry into VxWorks if your host is not on the same local network (subnet) as the VxWorks system. See `routeAdd` in the *VxWorks Reference Guide* for more information.

To check that VxWorks can properly respond to your host over the network, use the host command:

```
ping <target_name>
```

Verifying the Tornado Installation

To verify the installation, run one of the VxWorks demonstration programs to ensure you can boot your VxWorks target and download object files to it. Consult the Tornado documentation as needed to configure and debug your Tornado installation. Be sure that it is fully functional before you try to use it with Simulink and Real-Time Workshop.

Implementing a Tornado Application

In this section...
“Designing the Simulink Model” on page 13-12
“Adding Device Driver Blocks” on page 13-12
“Specifying Code Generation Options” on page 13-13
“Configuring the Template Makefile” on page 13-19

Designing the Simulink Model

A Simulink model to be converted into a VxWorks real-time program can implement any Simulink capability supported by Real-Time Workshop, and has no constraints beyond those that apply to any model intended for code generation by Real-Time Workshop. See the “Simulink” documentation and “Real-Time Workshop” documentation for information.

Adding Device Driver Blocks

The real-time program communicates with the I/O devices installed in the VxWorks target chassis by using a set of device drivers. These device drivers contain the necessary code that runs on the target processor for interfacing to specific I/O devices.

To make device drivers easy to use, they are implemented as Simulink S-functions using C/C++ MEX-files. This means you can connect them to your model like any other block and the code generator automatically includes a call to the block’s C/C++ code in the generated code. You can have multiple instances of device driver blocks in your model.

You can inline S-functions by using the Target Language Compiler. Inlining allows you to restrict function calls to only those that are necessary for the S-function. This can greatly increase the efficiency of the S-function. For more information about inlining S-functions, see Chapter 11, “S-Function Target” and the *Real-Time Workshop Target Language Compiler* documentation.

For additional information on creating device drivers, see the Real-Time Workshop Embedded Coder documentation and Chapter 11, “S-Function Target”.

Specifying Code Generation Options

To specify the code generation options necessary for a Tornado application, open the Model Explorer or the Configuration Parameters dialog box, then select configuration panes and set options as described in this section. The options that you specify set the appropriate macros in the template makefile, causing any necessary additional steps to be performed during the build process.

Depending on your application, you may also want to specify other code generation options, such as those that control parameter inlining and tunability. For more information, see “Configuring Real-Time Workshop Code Generation Parameters” on page 2-49. You must also specify some information by editing the template makefile, as described in “Configuring the Template Makefile” on page 13-19.

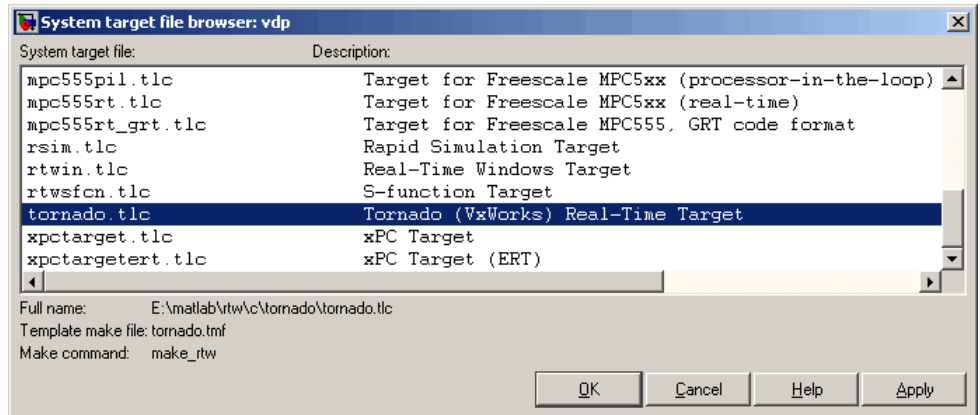
Selecting the Tornado Target

To specify the Tornado (VxWorks) target for code generation,

- 1** Select the **Real-Time Workshop > General** pane.
- 2** Click **Browse**.

The System Target File Browser opens.

- 3** Select `tornado.tlc` (the Tornado target) in the left column, then click **OK**.



Specifying the Tornado target adds a **Real-Time Workshop > Tornado Target** pane and sets **Real-Time Workshop > General** options as follows:

- **System target file:** tornado.tlc
- **TLC Options:** -p0 -aWarnNonSaturatedBlocks=0
- **Make command:** make_rtw
- **Template makefile:** tornado.tmf

If you will use a template makefile with a nondefault name, as described in “Configuring the Template Makefile” on page 13-19, you must replace the default **Template makefile** name `tornado.tmf` with the name you want to use instead.

Specifying the Solver

Because generated code cannot use variable-step solvers as Simulink can, you must specify a fixed-step solver and set other options:

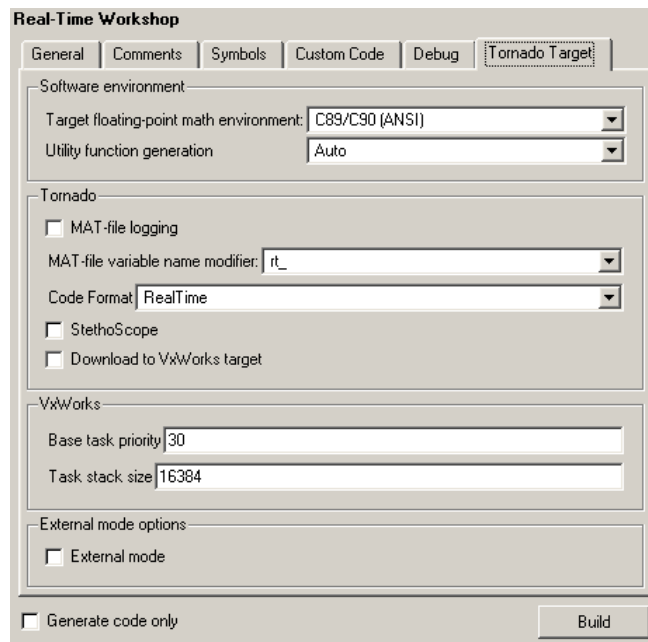
- 1 Select the **Solver** pane.
- 2 Set **Type** to Fixed-step.
- 3 Select a **Solver** integration algorithm as appropriate to your model:
 - For a model with any continuous states, choose a fixed-step algorithm.

- For a discrete model, choose discrete (no continuous states).

4 Set **Fixed-step size** to the desired integration step size.

Setting Target-Specific Options

Once you have selected the Tornado target, as described above, you can set target-specific code generation options. First select the **Tornado Target** pane. The next figure shows the default Tornado configuration.



You can change options on the **Tornado Target** pane to enable and configure the capabilities described in this section.

MAT-File Logging. Select **MAT-file logging** to enable data logging during program execution. The program creates a file named *model.mat* at the end of program execution. This file contains the variables that you specified in the **Data Import/Export** pane of the Configuration Parameters dialog box.

Real-Time Workshop adds a prefix or suffix to the names of the **Data Import/Export** pane variables that you select for logging. The **MAT-file variable name modifier** menu lets you select this prefix or suffix.

By default, the MAT-file is created in the root directory of the current default device in VxWorks. This is typically the host file system from which VxWorks was booted. Other remote file systems can be used as a destination for the MAT-file using rsh or ftp network devices or NFS. See the *VxWorks Programmer's Guide* for more information.

If a device or filename other than the default is desired, use the OPTS flag to add "-DSAVEFILE=*filename*" (with quotes) to the **Make command** shown on the **Real-Time Workshop > General** pane. For example:

```
make_rtw OPTS="-DSAVEFILE=MyFileName"
```

Generated Code Format. Use **Code format** to specify the RealTime or RealTimeMalloc code generation format.

StethoScope Monitoring. Select **StethoScope** to enable the use of StethoScope with the generated executable. You cannot select both **StethoScope** and **External mode** at the same time.

With StethoScope, you can access the output of any block in the model (as executed by the real-time program) and display this data on the host. You can install signals in StethoScope in one of two ways:

- From the real-time program using the rtBlockIOSignals data structure. See "C-API for Interfacing with Signals and Parameters" on page 17-2 for details.
- With the Tornado WindSh command while the real-time program is running. See the *StethoScope User's Manual* for details.

When you start the downloaded program, you must specify two command-line arguments that control the block names used by StethoScope. See "Starting the Program" on page 13-23 for information about these and other command-line arguments.

Automatic Download. Select **Download to VxWorks target** to enable automatic downloading of the generated program.

Base Task Priority. Specify the priority with which the base rate task for the model is to be spawned. The default value is 30. For a multirate, multitasking model, Real-Time Workshop increments the priority of each subrate task by one. For example, if a model includes two subrate tasks and the priority of the base rate task is 30, the priorities for the subrate tasks are 31 and 32.

Note, the value you specify for this option will be overridden by a base priority specified in a call to the `rt_main()` function spawned as a task.

Task Stack Size. Specify the stack size to be used in calls to the VxWorks function `taskSpawn()`, which spawn tasks for the base rate and subrates of the model. The default size is 16384 bytes.

The VxWorks system target file uses the value you specify for this option to set the TLC variables `MaxStackSize` and `MaxStackVariableSize`. The variables are set as follows:

<code>MaxStackSize</code>	One-half the size of the Task stack size setting (8192 bytes by default)
<code>MaxStackVariableSize</code>	One-half the size of the <code>MaxStackSize</code> (4096 bytes by default)

These variable settings help ensure the generated code does not exceed the stack size allocated for each task. Thus, you should tune this option to the match the requirements of your generated code.

Simulink External Mode. Simulink external mode provides a mechanism to monitor signals in your model and download new parameter values to the executing real-time program. See Chapter 6, “External Mode” for information about external mode. This section does not repeat the information available there.

Communication between Simulink and a real-time VxWorks program uses the sockets network API and requires an Ethernet connection that supports TCP/IP. The Tornado environment must be configured to provide these capabilities. See “Installing the Tornado Software” on page 13-10 for more information.

To configure your application to use external mode, select **External mode** in the **Real-Time Workshop > Tornado Target** pane. You cannot select both **External mode** and **StethoScope** at the same time. Two **Host/Target interface** options appear below the **External mode** check box: **Transport layer** and **MEX-file arguments**.

The value of **Transport layer** is preset to `tcpip` and cannot be changed; Tornado supports only the TCP/IP protocol. To the right of the **Transport layer** field, the string `MEX-file name: ext_comm` names the MEX file that the Simulink external mode transport layer uses with the Tornado target. This name cannot be changed. The full pathname of the MEX-file is:

```
matlabroot/toolbox/rtw/rtw/ext_comm.*
```

where `*` is a host-dependent MEX-file extension.

The value of **MEX-file arguments** must be a string of arguments to be passed to the transport layer MEX-file. The format is:

```
'target_network_name' [verbosity] [TCP port number]
```

You must provide the first argument, which specifies the name of the VxWorks target system. You can also specify a verbosity and a TCP port number. Verbosity can be 0 (the default) or 1 if extra information is desired. The TCP port number can range from 256 to 65535; the default is 17725. If a conflict exists with other software using port 17725, you can change the port with the third argument. The arguments are positional, so you must specify a verbosity if you specify a port number.

For example, to specify a target system called `halebopp`, the default verbosity of 0, and the nondefault TCP port 18000, give **MEX-file arguments** the value:

```
'halebopp' 0 18000
```

You can also enable verbose mode by using the `OPTS` flag to add `-DVERBOSE` to the **Make command** shown on the **Real-Time Workshop > General** pane. For example:

```
make_rtw OPTS="-DVERBOSE"
```

Configuring the Template Makefile

In addition to setting code generation options, you must enter some information into the VxWorks makefile, which by default is named `tornado.tmf`. You can rename the makefile if you like, provided that you also specify the name as a code generation parameter, as described in “Selecting the Tornado Target” on page 13-13.

The makefile information you must enter describes the environment in which you are using VxWorks. This section lists the lines in the file that you must edit. For additional information, see “Rapid Prototyping System-Independent Components” on page 7-27.

Specifying the VxWorks Target Type and CPU

To provide information used by VxWorks, you must specify the type of target and the specific CPU on the target. The target type is then used to locate the correct cross-compiler and linker for your system.

The CPU type is used to define the CPU macro that is in turn used by many of the VxWorks header files. See the *VxWorks Programmer’s Guide* for information on the appropriate values to use.

This information is in the section labeled

```
#----- VxWorks Configuration -----
```

Edit the following lines to reflect your setup.

```
VX_TARGET_TYPE = 68k
CPU_TYPE = MC68040
```

Specifying the Tornado Tool Locations

To locate the Tornado tools used in the build process, the following three macros must either be defined in the environment or specified in the template makefile. Modify these macros to reflect your setup.

```
#----- Tool Locations -----
WIND_BASE = c:/Tornado
WIND_REGISTRY = $(COMPUTERNAME)
```

```
WIND_HOST_TYPE = x86-win32
```

Resolving Header File Paths

Tornado 2.2.1 installs some standard header files in an include directory under the target compiler target directory. For example, if you are targeting the Freescale 68xxx processor for VxWorks with the GCC 2.96 compiler, Tornado installs the header files at the following location:

```
WIND_BASE/host/WIND_HOST_TYPE/lib/gcc-lib/m68k-wrs-vxworks/gcc-2.96/include
```

To use Tornado 2.2.1 or higher with the Tornado (VxWorks) Real-Time Target, `tornado.tlc`, you must enable a macro in template makefile `tornado.tmf`. To enable the macro,

- 1 Open `matlabroot/rtw/c/tornado/tornado.tmf`.
- 2 Search for `TORNADO_TARGET_COMPILER_INCLUDES`.
- 3 Uncomment the macro `TORNADO_TARGET_COMPILER_INCLUDES` and set it to the include directory that contains the Tornado standard header files.

Given the path shown above, you would set the macro as follows:

```
TORNADO_TARGET_COMPILER_INCLUDES =  
$(WIND_BASE)/host/$(WIND_HOST_TYPE)/lib/gcc-lib/m68k-wrs-vxworks/gcc-2.96/include
```

If you are using a version of Tornado before 2.2.1, leave the macro commented out.

Configuring for Automatic Downloading

To perform automatic downloading during the build process, you must specify the target name and host name that the Tornado target server are to run on. Modify these macros to reflect your setup.

```
#----- Macros for Downloading to Target-----  
TARGET = targetname  
TGTSVR_HOST = hostname
```


Building the Application

Once you have completed the operations previously described in “Installing the Tornado Software” on page 13-10 and “Implementing a Tornado Application” on page 13-12, you are ready to build the real-time application:

- 1 If you specified automatic downloading, reset VxWorks by pressing `control-x` on the host console or power-cycling the VxWorks chassis. This ensures that no dangling processes or stale data exist in VxWorks.

Note Be sure to reset VxWorks again before every subsequent build and automatic download.

- 2 Click the **Build** button in the **Real-Time Workshop** pane of the Model Explorer or the Configuration Parameters dialog box.

The resulting object file is named with the `.lo` extension, which stands for *loadable object*. This file is compiled for the target processor using the cross-compiler specified in the makefile.

Automatic Download and Execution

If you specified automatic downloading, the following actions occur automatically as soon as the build is complete:

- 1 The target server is started.
- 2 The object file is downloaded.
- 3 If **StethoScope** was selected, the StethoScope object files (`libxdr.so`, `libutilstssip.so`, and `libscope.so`) are downloaded.
- 4 The downloaded program is started on the target.

If **StethoScope** was selected, you can now start StethoScope on the host. See the *StethoScope User's Manual* for more information.

Manual Download and Execution

In this section...
“Introduction” on page 13-22
“Resetting VxWorks” on page 13-22
“Downloading Files” on page 13-22
“Starting the Program” on page 13-23

Introduction

If you did not specify automatic downloading, you must use Tornado tools to download and start the program.

Resetting VxWorks

Reset VxWorks by pressing control-x on the host console or power-cycling the VxWorks chassis. This ensures that no dangling processes or stale data exist in VxWorks.

Note Be sure to reset VxWorks again before every subsequent manual download.

Downloading Files

To download the real-time program, use the VxWorks `ld` routine from within WindSh (wind shell). WindSh can also be run from the command line or from within the Tornado development environment.

For example, if you want to download the file `vx_equal.lo`, which is in the `/home/my_working_dir` directory, use the following commands at the WindSh prompt.

```
cd "/home/my_working_dir"  
ld <vx_equal.lo
```

You will also need to load the StethoScope libraries if the **StethoScope** option was selected during the build. The *Tornado User's Guide* describes the `ld` library routine.

Starting the Program

The real-time program defines a function, `rt_main()`, which spawns the tasks to execute the model code, and communicate with Simulink if you selected external mode during the build procedure. It also initializes StethoScope if you selected this option during the build procedure.

The `rt_main` function is defined in the `rt_main.c` application module. This module is located in the `matlabroot/rtw/c/tornado` directory.

The `rt_main` function takes six arguments, and is defined by the following ANSI C function prototype:

```
RT_MODEL * (*model_name)(void),
char_T    *optStr,
char_T    *scopeInstallString,
int_T     scopeFullNames,
int_T     priority,
int_T     port
```

The following table lists the arguments to this function.

Arguments to the `rt_main` RT_MODEL

Argument	Description
<code>model_name</code>	Pointer to the entry point function in the generated code. This function has the same name as the Simulink model. It registers the local functions that implement the model code by adding function pointers to the model's <code>rtM</code> . See Chapter 7, "Program Architecture" for more information.

Arguments to the rt_main RT_MODEL (Continued)

Argument	Description
optStr	<p>Options string used to specify a stop time (-tf) and whether to wait (-w) in external mode for a message from Simulink before starting the simulation. An example options string is</p> <pre data-bbox="753 527 911 552">"-tf 20 -w"</pre> <p>The -tf option overrides the stop time that was set during code generation. If the value of the -tf option is inf, the program runs indefinitely.</p>
scopeInstallString	<p>Character string that determines which signals are installed to StethoScope. Possible values are</p> <ul data-bbox="716 800 1310 986" style="list-style-type: none"> • NULL — Install no signals. This is the default value. • "*" — Install all signals. • "[A-Z]*" — Install signals from blocks whose names start with an uppercase letter. <p>Specifying any other string installs signals from blocks whose names start with that string.</p>
scopeFullNames	<p>Determines whether StethoScope uses full hierarchical block names for the signals it accesses or just the individual block name. Possible values are</p> <ul data-bbox="716 1263 1270 1367" style="list-style-type: none"> • 1 Use full block names. • 0 Use individual block names. This is the default value. <p>It is important to use full block names if your program has multiple instances of a model or S-function.</p>

Arguments to the `rt_main RT_MODEL` (Continued)

Argument	Description
<code>priority</code>	Priority of the program's highest priority task (<code>tBaseRate</code>). Not specifying any value (or specifying a value of 0) assigns <code>tBaseRate</code> to the default priority, 30.
<code>port</code>	Port number that the external mode sockets connection should use. The valid range is 256 to 65535. The port number defaults to 17725.

Passing `optStr` by Using the Template Makefile

You can also pass the `-w` and `-tf` options (see `optStr` in the preceding table) to `rt_main` by using the `PROGRAM_OPTS` macro in `tornado.tmf`. `PROGRAM_OPTS` passes a string of the form

```
-opt1 val1 -opt2 val2
```

In the following examples, the `PROGRAM_OPTS` directive sets an infinite stop time and instructs the program to wait for a message from Simulink before starting the simulation. The argument string must be delimited by single quotes nested within double quotes:

```
PROGRAM_OPTS = "'-tf inf -w'"
```

Including the single quotes ensures that the argument string is passed to the target program correctly under both Windows and UNIX.

Calling `rt_main`

To begin program execution, call `rt_main` from WindSh. For example,

```
sp(rt_main, vx_equal, "-tf 20 -w", "*", 0, 30, 17725)
```

- Begins execution of the `vx_equal` model
- Specifies a stop time of 20 seconds
- Provides access to all signals (block outputs) in the model by StethoScope

- Uses only individual block names for signal access (instead of the hierarchical name)
- Uses the default priority (30) for the `tBaseRate` task
- Uses TCP port 17725, the default

Inserting Custom Code Into Generated Code

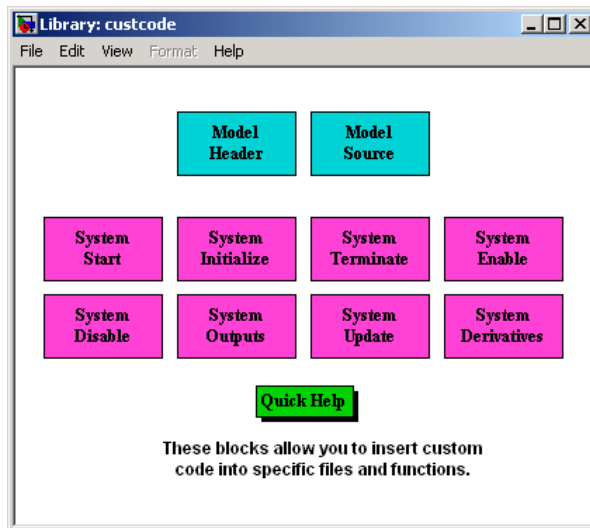
The following sections explain how to use blocks in the Custom Code block library to insert custom code into the code generated for a model. This chapter includes the following topics:

Custom Code Library (p. 14-2)	Discusses blocks that insert custom code into the generated model code
Example: Using a Custom Code Block (p. 14-6)	Shows an example of how to use a custom code block
Custom Code in Subsystems (p. 14-9)	Discusses the use of Custom Code blocks within atomic subsystems
Preventing User Source Code from Being Deleted from Build Directories (p. 14-10)	Explains how to preserve custom code during the build process

Custom Code Library

The Custom Code library contains blocks that enable you to insert your own C or C++ code into specific functions within code generated by Real-Time Workshop for root models and subsystems. These blocks are a superset of code customization capabilities built into the **Custom Code** Configuration Parameters dialog box, and provide greater flexibility in terms of code placement than the controls on the dialog box.

The Custom Code library is part of the Real-Time Workshop library. You can access the Real-Time Workshop library by using the Simulink Library Browser. You can access Custom Code blocks by using the Real-Time Workshop library or by entering the MATLAB command `rtwlib` and then double-clicking the Custom Code Library block within it. Alternatively, you can enter the command `custcode`.



This chapter discusses use of the Custom Code library only.

Note If you need to integrate custom C++ code with generated C code or vice versa, see “Integrating C and C++ Code” on page 10-80 for information on language compatibility requirements.

All Custom Code blocks except for Model Header and Model Source can be dragged into either root models or atomic subsystems. Model Header and Model Source blocks can only be placed in root models.

Note You can use models containing Custom Code blocks as submodels (models referenced by Model blocks). However, when simulation targets for submodels are generated, all Custom Code blocks within them are ignored. On the other hand, when submodel code is generated to create Real-Time Workshop targets, custom code is included and is compiled in the generated code.

The Custom Code library contains ten blocks that insert custom code into the generated model files and functions. You can view the blocks either by

- Expanding the Custom Code node (under Real-Time Workshop library) in the Simulink Library Browser
- Right-clicking the Custom Code sublibrary icon in the right pane of the Simulink Library Browser

The latter method opens the window shown in the previous section.

The two blocks on the top row contain text fields for inserting custom code at the top and bottom of

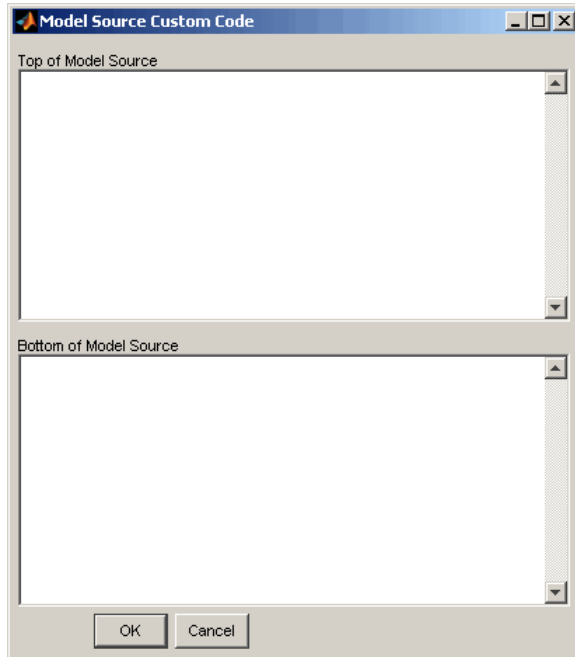
- *model.h* — Model Header File block
- *model.c* or *model.cpp* — Model Source File block

Each block contains two fields, in which you type or paste code and comments:

- Top of Model Source/Header

- Bottom of Model Source/Header

The next figure shows the ModelSource block dialog box.



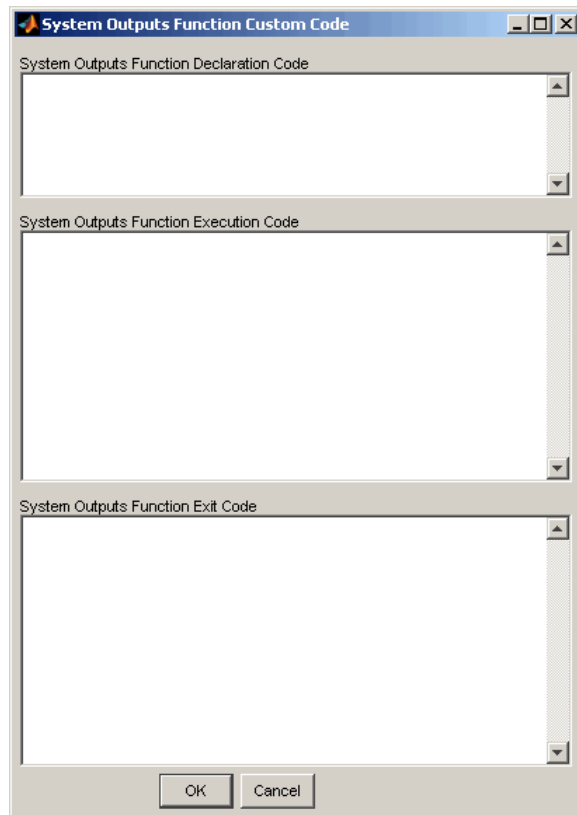
The eight function blocks in the second and third rows contain text fields to insert custom code sections at the top and bottom of these designated model functions:

- SystemStart — System Start function block
- SystemInitialize — System Initialize function block
- SystemTerminate — System Terminate function block
- SystemEnable — System Enable function block
- SystemDisable — System Disable function block
- SystemOutputs — System Outputs function block
- SystemUpdate — System Update function block

- SystemDerivatives — System Derivatives function block

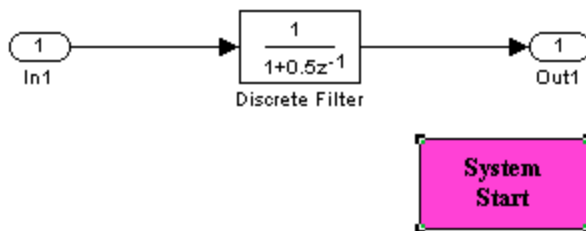
Each of these blocks provides a System Outputs Function Custom Code dialog box that contains three fields:

- Declaration code
- Execution code
- Exit code

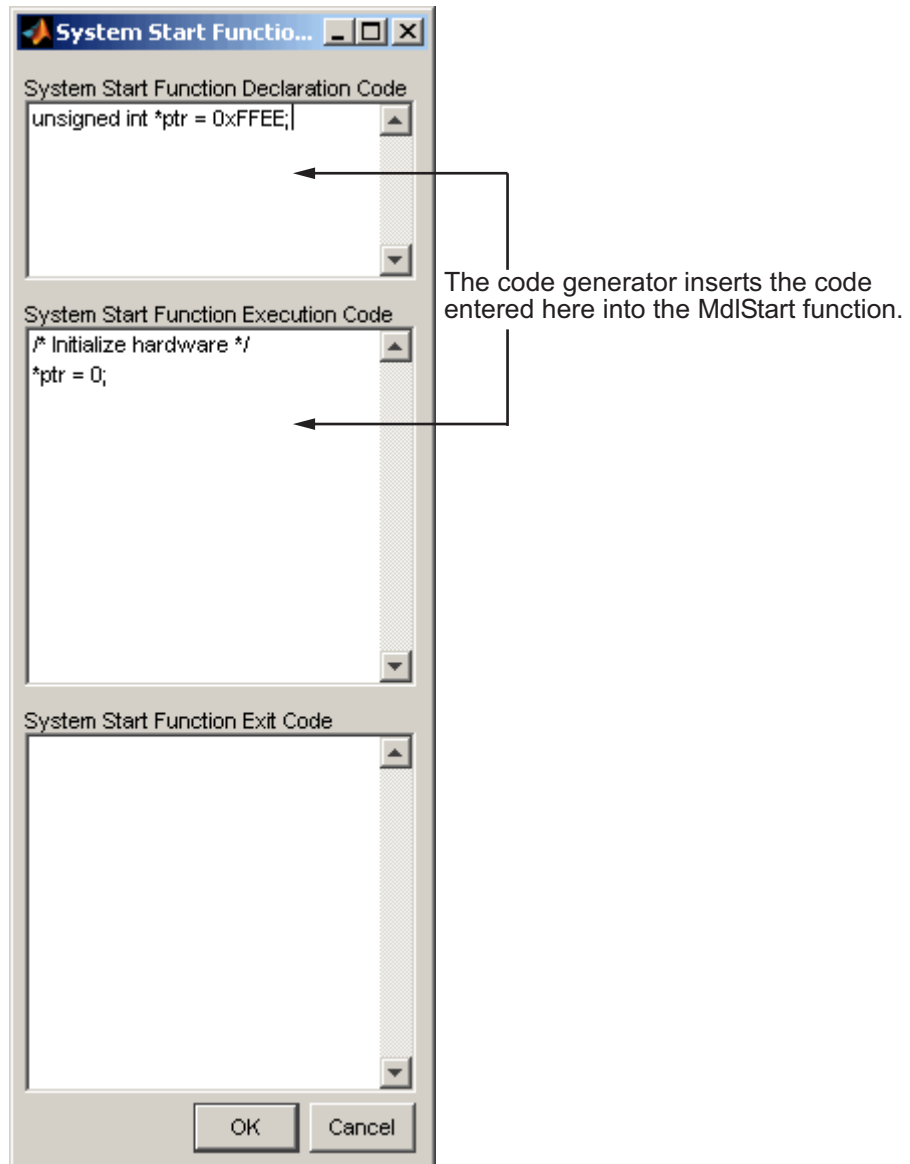


Example: Using a Custom Code Block

The following example uses a SystemStart function block to introduce code into the Md1Start function. The next figure shows a simple model with the System Start function block inserted.



Double-clicking the System Start Function block opens the System Start Function Custom Code dialog box.



You can insert custom code into any or all of the available text fields.

The code below is the MdlStart function for this example (mymodel).

```
void MdlStart(void)
{
    {
        {
            /* user code (Start function Header) */
            /* System '<Root>' */
            unsigned int *ptr = 0xFFEE;

            /* user code (Start function Body) */
            /* System '<Root>' */
            /* Initialize hardware */
            *ptr = 0;
        }
    }

    MdlInitialize();
}
```

The custom code entered in the System Start Function Custom Code dialog box is embedded directly in the generated code. Each block of custom code is tagged with a comment such as

```
/* user code (Start function Header) */
```

Custom Code in Subsystems

The location of a Custom Code block in your model determines the location of the code it contains. You can use System Custom Code blocks either at root level or within atomic subsystems; the code is local to the subsystem in which you place the blocks. For example, the System Outputs block places code in `mdlOutputs` when the code block resides in the root model. If the System Outputs block resides in a triggered or enabled subsystem, however, the code is placed in the subsystem's Outputs function.

The ordering for a triggered or enabled system is

- 1 Output entry
- 2 Output exit
- 3 Update entry
- 4 Update exit

Note If a root model or atomic subsystem does not need to generate a function for which a Custom Code block has been supplied, either the code in the block is not used or an error is generated. There is no diagnostic setting to control this. To eliminate the error, remove the Custom Code block.

Preventing User Source Code from Being Deleted from Build Directories

Prior to Release 13 (Version 5.0), Real-Time Workshop did not delete any .c or .h files that the user had placed in the build directory when rebuilding targets. From Release 13 onward, all foreign source files are by default deleted during builds, but can be preserved by following the guidelines given below.

If you put a .c/.cpp or .h source file in a build directory, and you want to prevent Real-Time Workshop from deleting it during the TLC code generation process, insert the string `target specific file` in the first line of the .c/.cpp or .h file. For example,

```
/* COMPANY-NAME target specific file
 *
 * This file is created for use with the
 * COMPANY-NAME target.
 * It is used for ...
 */
...
```

Make sure you spell the string “target specific file” as shown in the preceding example, and that the string is in the first line of the source file. Other text can appear before or after this string.

In addition to preserving them, flagging user files in this manner prevents post-processing them to indent them along with generated source files. Auto-indenting occurred in previous releases to build directory files with names having the pattern `model_*.c/.cpp` (where * could be any string). The indenting is harmless, but can cause differences to be detected by source control software that might trigger unnecessary updates.

Timing Services

Absolute and Elapsed Time
Computation (p. 15-2)

Describes efficient, overflow-free
integer time computation services
provided to blocks that request
absolute or elapsed time

APIs for Accessing Timers (p. 15-5)

Describes APIs you can use to access
timers for use in S-functions, in both
simulation and code generation

Elapsed Timer Code Generation
Example (p. 15-10)

Discusses analysis of how a simple
model generates and maintains an
elapsed timer

Absolute and Elapsed Time Computation

In this section...

“Introduction” on page 15-2

“Timers for Periodic and Asynchronous Tasks” on page 15-3

“Allocation of Timers” on page 15-3

“Integer Timers in Generated Code” on page 15-3

“Elapsed Time Counters in Triggered Subsystems” on page 15-4

Introduction

Certain blocks require the value of either *absolute* time (that is, the time from the start of program execution to the present time) or *elapsed* time (for example, the time elapsed between two trigger events). All targets that support the real-time model (`rtModel`) data structure provide efficient time computation services to blocks that request absolute or elapsed time. Absolute and elapsed timer features include

- Timers are implemented as unsigned integers in generated code.
- In multirate models, at most one timer is allocated per rate, on an as-needed basis. If no blocks executing at a given rate require a timer, no timer is allocated to that rate. This minimizes memory allocated for timers and significantly reduces overhead involved in maintaining timers.
- Allocation of elapsed time counters for use of blocks within triggered subsystems is minimized, further reducing memory usage and overhead.
- Real-Time Workshop provides S-function and TLC APIs that let your S-functions access timers, in both simulation and code generation.
- For ERT and ERT-derived targets, the word size of the timers is determined by a user-specified maximum counter value. Correct specification of this value ensures that timers will not overflow. See the description of the parameter “Controlling Memory Allocation for Time Counters” on page 9-47. See also the Real-Time Workshop Embedded Coder documentation for information on restrictions on its use.

See Appendix A, “Blocks That Depend on Absolute Time” for a complete list of blocks in this category.

Timers for Periodic and Asynchronous Tasks

This chapter discusses timing services provided for blocks executing within *periodic* tasks (that is, tasks running at the model’s base rate or subrates).

Real-Time Workshop also provides timer support for blocks whose execution is *asynchronous* with respect to the periodic timing source of the model. See the following sections of the Asynchronous Support chapter:

- “Using Timers in Asynchronous Tasks” on page 16-27
- “Creating a Customized Asynchronous Library” on page 16-30

Allocation of Timers

If you create or maintain an S-Function block that requires absolute or elapsed time data, it must register the requirement (see “APIs for Accessing Timers” on page 15-5). In multirate models, timers are allocated on a per-rate basis. For example, consider a model structured as follows:

- There are three rates, A, B, and C, in the model.
- No blocks running at rate B require absolute or elapsed time.
- Two blocks running at rate C register a requirement for absolute time.
- One block running at rate A registers a requirement for absolute time.

In this case, two timers are generated, running at rates A and C respectively. The timing engine updates the timers as the tasks associated with rates A and C execute. Blocks executing at rates A and C obtain time data from the timers associated with rates A and C.

Integer Timers in Generated Code

In the generated code, timers for absolute and elapsed time are implemented as unsigned integers. The default size is 64 bits. This is the amount of memory allocated for a timer if you specify a value of `inf` for the **Application lifespan (days)** parameter. For an application with a sample rate of 1000

Mhz, a 64-bit counter will not overflow for more than 500 years. See “Using Timers in Asynchronous Tasks” on page 16-27 and “Controlling Memory Allocation for Time Counters” on page 9-47 for more information.

Elapsed Time Counters in Triggered Subsystems

Some blocks, such as the Discrete-Time Integrator block, perform computations requiring the elapsed time (ΔT) since the previous block execution. Blocks requiring elapsed time data must register the requirement (see “APIs for Accessing Timers” on page 15-5). A triggered subsystem then allocates and maintains a single elapsed time counter if required. This timer functions at the subsystem level, not at the individual block level. The timer is generated if the triggered subsystem (or any unconditionally executed subsystem within the triggered subsystem) contains one or more blocks requiring elapsed time data.

APIs for Accessing Timers

In this section...

- “Introduction” on page 15-5
- “C-API for S-Functions” on page 15-5
- “TLC API for Code Generation” on page 15-8

Introduction

This section describes APIs that let your S-functions take advantage of the efficiencies offered by the absolute and elapsed timers. Simstruct macros are provided for use in simulation, and TLC functions are provided for inlined code generation. Note that

- To generate and use the new timers as described above, your S-functions must register the need to use an absolute or elapsed timer by calling `ssSetNeedAbsoluteTime` or `ssSetNeedElapseTime` in `mdlInitializeSampleTime`.
- Existing S-functions that read absolute time but do not register by using these macros will continue to operate correctly, but will generate old-style, less efficient code.

C-API for S-Functions

The SimStruct macros described in this section provide access to absolute and elapsed timers for S-functions during simulation.

In the functions below, the `SimStruct *S` argument is a pointer to the `simstruct` of the calling S-function.

- `void ssSetNeedAbsoluteTime(SimStruct *S, boolean b)`: if `b` is `TRUE`, registers that the calling S-function requires absolute time data, and allocates an absolute time counter for the rate at which the S-function executes (if such a counter has not already been allocated).
- `int ssGetNeedAbsoluteTime(SimStruct *S)`: returns 1 if the S-function has registered that it requires absolute time.

- `double ssGetTaskTime(SimStruct *S, tid)`: read absolute time for a given task with task identifier `tid`. `ssGetTaskTime` operates transparently, regardless of whether or not you use the new timer features. `ssGetTaskTime` is documented in the SimStruct Functions chapter of the Simulink S-function documentation.
- `void ssSetNeedElapseTime(SimStruct *S, boolean b)`: if `b` is `TRUE`, registers that the calling S-function requires elapsed time data, and allocates an elapsed time counter for the triggered subsystem in which the S-function executes (if such a counter has not already been allocated). See also “Elapsed Time Counters in Triggered Subsystems” on page 15-4.
- `int ssGetNeedElapseTime(SimStruct *S)`: returns 1 if the S-function has registered that it requires elapsed time.
- `void ssGetElapseTime(SimStruct *S, (double *)elapseTime)`: returns, to the location pointed to by `elapseTime`, the value (as a double) of the elapsed time counter associated with the S-function.
- `void ssGetElapseTimeCounterDtype(SimStruct *S, (int *)dtype)`: returns the data type of the elapsed time counter associated with the S-function to the location pointed to by `dtype`. This function is intended for use with the `ssGetElapseTimeCounter` function (see below).
- `void ssGetElapseResolution(SimStruct *S, (double *)resolution)`: returns the resolution (that is, the sample time) of the elapsed time counter associated with the S-function to the location pointed to by `resolution`. This function is intended for use with the `ssGetElapseTimeCounter` function (see below).
- `void ssGetElapseTimeCounter(SimStruct *S, (void *)elapseTime)`: This function is provided for the use of blocks that require the elapsed time values for fixed-point computations. `ssGetElapseTimeCounter` returns, to the location pointed to by `elapseTime`, the integer value of the elapsed time counter associated with the S-function. If the counter size is 64 bits, the value is returned as an array of two 32-bit words, with the low-order word stored at the lower address.

To determine how to access the returned counter value, obtain the data type of the counter by calling `ssGetElapseTimeCounterDtype`, as in the following code:

```
int    *y_dtype;
ssGetElapseTimeCounterDtype(S, y_dtype);
```

```
switch(*y_dtype) {
  case SS_DOUBLE_UINT32:
    {
      uint32_T dataPtr[2];
      ssGetElapseTimeCounter(S, dataPtr);
    }
    break;
  case SS_UINT32:
    {
      uint32_T dataPtr[1];
      ssGetElapseTimeCounter(S, dataPtr);
    }
    break;
  case SS_UINT16:
    {
      uint16_T dataPtr[1];
      ssGetElapseTimeCounter(S, dataPtr);
    }
    break;
  case SS_UINT8:
    {
      uint8_T dataPtr[1];
      ssGetElapseTimeCounter(S, dataPtr);
    }
    break;
  case SS_DOUBLE:
    {
      real_T dataPtr[1];
      ssGetElapseTimeCounter(S, dataPtr);
    }
    break;
  default:
    ssSetErrorStatus(S, "Invalid data type for elapse time
      counter");
    break;
}
```

If you want to use the actual elapsed time, issue a call to the `ssGetElapseTime` function to access the elapsed time directly. You do not need to get the counter value and then calculate the elapsed time.

```
double *y_elapseTime;  
.  
.  
.  
ssGetElapseTime(S, elapseTime)
```

TLC API for Code Generation

The following TLC functions support elapsed time counters in generated code when you inline S-functions by writing TLC scripts for them.

- `LibGetTaskTimeFromTID(block)`: Generates code to read the absolute time for the task in which block executes.

`LibGetTaskTimeFromTID` is documented with other sample time functions in the TLC Function Library Reference pages of the Target Language Compiler documentation.

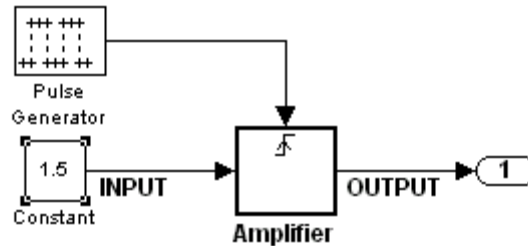
Note Do not use `LibGetT` for this purpose. `LibGetT` always reads the base rate (`tid 0`) timer. If `LibGetT` is called for a block executing at a subrate, the wrong timer is read, causing serious errors.

- `LibGetElapseTime(system)`: Generates code to read the elapsed time counter for system. (`system` is the parent system of the calling block.) See “Elapsed Timer Code Generation Example” on page 15-10 for an example of code generated by this function.
- `LibGetElapseTimeCounter(system)`: Generates code to read the integer value of the elapsed time counter for system. (`system` is the parent system of the calling block.) This function should be used in conjunction with `LibGetElapseTimeCounterDtypeId` and `LibGetElapseTimeResolution`. (See the discussion of `ssGetElapseTimeCounter` above.)
- `LibGetElapseTimeCounterDtypeId(system)`: Generates code that returns the data type of the elapsed time counter for system. (`system` is the parent system of the calling block.)

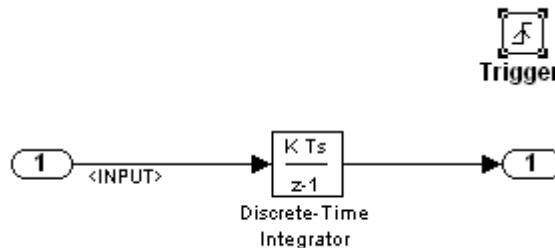
- `LibGetElapseTimeResolution(system)`: Generates code that returns the resolution of the elapsed time counter for `system`. (`system` is the parent system of the calling block.)

Elapsed Timer Code Generation Example

This section shows a simple model illustrating how an elapsed time counter is generated and used by a Discrete-Time Integrator block within a triggered subsystem. The following block diagrams show the model `elapsedTime_exp`, which contains subsystem `Amplifier`, which includes a Discrete-Time Integrator block.



`elapsedTime_exp` Model



Amplifier Subsystem

A 32-bit timer for the base rate (the only rate in this model) is defined within the `rtModel` structure, as follows, in `model.h`.

```

/*
 * Timing:
 * The following substructure contains information regarding
 * the timing information for the model.
 */

```

```

struct {
    time_T stepSize;
    uint32_T clockTick0;
    uint32_T clockTickH0;
    time_T stepSize0;
    time_T tStart;
    time_T tFinal;
    time_T timeOfLastOutput;
    void *timingData;
    real_T *varNextHitTimesList;
    SimTimeStep simTimeStep;
    boolean_T stopRequestedFlag;
    time_T *sampleTimes;
    time_T *offsetTimes;
    int_T *sampleTimeTaskIDPtr;
    int_T *sampleHits;
    int_T *perTaskSampleHits;
    time_T *t;
    time_T sampleTimesArray[1];
    time_T offsetTimesArray[1];
    int_T sampleTimeTaskIDArray[1];
    int_T sampleHitArray[1];
    int_T perTaskSampleHitsArray[1];
    time_T tArray[1];
} Timing;

```

Had the target been ERT instead of GRT, the Timing structure would have been pruned to contain only the data required by the model, as follows:

```

/* Real-time Model Data Structure */ (for ERT!)
struct _RT_MODEL_elapseTime_exp_Tag {

    /*
     * Timing:
     * The following substructure contains information regarding
     * the timing information for the model.
     */
    struct {
        uint32_T clockTick0;

```

```

    } Timing;
};

```

Storage for the previous-time value of the Amplifier subsystem (Amplifier_PREV_T) is allocated in the D_Work(states) structure in *model.h*.

```

typedef struct D_Work_elapseTime_exp_tag {
    real_T DiscreteTimeIntegrator_DSTATE; /* '<S1>/Discrete-Time
                                           Integrator' */
    int32_T clockTickCounter;             /* '<Root>/Pulse Generator' */
    uint32_T Amplifier_PREV_T;           /* '<Root>/Amplifier' */
} D_Work_elapseTime_exp;

```

These structures are declared in *model.c*:

```

/* Block states (auto storage) */
D_Work_elapseTime_exp elapseTime_exp_DWork;
.
.
.
/* Real-time model */
rtModel_elapseTime_exp elapseTime_exp_M;
rtModel_elapseTime_exp *elapseTime_exp_M = &elapseTime_exp_M;

```

The elapsed time computation is performed as follows within the *model_step* function:

```

/* Output and update for trigger system: '<Root>/Amplifier' */
uint32_T rt_currentTime =
    ((uint32_T)elapseTime_exp_M->Timing.clockTick0);
uint32_T rt_elapseTime = rt_currentTime -
    elapseTime_exp_DWork.Amplifier_PREV_T;
elapseTime_exp_DWork.Amplifier_PREV_T = rt_currentTime;

```

As shown above, the elapsed time is maintained as a state of the triggered subsystem. The Discrete-Time Integrator block finally performs its output and update computations using the elapsed time.

```

/* DiscreteIntegrator: '<S1>/Discrete-Time Integrator' */
OUTPUT = elapseTime_exp_DWork.DiscreteTimeIntegrator_DSTATE;

```

```
/* Update for DiscreteIntegrator: '<S1>/Discrete-Time Integrator'*/  
  elapsedTime_exp_DWork.DiscreteTimeIntegrator_DSTATE += 0.3 *  
  (real_T)rt_elapsedTime * 1.5 ;
```

Because the triggered subsystem maintains the elapsed time, the TLC implementation of the Discrete-Time Integrator block needs only a single call to `LibGetElapsedTime` to access the elapsed time value.

Asynchronous Support

Introduction (p. 16-2)	Introduces the asynchronous blocks in the Real-Time Workshop libraries
Handling Interrupts (p. 16-5)	Describes the Async Interrupt, Task Synchronization, and Protected/Unprotected Rate Transition blocks
Rate Transitions and Asynchronous Blocks (p. 16-21)	Explains how and when to use Rate Transition blocks to handle data transfers to and from asynchronous blocks
Using Timers in Asynchronous Tasks (p. 16-27)	Explains how Real-Time Workshop maintains absolute and elapsed timing data for use of blocks executing in an asynchronous task
Creating a Customized Asynchronous Library (p. 16-30)	Provides guidelines for creating your own asynchronous blocks, using the VxWorks library blocks as templates; required API calls for C/C++ and TLC block implementations
Asynchronous Support Limitations (p. 16-39)	Identifies asynchronous support limitations

Introduction

In this section...
“About Asynchronous Support” on page 16-2
“VxWorks Library Overview” on page 16-2
“Accessing the VxWorks Library” on page 16-4
“Generating Code with the VxWorks Library Blocks” on page 16-4
“Demos and Additional Information” on page 16-4

About Asynchronous Support

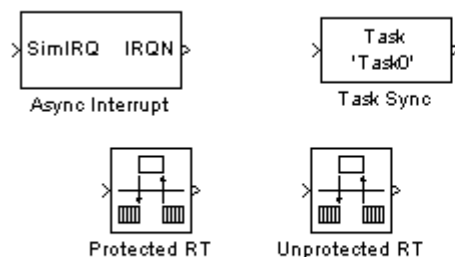
Real-Time Workshop models are normally timed from a *periodic* interrupt source (for example, a hardware timer). Blocks in a periodically clocked single-rate model run at a timer interrupt rate (the base rate of the model). Blocks in a periodically clocked multirate model run at the base rate or at submultiples of that rate.

Many systems must also support execution of blocks in response to events that are *asynchronous* with respect to the periodic timing source of the system. For example, a peripheral device might signal completion of an input operation by generating an interrupt. The system must service such interrupts appropriately, for example, by acquiring data from the interrupting device.

This chapter explains how to use blocks to model and generate code for asynchronous event handling, including servicing of hardware-generated interrupts, maintenance of timers, asynchronous read and write operations, and spawning of asynchronous tasks under a real-time operating system (RTOS). Although the blocks target the VxWorks Tornado RTOS, this chapter provides source code analysis and other information you can use to develop blocks that support asynchronous event handling for an alternative target RTOS.

VxWorks Library Overview

The next figure shows the blocks in the VxWorks library (vxlib1).



The key blocks in the library are the Async Interrupt and Task Sync blocks. These blocks are targeted for the VxWorks Tornado operating system. You can use them, without modification, to support VxWorks applications.

If you want to implement asynchronous support for an RTOS other than VxWorks, guidelines and example code are provided that will help you to adapt the VxWorks library blocks to target your RTOS. This topic is discussed in “Creating a Customized Asynchronous Library” on page 16-30.

The VxWorks library includes blocks you can use to

- Generate interrupt-level code — Async Interrupt block
- Spawn a VxWorks task that calls a function call subsystem — Task Sync block
- Ensure data integrity when transferring data between blocks running as different tasks — Protected RT block
- Use an unprotected/nondeterministic mode when transferring data between blocks running as different tasks — Unprotected RT block

For detailed descriptions of the blocks in the VxWorks library, see the *Real-Time Workshop Reference*. The use of the Protected and Unprotected Rate Transition blocks in asynchronous contexts is discussed in “Rate Transitions and Asynchronous Blocks” on page 16-21. For general information on rate transitions, see Chapter 8, “Models with Multiple Sample Rates”.

Accessing the VxWorks Library

The VxWorks library (vxlib1) is part of the Real-Time Workshop library. You can access the VxWorks library by opening the Simulink Library Browser, clicking the **Real-Time Workshop** entry, and clicking **VxWorks**. Alternatively, enter the MATLAB command `vxlib1`.

Generating Code with the VxWorks Library Blocks

To generate a VxWorks compatible application from a model containing VxWorks library blocks, configure the model for one of the following targets:

- The Embedded Real-Time (ERT) target. This target is provided with Real-Time Workshop Embedded Coder.

When using the ERT target with VxWorks library blocks, you must select the **Generate an example main program** option, and select `VxWorksExample` from the **Target operating system** menu.

- The Tornado (VxWorks) Real-Time target example, included with Real-Time Workshop (see Chapter 13, “Targeting Tornado for Real-Time Applications”).

Demos and Additional Information

Additional information relevant to the topics in this chapter can be found in

- The `rtwdemo_async` model. To open this demo, type `rtwdemo_async` at the MATLAB command prompt.
- Chapter 8, “Models with Multiple Sample Rates”, discusses general multitasking and rate transition issues for periodic models.
- Chapter 13, “Targeting Tornado for Real-Time Applications”, discusses the Tornado (VxWorks) Real-Time target example.
- The Real-Time Workshop Embedded Coder documentation discusses the Embedded Real-Time (ERT) target, including task execution and scheduling.
- See your VxWorks system documentation for detailed information about the VxWorks system calls mentioned in this chapter.

Handling Interrupts

In this section...
“Generating Interrupt Service Routines” on page 16-5
“Spawning a VxWorks Task” on page 16-13

Generating Interrupt Service Routines

To generate an interrupt service routine (ISR) associated with a specific VxWorks VME interrupt level, use the Async Interrupt block. The Async Interrupt block enables the specified interrupt level and installs an ISR that calls a connected function call subsystem.

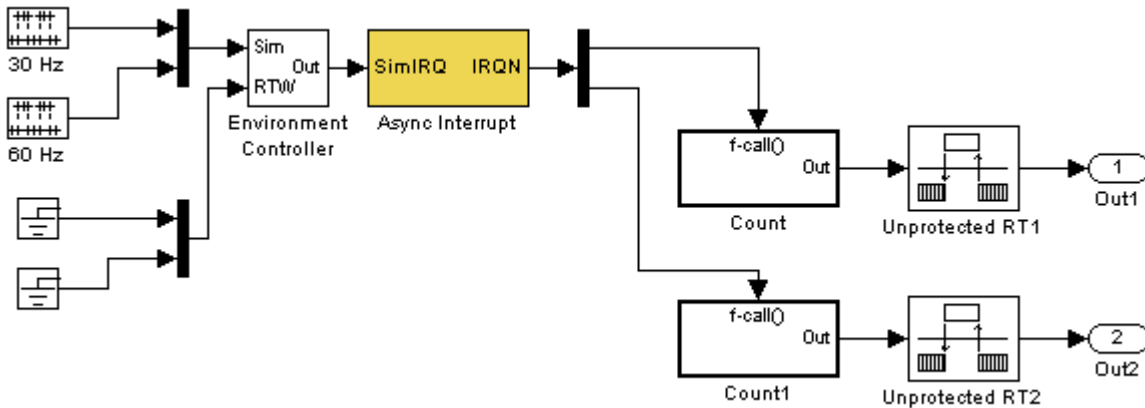
You can also use the Async Interrupt block in a simulation. It provides an input port that can be enabled and connected to a simulated interrupt source.

Connecting the Async Interrupt Block

To generate an ISR, connect an output of the VxWorks Async Interrupt block to the control input of

- A function call subsystem
- The input of a VxWorks Task Sync block
- The input to a Stateflow chart configured for a function call input event

The next figure shows an Async Interrupt block configured to service two interrupt sources. The outputs (signal width 2) are connected to two function call subsystems.



Requirements and Restrictions

Note the following requirements and restrictions:

- The Async Interrupt block supports VME interrupts 1 through 7.
- The Async Interrupt block requires a VxWorks Board Support Package (BSP) that supports the following VxWorks system calls:
 - `sysIntEnable`
 - `sysIntDisable`
 - `intConnect`
 - `intLock`
 - `intUnlock`
 - `tickGet`

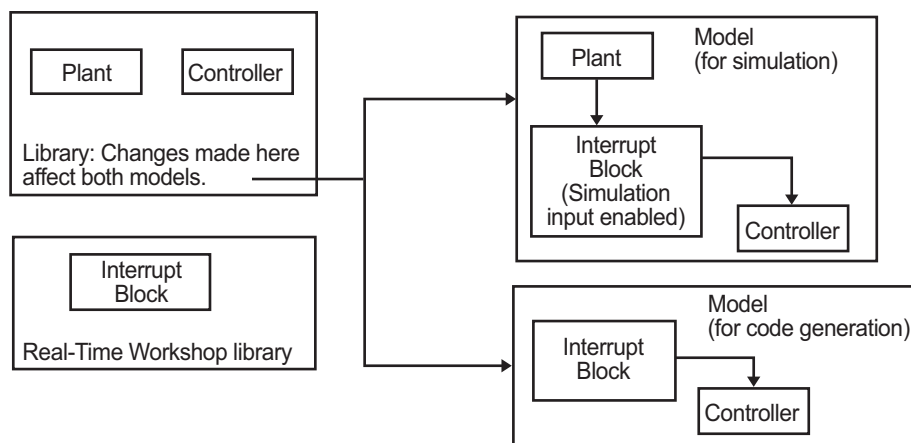
Performance Considerations

Execution of large subsystems at interrupt level can have a significant impact on interrupt response time for interrupts of equal and lower priority in the system. As a general rule, it is best to keep ISRs as short as possible. Connect only function call subsystems that contain a small number of blocks to an Async Interrupt block.

A better solution for large subsystems is to use the Task Sync block to synchronize the execution of the function call subsystem to a VxWorks task. The Task Sync block is placed between the Async Interrupt block and the function call subsystem. The Async Interrupt block then installs the Task Sync block as the ISR. The ISR releases a synchronization semaphore (performs a `semGive`) to the task, and returns immediately from interrupt level. The task is then scheduled and run by VxWorks. See “Spawning a VxWorks Task” on page 16-13 for more information.

Using the Async Interrupt Block in Simulation and Code Generation

This section describes a *dual-model* approach to the development and implementation of real-time systems that include ISRs. In this approach, you develop one model that includes a plant and a controller for simulation, and another model that only includes the controller for code generation. Using a Simulink library, you can implement changes to both models simultaneously. The next figure shows how changes made to the plant or controller, both of which are in a library, are propagated to the models.



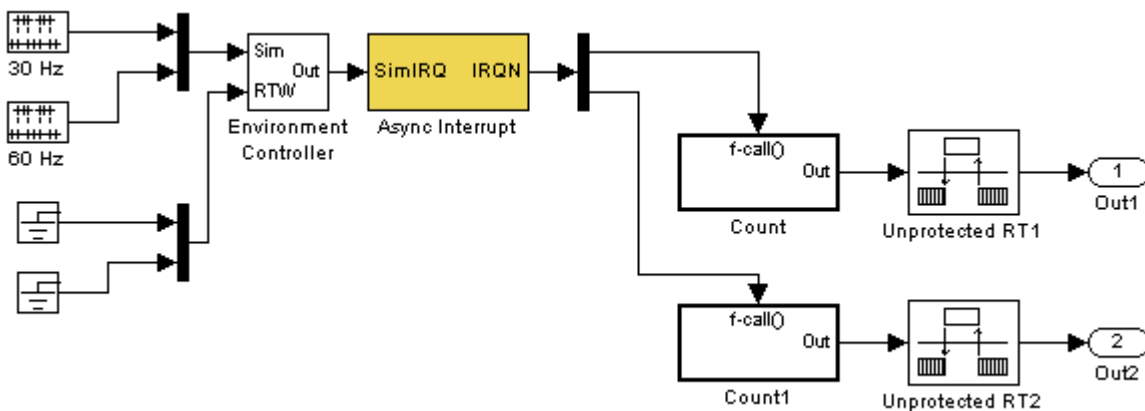
Dual-Model Use of Async Interrupt Block for Simulation and Code Generation

A *single-model* approach is also possible. In this approach, the Plant component of the model is active only in simulation. During code generation, the Plant components are effectively switched out of the system and code is

generated only for the interrupt block and controller parts of the model. For an example of this approach, see the `rtwdemo_async` model.

Dual-Model Approach: Simulation

The following block diagram shows a simple model that illustrates the dual-model approach to modeling. During simulation, the Pulse Generator blocks provide simulated interrupt signals.



The simulated interrupt signals are routed through the Async Interrupt block's input port. Upon receiving a simulated interrupt, the block calls the connected subsystem.

During simulation, subsystems connected to Async Interrupt block outputs are executed in order of their VxWorks priority. In the event that two or more interrupt signals occur simultaneously, the Async Interrupt block executes the downstream systems in the order specified by their interrupt levels (level 7 gets the highest priority). The first input element maps to the first output element.

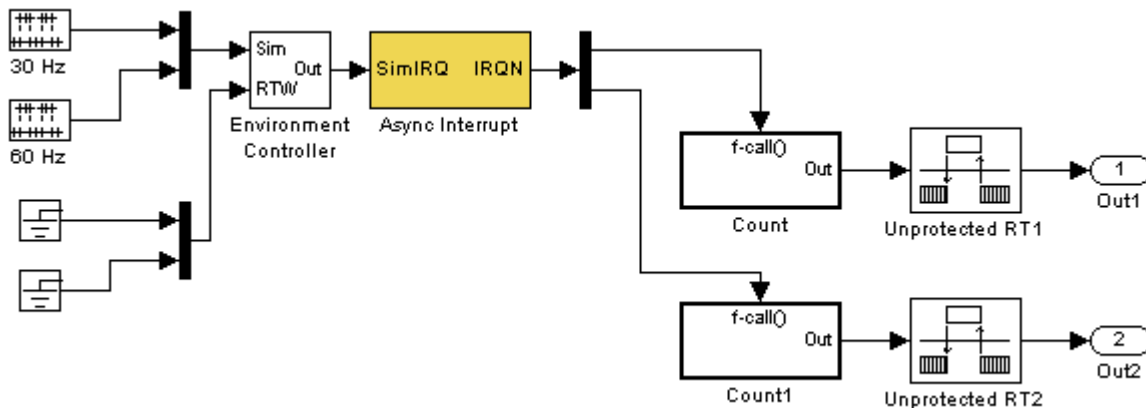
You can also use the Async Interrupt block in a simulation without enabling the simulation input. In such a case, the Async Interrupt block inherits the base rate of the model and calls the connected subsystems in order of their VxWorks priorities. (In effect, in this case the Async Interrupt block behaves as if all inputs received a 1 simultaneously.)

Dual-Model Approach: Code Generation

In the generated code for the sample model,

- Ground blocks provide input signals to the Environment Controller block
- The Async Interrupt block does not use its simulation input

The Ground blocks drive control input of the Environment Controller block to ensure that no code is generated for that signal path. Real-Time Workshop does not generate code for blocks that drive the simulation control input to the Environment Controller block because that path is not selected during code generation. However, the sample times of driving blocks for the simulation input to the Environment Controller block contribute to the sample times supported in the generated code. To avoid including unnecessary sample times in the generated code, ensure that the sample times of the blocks driving the simulation input are used in the model where generated code is intended.

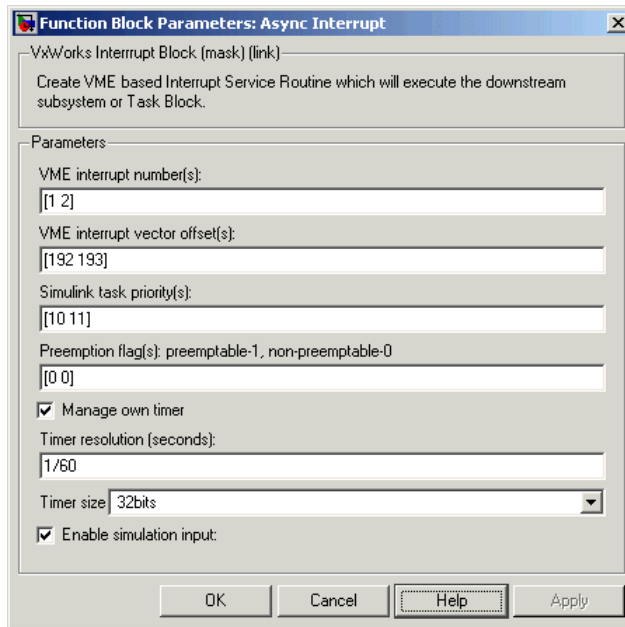


Standalone functions are installed as ISRs and the interrupt vector table is as follows:

Offset

```
192    &isr_num1_vec192()
193    &isr_num2_vec193()
```

Consider the code generated from this model, assuming that the Async Interrupt block parameters are configured as shown in the next figure.



Initialization Code. In the generated code, the Async Interrupt block installs the code in the Subsystem blocks as interrupt service routines. The interrupt vectors for IRQ1 and IRQ2 are stored at locations 192 and 193 relative to the base of the interrupt vector table, as specified by the **VME interrupt vector offset(s)** parameter.

Installing an ISR requires two VxWorks calls, `int_connect` and `sysInt_Enable`. The Async Interrupt block inserts these calls in the `model_initialize` function, as shown in the following code excerpt.

```

/* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
/* Connect and enable ISR function: isr_num1_vec192 */
if( intConnect(INUM_TO_IVEC(192), isr_num1_vec192, 0) != OK) {
    printf("intConnect failed for ISR 1.\n");
}
sysIntEnable(1);

```



```

/* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
/* Connect and enable ISR function: isr_num2_vec193 */
if( intConnect(INUM_TO_IVEC(193), isr_num2_vec193, 0) != OK)
{
    printf("intConnect failed for ISR 2.\n");
}
sysIntEnable(2);

```

The hardware that generates the interrupt is not configured by the Async Interrupt block. Typically, the interrupt source is a VME I/O board, which generates interrupts for specific events (for example, end of A/D conversion). The VME interrupt level and vector are set up in registers or by using jumpers on the board. You can use the `mdlStart` routine of a user-written device driver (S-function) to set up the registers and enable interrupt generation on the board. You must match the interrupt level and vector specified in the Async Interrupt block dialog to the level and vector set up on the I/O board.

Generated ISR Code. The actual ISR generated for IRQ1 is listed below.

```

/* VxWorks Interrupt Block: '<Root>/Async Interrupt' */

void isr_num1_vec192(void)
{
    int_T lock;
    FP_CONTEXT context;

    /* Use tickGet() as a portable tick counter example.
       A much higher resolution can be achieved with a
       hardware counter */
    Async_Code_M->Timing.clockTick2 = tickGet();

    /* disable interrupts (system is configured as non-ive) */
    lock = intLock();

    /* save floating point context */
    fppSave(&context);

    /* Call the system: <Root>/Subsystem A */
    Count(0, 0);
}

```

```
        /* restore floating point context */
        fppRestore(&context);

        /* re-enable interrupts */
        intUnlock(lock);
    }
```

There are several features of the ISR that should be noted:

- Because of the setting of the **Preemption Flag(s)** parameter, this ISR is locked; that is, it cannot be preempted by a higher priority interrupt. The ISR is locked and unlocked by the VxWorks `int_lock` and `int_unlock` functions.
- The connected subsystem, `Count`, is called from within the ISR.
- The `Count` function executes algorithmic (model) code. Therefore, the floating-point context is saved and restored across the call to `Count`.
- The ISR maintains its own absolute time counter, which is distinct from other periodic base rate or substrate counters in the system. Timing data is maintained for the use of any blocks executed within the ISR that require absolute or elapsed time.

See “Using Timers in Asynchronous Tasks” on page 16-27 for details.

Model Termination Code. The model’s termination function disables the interrupts:

```
/* Model terminate function */
void Async_Code_terminate(void)
{
    /* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
    /* Disable interrupt for ISR system: isr_num1_vec192 */
    sysIntDisable(1);

    /* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
    /* Disable interrupt for ISR system: isr_num2_vec193 */
    sysIntDisable(2);
}
```

Spawning a VxWorks Task

To spawn an independent VxWorks task, use the Task Sync block. The Task Sync block is a function call subsystem that spawns an independent VxWorks task. The task calls the function call subsystem connected to the output of the Task Sync block.

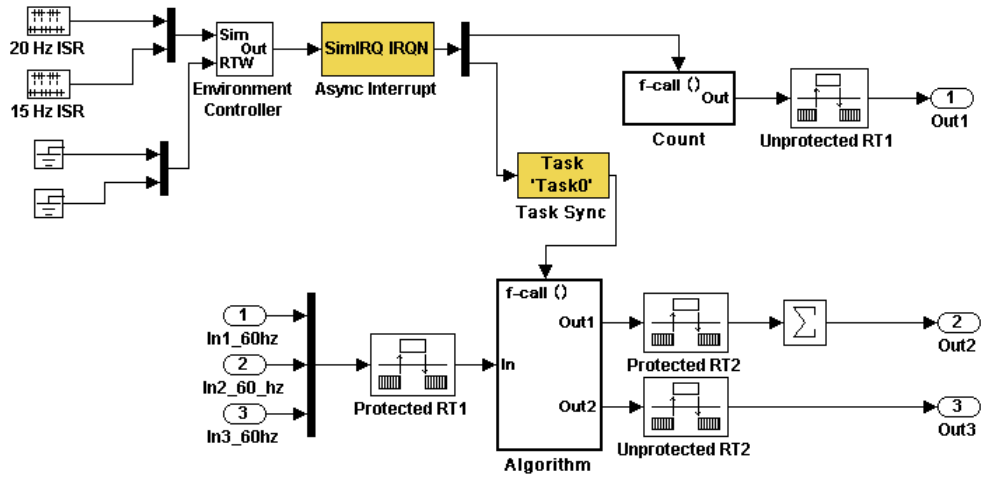
Typically, the Task Sync block is placed between an Async Interrupt block and a function call subsystem block or a Stateflow chart. Another example would be to place the Task Sync block at the output of a Stateflow diagram that has an event, “Output to Simulink,” configured as a function call.

The VxWorks Task Sync block performs the following functions:

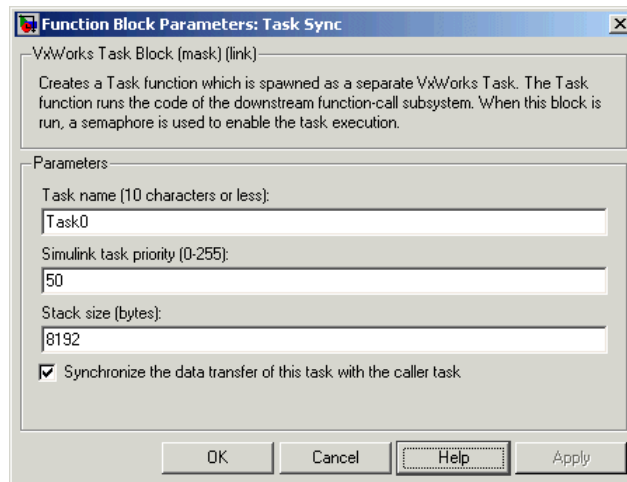
- An independent task is spawned, using the VxWorks system call `taskSpawn`. When the task is activated, it calls the downstream function call subsystem code. The task is deleted using `taskDelete` during model termination.
- A semaphore is created to synchronize the connected subsystem to the execution of the Task Sync block.
- The spawned task is wrapped in an infinite `for` loop. In the loop, the spawned task listens for the semaphore, using `semTake`. When `semTake` is first called, `NO_WAIT` is specified. This allows the task to determine whether a second `semGive` has occurred prior to the completion of the function call subsystem. This would indicate that the interrupt rate is too fast or the task priority is too low.
- The Task Sync block generates synchronization code (for example, `semGive()`). This code allows the spawned task to run; the task in turn calls the connected function call subsystem code. The synchronization code can run at interrupt level. This is accomplished by connecting the Task Sync block to the output of an Async Interrupt block, which triggers execution of the Task Sync block within an ISR.
- If blocks in the downstream algorithmic code require absolute time, it can be supplied either by the timer maintained by the Async Interrupt block, or by an independent timer maintained by the task associated with the Task Sync block.

For an example of how to use the Task Sync block, see the `rtwdemo_async` demo. The block diagram for the model appears in the next figure. Before reading the following discussion, open the demo model and double-click the

Generate Code button. You can then examine the generated code in the HTML code generation report produced by the demo.



In this model, the Async Interrupt block is configured for VME interrupts 1 and 2, using interrupt vector offsets 192 and 193. Interrupt 2 is connected to the Task Sync block, which in turn drives the Algorithm subsystem. Consider the code generated from this model, assuming that the Task Sync block parameters are configured as shown in the next figure.



Initialization Code

The Task Sync block generates initialization code for initialization by Md1Start, which itself creates and initializes the synchronization semaphore. It also spawns an independent task (task0).

```

/* VxWorks Task Block: <S5>/S-Function (vxtask1) */
/* Spawn task: Task0 with priority 50 */
if ((* (SEM_ID *)rtwdemo_async_DWork.SFunction_PWORK.SemID =
    semBCreate(SEM_Q_PRIORITY, SEM_EMPTY)) == NULL) {
    printf("semBCreate call failed for block Task0.\n");
}
if ((rtwdemo_async_DWork.SFunction_IWORK.TaskID = taskSpawn("Task0",
    50.0, VX_FP_TASK, 8192.0, (FUNCPTR)Task0, 0, 0, 0, 0, 0, 0,
    0, 0, 0)) == ERROR) {
    printf("taskSpawn call failed for block Task0.\n");
}

```

After spawning Task0, Md1Start connects and enables the ISR (ISR_num2_vec193) for interrupt 2:

```

/* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
/* Connect and enable ISR function: isr_num1_vec192 */
if (intConnect(INUM_TO_IVEC(192), isr_num1_vec192, 0) != OK) {

```

```
        printf("intConnect failed for ISR 1.\n");
    }
    sysIntEnable(1);
```

The ordering of these operations is significant. The task must be spawned before the interrupt that activates it can be enabled.

Task and Task Synchronization Code

The function Task0, generated by the Task Sync block, runs as a VxWorks task. The task waits for a synchronization semaphore in an infinite for loop. If it obtains the semaphore, it updates its task timer and calls the Algorithm subsystem.

For this demo, the **Synchronize the data transfer of this task with the caller task** option of the Task Sync block is selected. Therefore, the timer associated with the Task Sync block (rtM->Timing.clockTick3) is updated with the value of the timer that is maintained by the Async Interrupt block (rtM->Timing.clockTick4). Therefore, blocks within the Algorithm subsystem use timer values based on the time of the most recent interrupt (not the most recent activation of Task0).

```
/* VxWorks Task Block: <S5>/S-Function (vxtask1) */
/* Spawned with priority: 50 */
void Task0(void)
{
    /* Wait for semaphore to be released by system:
       rtwdemo_async/Task Sync */
    for(;;) {
        if (semTake(*(SEM_ID
                    *)rtwdemo_async_DWork.SFunction_PWORK.SemID,NO_WAIT) !=
            ERROR) {
            logMsg("Rate for Task Task0() too fast.\n",0,0,0,0,0);
#ifdef STOPONOVERRUN
            logMsg("Aborting real-time simulation.\n",0,0,0,0,0);
            semGive(stopSem);
            return(ERROR);
#endif
        } else {
            semTake(*(SEM_ID
```

```

        *)rtwdemo_async_DWork.SFunction_PWORK.SemID,
        WAIT_FOREVER);
    }
    /* Use the upstream clock tick counter for this Task. */
    rtwdemo_async_M->Timing.clockTick2 =
    rtwdemo_async_M->Timing.clockTick3;

    /* Call the system: <Root>/Algorithm */
{

    /* Output and update for function-call system: '<Root>/Algorithm' */

    {

        uint32_T rt_currentTime = ((uint32_T)rtwdemo_async_M->Timing.clockTick2);
        uint32_T rt_elapseTime = rt_currentTime -
            rtwdemo_async_DWork.Algorithm_PREV_T;
        rtwdemo_async_DWork.Algorithm_PREV_T = rt_currentTime;

        {
            int32_T i;

            /* DiscreteIntegrator: '<S1>/Integrator' */
            rtwdemo_async_B.Integrator = rtwdemo_async_DWork.Integrator_DSTATE;
            for(i = 0; i < 60; i++) {

                /* Sum: '<S1>/Sum' */
                rtwdemo_async_B.Sum[i] = rtwdemo_async_B.ProtectedRT1[i] + 1.25;
            }
        }

        /* Sum: '<S1>/Sum1' */
        rtwdemo_async_B.Sum1 = rtwdemo_async_B.Sum[0];
        {
            int_T i1;

            const real_T *u0 = &rtwdemo_async_B.Sum[1];

            for (i1=0; i1 < 59; i1++) {
                rtwdemo_async_B.Sum1 += u0[i1];
            }
        }
    }
}

```

```
    }
  }

  {
    int32_T i;
    if(rtwdemo_async_DWork.ProtectedRT2_ActiveBufIdx) {
      for(i = 0; i < 60; i++) {
        rtwdemo_async_DWork.ProtectedRT2_Buffer0[i] =
          rtwdemo_async_B.Sum[i];
      }
      rtwdemo_async_DWork.ProtectedRT2_ActiveBufIdx = (boolean_T)0U;
    } else {
      for(i = 0; i < 60; i++) {
        rtwdemo_async_DWork.ProtectedRT2_Buffer1[i] =
          rtwdemo_async_B.Sum[i];
      }
      rtwdemo_async_DWork.ProtectedRT2_ActiveBufIdx = (boolean_T)1U;
    }
  }

  /* Update for DiscreteIntegrator: '<S1>/Integrator' */
  rtwdemo_async_DWork.Integrator_DSTATE = (real_T)rt_elapseTime *
    1.6666666666666666E-002 * rtwdemo_async_B.Sum1 +
    rtwdemo_async_DWork.Integrator_DSTATE;
}
```

The semaphore is granted by the function `isr_num2_vec193`, which is called from interrupt level:

```
/* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
void isr_num2_vec193(void)
{

  /* Use tickGet() as a portable tick counter example. A much
     higher resolution can be achieved with a hardware counter */
  rtwdemo_async_M->Timing.clockTick3 = tickGet();

  /* Call the system: <S4>/Subsystem */

  /* Output and update for function-call system:
```



```

    '<S4>/Subsystem' */
{
    {
        int32_T i;
        for(i = 0; i < 60; i++) {
            if(rtwdemo_async_DWork.ProtectedRT1_ActiveBufIdx) {
                rtwdemo_async_B.ProtectedRT1[i] =
                    rtwdemo_async_DWork.ProtectedRT1_Buffer1[i];
            } else {
                rtwdemo_async_B.ProtectedRT1[i] =
                    rtwdemo_async_DWork.ProtectedRT1_Buffer0[i];
            }
        }
    }
}

/* VxWorks Task Block: <S5>/S-Function (vxtask1) */
/* Release semaphore for system task: Task0 */
semGive(*(SEM_ID *)rtwdemo_async_DWork.SFunction_PWORK.SemID);
}
}

```

The ISR maintains a timer that stores the tick count at the time of interrupt. This timer is updated before releasing the semaphore that activates Task0.

As this example shows, the Task Sync block generates only a small amount of interrupt-level code.

Task Termination Code

The Task Sync block also generates the following termination code.

```

/* Model terminate function */

void rtwdemo_async_terminate(void)
{
    /* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
    /* Disable interrupt for ISR system: isr_num1_vec192 */
    sysIntDisable(1);
}

```

```
/* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
/* Disable interrupt for ISR system: isr_num2_vec193 */
sysIntDisable(2);

/* Terminate for function-call system: '<S4>/Subsystem' */
/* VxWorks Task Block: <S5>/S-Function (vxtask1) */
/* Destroy task: Task0 */
taskDelete(rtwdemo_async_DWork.SFunction_IWORK.TaskID);
}
```

Rate Transitions and Asynchronous Blocks

In this section...
“Introduction” on page 16-21
“Handling Rate Transitions for Asynchronous Tasks” on page 16-23
“Handling Multiple Asynchronous Interrupts” on page 16-23

Introduction

Because an asynchronous function call subsystem can preempt or be preempted by other model code, an inconsistency arises when more than one signal element is connected to an asynchronous block. The issue is that signals passed to and from the function call subsystem can be in the process of being written to or read from when the preemption occurs. Thus, some old and some new data is used. This situation can also occur with scalar signals in some cases. For example, if a signal is a double (8 bytes), the read or write operation might require two machine instructions.

The Simulink Rate Transition block is designed to deal with preemption problems that occur in data transfer between blocks running at different rates. These issues are discussed in Chapter 8, “Models with Multiple Sample Rates”.

You can handle rate transition issues automatically by selecting the **Automatically handle data transfers between tasks** option on the **Solver** pane of the Configuration Parameters dialog box. This saves you from having to manually insert Rate Transition blocks to avoid invalid rate transitions, including invalid *asynchronous-to-periodic* and *asynchronous-to-asynchronous* rate transitions, in multirate models. For asynchronous tasks, Simulink configures the inserted blocks to ensure data integrity but not determinism during data transfers.

For asynchronous rate transitions, the Rate Transition block guarantees data integrity, but cannot guarantee determinism. Therefore, when you insert Rate Transition blocks explicitly, you must clear the **Ensure data determinism** check box in the Block Parameters dialog box.

When you insert a Rate Transition block between two blocks to ensure data integrity and priorities are assigned to the tasks associated with the blocks, Real-Time Workshop assumes that the higher priority task can preempt the lower priority task and the lower priority task cannot preempt the higher priority task. If the priority associated with task for either block is not assigned or the priorities of the tasks for both blocks are the same, Real-Time Workshop assumes that either task can preempt the other task.

Priorities of periodic tasks are assigned by Simulink, in accordance with the options specified in the **Solver options** section of the **Solver** pane of the Configuration Parameters dialog box. When the **Periodic sample time constraint** option field of **Solver options** is set to Unconstrained, the model base rate priority is set to 40. Priorities for subrates then increment or decrement by 1 from the base rate priority, depending on the setting of the **Higher priority value indicates higher task priority option**.

You can assign priorities manually by using the **Periodic sample time properties** field. Simulink does not assign a priority to asynchronous blocks. For example, the priority of a function call subsystem that connects back to an Async Interrupt block is assigned by the Async Interrupt block.

The **Simulink task priority** field of the Async Interrupt block specifies a priority level (required) for every interrupt number entered in the **VME interrupt number(s)** field. The priority array sets the priorities of the subsystems connected to each interrupt.

For the Task Sync block, the **Simulink task priority** field similarly specifies the block priority relative to connected blocks (in addition to assigning a VxWorks priority to the generated task code). If VxWorks is the target, the **Higher priority value indicates higher task priority option** should be deselected.

The VxWorks library provides two types of rate transition blocks as a convenience. These are simply preconfigured instances of the built-in Simulink Rate Transition block:

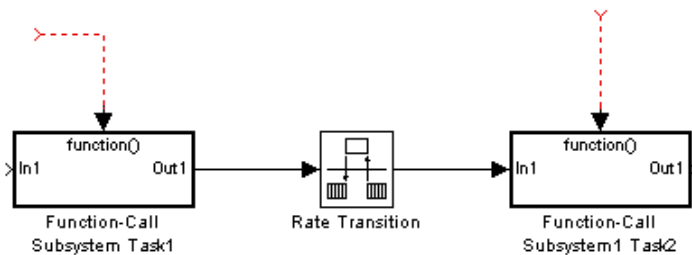
- Protected Rate Transition block: Rate Transition block that is configured with the **Ensure data integrity during data transfers** on and **Ensure deterministic data transfer** off.

- Unprotected Rate Transition block: Rate Transition block that is configured with the **Ensure data integrity during data transfers** option off.

Handling Rate Transitions for Asynchronous Tasks

For rate transitions that involve asynchronous tasks, you can ensure data integrity. However, you cannot ensure determinism. You have the option of using the Rate Transition block or target-specific rate transition blocks.

Consider the following model, which includes a Rate Transition block.



You can use the Rate Transition block in either of the following modes:

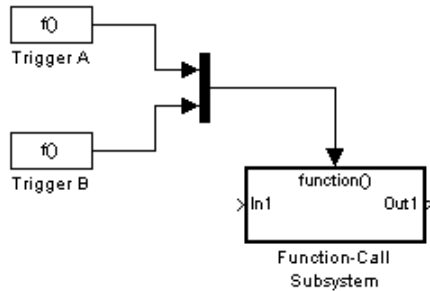
- Ensure data integrity, no determinism
- Unprotected

Alternatively, you can use target-specific rate transition blocks. The following blocks are available for VxWorks:

- Protected Rate Transition block (reader)
- Protected Rate Transition block (writer)
- Unprotected Rate Transition block

Handling Multiple Asynchronous Interrupts

Consider the following model, in which two functions trigger the same subsystem.



The two tasks must have equal priorities. When priorities are the same, the outcome depends on whether they are firing periodically or asynchronously, and also on a diagnostic setting. The following table and notes describe these outcomes:

Supported Sample Time and Priority for Function Call Subsystem with Multiple Triggers

	Async Priority = 1	Async Priority = 2	Async Priority Unspecified	Periodic Priority = 1	Periodic Priority = 2
Async Priority = 1	Supported (1)				
Async Priority = 2		Supported (1)			
Async Priority Unspecified			Supported (2)		
Periodic Priority = 1				Supported	
Periodic Priority = 2					Supported

1 Control these outcomes using the **Tasks with equal priority** option in the **Diagnostics** pane of the Configuration Parameters dialog box; set this diagnostic to none if tasks of equal priority cannot preempt each other in the target system.

2 For this case, the following warning message is issued unconditionally:

```
The function call subsystem <name> has multiple asynchronous
triggers that do not specify priority. Data integrity will
not be maintained if these triggers can preempt one another.
```

Empty cells in the above table represent multiple triggers with differing priorities, which are unsupported.

Real-Time Workshop provides absolute time management for a function call subsystem connected to multiple interrupts in the case where timer settings for TriggerA and TriggerB (time source, resolution) are the same.

Assume that all the following conditions are true for the model shown above:

- A function call subsystem is triggered by two asynchronous triggers (TriggerA and TriggerB) having identical priority settings.
- Each trigger sets the source of time and timer attributes by calling the functions `ssSetTimeSource` and `ssSetAsyncTimerAttributes`.
- The triggered subsystem contains a block that needs elapsed or absolute time (for example, a Discrete Time Integrator).

The asynchronous function call subsystem has one global variable, `clockTick#` (where # is the task ID associated with the subsystem). This variable stores absolute time for the asynchronous task. There are two ways timing can be handled:

- If the time source is set to `SS_TIMESOURCE_BASERATE`, Real-Time Workshop generates timer code in the function call subsystem, updating the clock tick variable from the base rate clock tick. Data integrity is ensured if the same priority is assigned to TriggerA and TriggerB.
- If the time source is `SS_TIMESOURCE_SELF`, generated code for both TriggerA and TriggerB updates the same clock tick variable from the hardware clock.

The word size of the clock tick variable can be set directly or be established according to the **Application lifespan (days)** setting and the timer resolution set by the TriggerA and TriggerB S-functions (which must be the same). See “Using Timers in Asynchronous Tasks” on page 16-27 and

“Controlling Memory Allocation for Time Counters” on page 9-47 for more information.

Using Timers in Asynchronous Tasks

An ISR can set a source for absolute time. This is done with the function `ssSetTimeSource`, which has the following three options:

- `SS_TIMESOURCE_SELF`: Each generated ISR maintains its own absolute time counter, which is distinct from any periodic base rate or substrate counters in the system. The counter value and the timer resolution value (specified in the **Timer resolution (seconds)** parameter of the Async Interrupt block) are used by downstream blocks to determine absolute time values required by block computations.
- `SS_TIMESOURCE_CALLER`: The ISR reads time from a counter maintained by its caller. Time resolution is thus the same as its caller's resolution.
- `SS_TIMESOURCE_BASERATE`: The ISR can read absolute time from the model's periodic base rate. Time resolution is thus the same as its base rate resolution.

By default, the counter is implemented as a 32-bit unsigned integer member of the Timing substructure of the real-time model structure. For any target that supports the `rtModel` data structure, when the time data type is not set by using `ssSetAsyncTimeDataType`, the counter word size is determined by the **Application lifespan (days)** model parameter. As an example (from ERT target code),

```
/* Real-time Model Data Structure */
struct _RT_MODEL_elapseTime_exp_Tag {
    const char *errorStatus;

    /*
     * Timing:
     * The following substructure contains information regarding
     * the timing information for the model.
     */
    struct {
        uint32_T clockTick1;
        uint32_T clockTick2;
    } Timing;
};
```

The example omits unused fields in the Timing data structure (a feature of ERT target code not found in GRT). For any target that supports the rtModel data structure, the counter word size is determined by the **Application lifespan (days)** model parameter.

By default, the VxWorks library blocks set the timer source to SS_TIMESOURCE_SELF and update their counters by using the system call tickGet. tickGet returns a timer value maintained by the VxWorks kernel. The maximum word size for the timer is UINT32. The following VxWorks example for the shows a generated call to tickGet.

```
/* VxWorks Interrupt Block: '<Root>/Async Interrupt' */
void isr_num2_vec193(void)
{

    /* Use tickGet() as a portable tick counter example. A much
       higher resolution can be achieved with a hardware counter */
    rtM->Timing.clockTick2 = tickGet();
    . . .
}
```

The tickGet call is supplied only as an example. It can (and in many instances should) be replaced by a timing source that has better resolution. If you are targeting VxWorks, you can obtain better timer resolution by replacing the tickGet call and accessing a hardware timer by using your BSP instead.

If you are implementing a custom asynchronous block for an RTOS other than VxWorks, you should either generate an equivalent call to the target RTOS, or generate code to read the appropriate timer register on the target hardware.

The default **Timer resolution (seconds)** parameter of your Async Interrupt block implementation should be changed to match the resolution of your target's timing source.

The counter is updated at interrupt level. Its value represents the tick value of the timing source at the most recent execution of the ISR. The rate of this timing source is unrelated to sample rates in the model. In fact, typically it is faster than the model's base rate. Select the timer source and set its rate and resolution based on the expected rate of interrupts to be serviced by the Async Interrupt block.

For an example of timer code generation, see “Async Interrupt Block Implementation” on page 16-31.

Creating a Customized Asynchronous Library

In this section...
“Introduction” on page 16-30
“Async Interrupt Block Implementation” on page 16-31
“Task Sync Block Implementation” on page 16-35
“asynclib.tlc Support Library” on page 16-36

Introduction

This section describes how to implement asynchronous blocks for use with your target RTOS, using the Async Interrupt and Task Sync blocks as a starting point. (Rate Transition blocks are target-independent, so you do not need to develop customized rate transition blocks.)

You can customize the asynchronous library blocks by modifying the block implementation. These files are

- The block’s underlying S-function MEX-file
- The TLC files that control code generation of the block

In addition, you need to modify the block masks to remove VxWorks-specific references and to incorporate parameters required by your target RTOS.

Custom block implementation is an advanced topic, requiring familiarity with the Simulink MEX S-function format and API, and with the Target Language Compiler (TLC). These topics are covered in the following documents:

- The “Overview of S-Functions” in the Simulink S-Functions documentation describes MEX S-functions and the S-function API in general.
- The Target Language Compiler documentation and Chapter 10, “Writing S-Functions for Real-Time Workshop Code Generation” describe how to create a TLC block implementation for use in code generation.

The following sections discuss the C/C++ and TLC implementations of the asynchronous library blocks, including required `SimStruct` macros and functions in the TLC asynchronous support library (`asynclib.tlc`).

Async Interrupt Block Implementation

The source files for the Async Interrupt block are located in `matlabroot/rtw/c/tornado/devices`:

- `vxinterrupt1.c`: C MEX-file source code, for use in configuration and simulation
- `vxinterrupt1.tlc`: TLC implementation, for use in code generation
- `asynclib.tlc`: library of TLC support functions, called by the TLC implementation of the block. The library calls are summarized in “`asynclib.tlc` Support Library” on page 16-36.

C-MEX Block Implementation

Most of the code in `vxinterrupt1.c` performs ordinary functions that are not related to asynchronous support (for example, obtaining and validating parameters from the block mask, marking parameters non tunable, and passing parameter data to the `model.rtw` file).

The `mdlInitializeSizes` function uses special `SimStruct` macros and `SS_OPTIONS` settings that are required for asynchronous blocks, as described below.

`ssSetAsyncTimerAttributes`. `ssSetAsyncTimerAttributes` declares that the block requires a timer, and sets the resolution of the timer as specified in the **Timer resolution (seconds)** parameter.

The function prototype is

```
ssSetAsyncTimerAttributes(SimStruct *S, double res)
```

where

- `S` is a `Simstruct` pointer.
- `res` is the **Timer resolution (seconds)** parameter value.

The following code excerpt shows the call to `ssSetAsyncTimerAttributes`.

```
/* Setup Async Timer attributes */
ssSetAsyncTimerAttributes(S,mxGetPr(TICK_RES)[0]);
```

ssSetAsyncTaskPriorities. `ssSetAsyncTaskPriorities` sets the Simulink task priority for blocks executing at each interrupt level, as specified in the block's **Simulink task priority** field.

The function prototype is

```
ssSetAsyncTaskPriorities(SimStruct *S, int numISRs,
                        int *priorityArray)
```

where

- `S` is a `SimStruct` pointer.
- `numISRs` is the number of interrupts specified in the **VME interrupt number(s)** parameter.
- `priorityarray` is an integer array containing the interrupt numbers specified in the **VME interrupt number(s)** parameter.

The following code excerpt shows the call to `ssSetAsyncTaskPriorities`:

```
/* Setup Async Task Priorities */
priorityArray = malloc(numISRs*sizeof(int_T));
for (i=0; i<numISRs; i++) {
    priorityArray[i] = (int_T)(mxGetPr(ISR_PRIORITIES)[i]);
}
ssSetAsyncTaskPriorities(S, numISRs, priorityArray);
free(priorityArray);
priorityArray = NULL;
}
```

SS_OPTION Settings. The code excerpt below shows the `SS_OPTION` settings for `vxinterrupt1.c`. `SS_OPTION_ASYNCHRONOUS_INTERRUPT` should be used when a function call subsystem is attached to an interrupt. For more information, see the documentation for `SS_OPTION` and `SS_OPTION_ASYNCHRONOUS` in `matlabroot/simulink/include/simstruc.h`

```

ssSetOptions( S, (SS_OPTION_EXCEPTION_FREE_CODE |
                 SS_OPTION_DISALLOW_CONSTANT_SAMPLE_TIME |
                 SS_OPTION_ASYNCHRONOUS_INTERRUPT |

```

TLC Implementation

This section discusses each function of `vxinterrupt1.tlc`, with an emphasis on target-specific features that you will need to change to generate code for your target RTOS.

Generating #include Directives. `vxinterrupt1.tlc` begins with the statement

```
%include "vxlib.tlc"
```

`vxlib.tlc` is a target-specific file that generates directives to include VxWorks header files. You should replace this with a file that generates includes for your target RTOS.

BlockInstanceSetup Function. For each connected output of the Async Interrupt block, `BlockInstanceSetup` defines a function name for the corresponding ISR in the generated code. The functions names are of the form

```
isr_num_vec_offset
```

where *num* is the ISR number defined in the **VME interrupt number(s)** block parameter, and *offset* is an interrupt table offset defined in the **VME interrupt vector offset(s)** block parameter.

In a custom implementation, there is no requirement to use this naming convention.

The function names are cached for use by the `Outputs` function, which generates the actual ISR code.

Outputs Function. `Outputs` iterates over all connected outputs of the Async Interrupt block. An ISR is generated for each such output.

The ISR code is cached in the "Functions" section of the generated code. Before generating the ISR, Outputs does the following:

- Generates a call to the downstream block (cached in a temporary buffer).
- Determines whether the ISR should be locked or not (as specified in the **Preemption Flag(s)** block parameter).
- Determines whether the block connected to the Async Interrupt block is a Task Sync block. (This information is obtained by using the asynclib calls `LibGetFcnCallBlock` and `LibGetBlockAttribute`.) If so,
 - The preemption flag for the ISR must be set to 1. An error results otherwise.
 - VxWorks calls to save and restore floating-point context are generated, unless the user has configured the model for integer-only code generation.

When generating the ISR code, Outputs calls the asynclib function `LibNeedAsyncCounter` to determine whether a timer is required by the connected subsystem. If so, and if the time source is set to be `SS_TIMESOURCE_SELF` by `ssSetTimeSource`, `LibSetAsyncCounter` is called to generate a VxWorks `tickGet` function call and update the appropriate counter. In your implementation, you should generate either an equivalent call to the target RTOS, or generate code to read the appropriate timer register on the target hardware.

If you are targeting VxWorks, you can obtain better timer resolution by replacing the `tickGet` call and accessing a hardware timer by using your BSP instead. `tickGet` supports only a 1/60 second resolution.

Start Function. The Start function generates the required VxWorks calls (`int_connect` and `sysInt_Enable`) to connect and enable each ISR. You should replace this with appropriate calls to your target RTOS.

Terminate Function. The Terminate function generates the VxWorks call `sysIntDisable` to disable each ISR. You should replace this with appropriate calls to your target RTOS.

Task Sync Block Implementation

The source files for the Task Sync block are located in `matlabroot/rtw/c/tornado/devices`. They are

- `vxtask1.c`: MEX-file source code, for use in configuration and simulation.
- `vxtask1.tlc`: TLC implementation, for use in code generation.
- `asynclib.tlc`: library of TLC support functions, called by the TLC implementation of the block. The library calls are summarized in “asynclib.tlc Support Library” on page 16-36.

C-MEX Block Implementation

Like the Async Interrupt block, the Task Sync block sets up a timer, in this case with a fixed resolution. The priority of the task associated with the block is obtained from the **Simulink task priority** parameter. The `SS_OPTION` settings are the same as those used for the Async Interrupt block.

```
ssSetAsyncTimerAttributes(S, 0.01);

priority = (int_T) (*(mxGetPr(PRIORITY)));
ssSetAsyncTaskPriorities(S,1,&priority);

ssSetOptions(S, (SS_OPTION_EXCEPTION_FREE_CODE |
                SS_OPTION_ASYNCHRONOUS |
                SS_OPTION_DISALLOW_CONSTANT_SAMPLE_TIME |
                }

```

TLC Implementation

Generating #include Directives. `vxtask1.tlc` begins with the statement

```
%include "vxlib.tlc"
```

`vxlib.tlc` is a target-specific file that generates directives to include VxWorks header files. You should replace this with a file that generates includes for your target RTOS.

BlockInstanceSetup Function. The `BlockInstanceSetup` function derives the task name, block name, and other identifier strings used later in code generation. It also checks for and warns about unconnected block conditions, and generates a storage declaration for a semaphore (`stopSem`) that is used in case of interrupt overflow conditions.

BlockInstanceData. The `BlockInstanceData` function generates storage for the semaphore that is used in management of the task spawned by the Task Sync block. Depending on the code format of the target, either a static storage declaration or a dynamic memory allocation call is generated. The ERT target and derived targets use a static memory declaration; the VxWorks target uses `malloc`.

Start Function. The `Start` function generates the required VxWorks calls to create a semaphore (`semBCreate`) and spawn a VxWorks task (`taskSpawn`). You should replace these with appropriate calls to your target RTOS.

Outputs Function. The `Outputs` function generates a VxWorks task that waits for a semaphore. When it obtains the semaphore, it updates the block's tick timer and calls the downstream subsystem code, as described in "Spawning a VxWorks Task" on page 16-13. `Outputs` also generates code (called from interrupt level) that grants the semaphore.

Terminate Function. The `Terminate` function generates the VxWorks call `taskDelete` to end execution of the task spawned by the block. You should replace this with appropriate calls to your target RTOS.

Note also that if the target RTOS has dynamically allocated any memory associated with the task (see "BlockInstanceData" on page 16-36), the `Terminate` function should deallocate the memory.

asynclib.tlc Support Library

`asynclib.tlc` is a library of TLC functions that support the implementation of asynchronous blocks. Some functions are specifically designed for use in asynchronous blocks. For example, `LibSetAsyncCounter` generates a call to update a timer for an asynchronous block. Other functions are utilities that return information required by asynchronous blocks (for example, information about connected function call subsystems).

The following table summarizes the public calls in the library. For details, see the library source code and the `vxinterrupt1.tlc` and `vxtask1.tlc` files, which call the library functions.

Summary of `asynclib.tlc` Library Functions

Function	Description
<code>LibGetBlockAttribute</code>	Returns a field value from a block record.
<code>LibGetFcnCallBlock</code>	Given an S-Function block and call index, returns the block record for the downstream function call subsystem block.
<code>LibBlockExecuteFcnCall</code>	For use by inlined S-functions with function call outputs. Generates code to execute a function call subsystem. <code>LibBlockExecuteFcnCall</code> calls the lower-level function <code>LibExecuteFcnCall</code> , but has a simplified argument list. See the Target Language Compiler documentation for more information on <code>LibExecuteFcnCall</code> .
<code>LibGetCallerClockTickCounter</code>	Provides access to an upstream asynchronous task's time counter.
<code>LibGetCallerClockTickCounterHighWord</code>	Provides access to the high word of an upstream asynchronous task's time counter.
<code>LibManageAsyncCounter</code>	Determines whether an asynchronous task needs a counter and manages its own timer.
<code>LibNeedAsyncCounter</code>	If the calling block requires an asynchronous counter, returns <code>TLC_TRUE</code> , otherwise returns <code>TLC_FALSE</code> .

Summary of asynclib.tlc Library Functions (Continued)

Function	Description
LibSetAsyncClockTicks	Returns code that sets <code>clockTick</code> counters that are to be maintained by the asynchronous task.
LibSetAsyncCounter	Generates code to set the tick value of the block's asynchronous counter.
LibSetAsyncCounterHighWord	Generates code to set the tick value of the high word of the block's asynchronous counter

Asynchronous Support Limitations

Simulink does not simulate asynchronous task behavior. Although you can specify a task priority for an asynchronous task represented in a model with the Task Sync block, the priority setting is for code generation purposes only and is not honored during simulation.

Data Exchange APIs

This chapter provides information on Real-Time Workshop application programming interfaces (APIs) that support data exchange interfaces between model code and other software components.

C-API for Interfacing with Signals and Parameters (p. 17-2)

Provides guidelines on how to use the Real-Time Workshop signal monitoring and parameter tuning APIs

Creating an External Mode Communication Channel (p. 17-23)

Explains how to support external mode on your custom target, using your own low-level communications layer

Combining Multiple Models (p. 17-35)

Discusses strategies for combining several models (or several instances of the same model) into a single executable

C-API for Interfacing with Signals and Parameters

In this section...

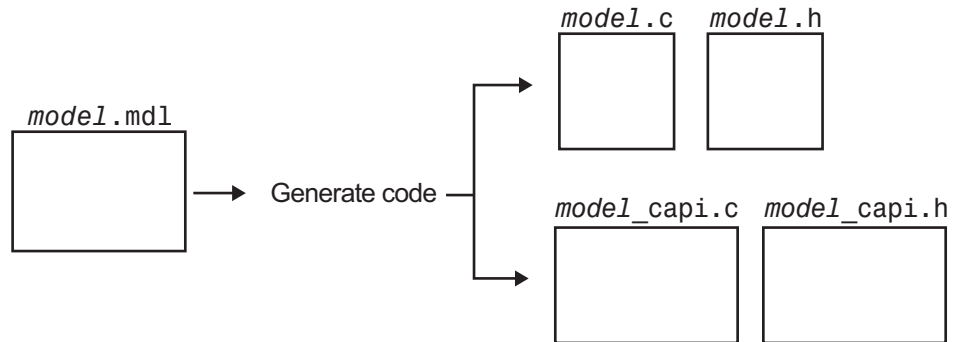
- “Introduction” on page 17-2
- “Generating C-API Files” on page 17-3
- “Description of C-API Files” on page 17-5
- “Using the C-API in an Application” on page 17-16
- “C-API Limitations” on page 17-20
- “Generating C-API and ASAP2 Files” on page 17-21
- “Target Language Compiler API for Signals and Parameters” on page 17-21

Introduction

Some Real-Time Workshop applications need to interact with signals or parameters in a model's generated code. For example, calibration applications monitor and modify parameters. Signal monitoring or data logging applications interface with signal data. Using the Real-Time Workshop C-API, you can build target applications that log signals, monitor signals, and tune parameters, while the generated code executes.

The C-API uses a small memory footprint, which is achieved by sharing information common to signals and parameters in smaller structures. An index into the structure map is provided in the signal or parameter structure, allowing multiple signals or parameters to share data.

When you configure a model to use the C-API, Real-Time Workshop generates two additional files, *model_capi.c* and *model_capi.h*, where *model* is the name of the model. Real-Time Workshop places the two C-API files in the build directory, based on settings on the Configuration Parameters dialog box. The C-API source code file contains information about global block output signals and global parameters defined in the generated code model source code. The C-API header file is an interface header file between the model source code and the generated C-API. You can use the information in these C-API files to create your application. Among the files generated are those shown in the next figure.



Generated Files with C-API Selected

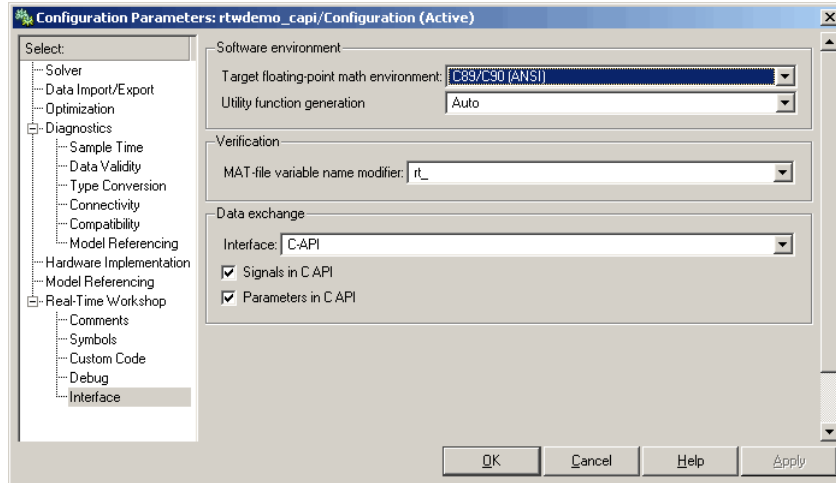
Generating C-API Files

There are two ways to select the C-API feature: using the Configuration Parameters dialog box or directly from the MATLAB command line.

Selecting C-API with the Configuration Parameters Dialog Box

- 1** In the open model, select **Configuration Parameters** on the **Simulation** menu. The Configuration Parameters dialog box appears.
- 2** Click **Interface** under **Real-Time Workshop** on the left pane. The **Interface** pane appears on the right.
- 3** Select C-API in the **Interface** field. The **Signals in C API** and **Parameters in C API** check boxes appear, as shown in the next figure.
- 4** If you want to generate C-API for global block outputs, select the **Signals in C API** check box. If you want to generate C-API for global block and model parameters, select the **Parameters in C API** check box. If you select both check boxes, the default, both signals and parameters will appear in the C-API.
- 5** Click the **Apply** button.
- 6** Click **Real-Time Workshop** in the left pane. The **Generate code** button appears in the right pane.

7 Click **Generate Code**.



C-API Checkboxes on Configuration Parameters Dialog Box

Selecting C-API from the MATLAB Command Line

From the MATLAB command line you can select or clear the two C-API check boxes on the Configuration Parameters dialog box using the `set_param` function. Type one or more of the following commands on the MATLAB command line as desired, where `modelName` is the one-word name of the model:

To select **Signals in C API**, type

```
set_param(modelname, 'RTWCAPISignals', 'on')
```

To clear **Signals in C API**, type

```
set_param(modelname, 'RTWCAPISignals', 'off')
```

To select **Parameters in C API**, type

```
set_param(modelname, 'RTWCAPIParams', 'on')
```

To clear **Parameters in C API**, type

```
set_param(modelname, 'RTWCAPIParams', 'off')
```

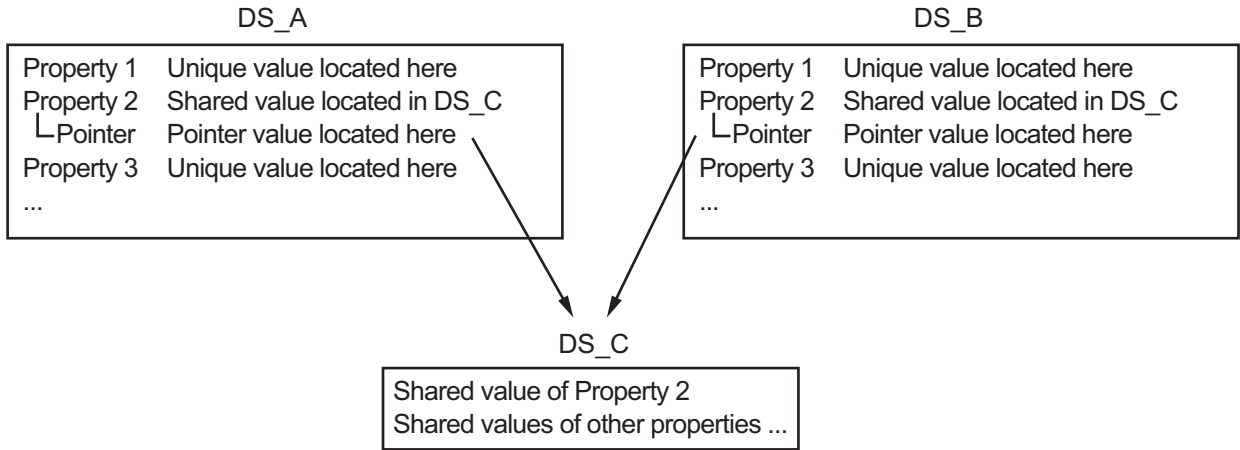
Description of C-API Files

The *model_capi.c* or *model_capi.cpp* file provides external applications with a consistent interface to the model's data. Depending on your configuration settings, the data could be a signal or parameter. In this discussion, the term "data item" refers to either a signal or a parameter. The C-API uses structures that provide an interface to the data item properties. The interface packages the properties of each data item in a data structure. If there are multiple data items in the model, the interface generates an array of data structures. The members of a data structure map to data properties.

Typically, to interface with data items, an application requires the following properties for each:

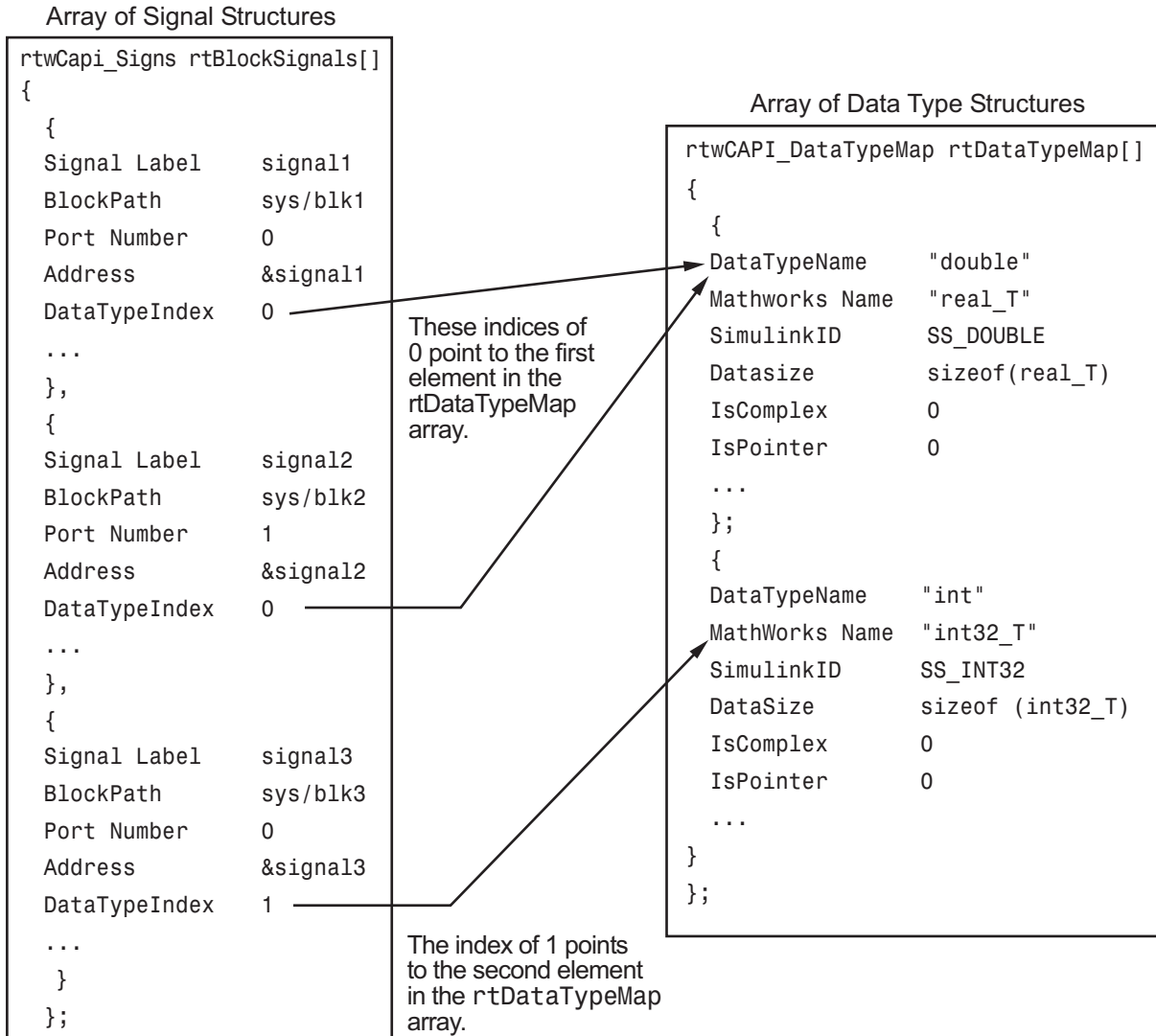
- Description: name, block path
- Address
- Data type information: native data type, data size, complexity, fixed-point scaling
- Dimensions information: number of rows, number of columns, data orientation (scalar, vector, matrix, or n -dimensional)
- Sample-time information (for signal only): sample time, task identifier, frames

As illustrated in the next figure, the properties of data item A, for example, are located in data structure DS_A. The properties of data item B are located in data structure DS_B.



Some property *values* can be unique to each data item, and there are some that several data items can share in common. Address, for example, has a unique value for each data item. But data type could be a property whose value several data items have in common. The interface places the unique property values directly in the data item's structure. So the address value of data item A is in DS_A.

But the fact that some data items can share a property allows the C-API to have a reuse feature. In this case, the interface places only an index value in DS_A and index value in DS_B. These indices point to a different data structure, DS_C, that contains the actual data type value. The next figure shows this scheme with more detail.



The figure shows three signals. Notice that signal1 and signal2 share the same data type, namely double. Instead of specifying this data type value in each signal data structure, the interface provides only an index value in the structure. "double" is in `rtwCapi_DataTypeMap rtDataTypeMap[]`. This

reuse of information reduces the memory size of the generated interface. Reuse can also occur between parameters and signals.

Structure Arrays Generated in the C-API File

Like data type, the interface maps other common properties (such as dimension, fixed-point scaling, and sample time) into separate structures and provides an index in the data item's structure. For a complete list of structure definitions, refer to the file *matlabroot/rtw/c/src/rtw_capi.h*. This file also describes each member in a structure. The structure arrays generated in the *model_capi.c* or *model_capi.cpp* file are of structure types defined in the *rtw_capi.h* file. Here is a brief description of the structure arrays generated in *model_capi.c* and *model_capi.cpp*:

- `rtBlockSignals` is an array of structures that contains information about global block output signals in the model. Each element in the array is of type `struct rtwCAPI_Signals`. The members of this structure provide the signal's path, name, address, and indices to the data type, dimensions, and fixed-point structure arrays.
- `rtBlockParameters` is an array of structures that contains information about the tunable block parameters in the model by block name and parameter name. Each element in the array is of type `struct rtwCAPI-BlockParameters`. The members of this structure provide the parameter's name, block path, parameter address, and indices to data type, dimension, and fixed-point structure arrays.
- `rtModelParameters` is an array of structures that contains information about all workplace variables that one or more blocks or Stateflow charts in the model referenced as block parameters. Each element in the array is of data type `rtwCAPI_ModelParameters`. The members of this structure provide the variable's name, address, and indices to data type, dimension, and fixed-point structure arrays.
- `rtDataAddrMap` is an array of base addresses of signals and parameters that appear in the `rtBlockSignals`, `rtBlockParameters`, and `rtModelParameters` structures. Each element of the `rtDataAddrMap` array is a pointer to void (`void*`).
- `rtDataTypeMap` array contains information about the various data types in the model. Each element of this array is of type `struct rtwCAPI-DataTypeMap`. The members of this structure provide the data

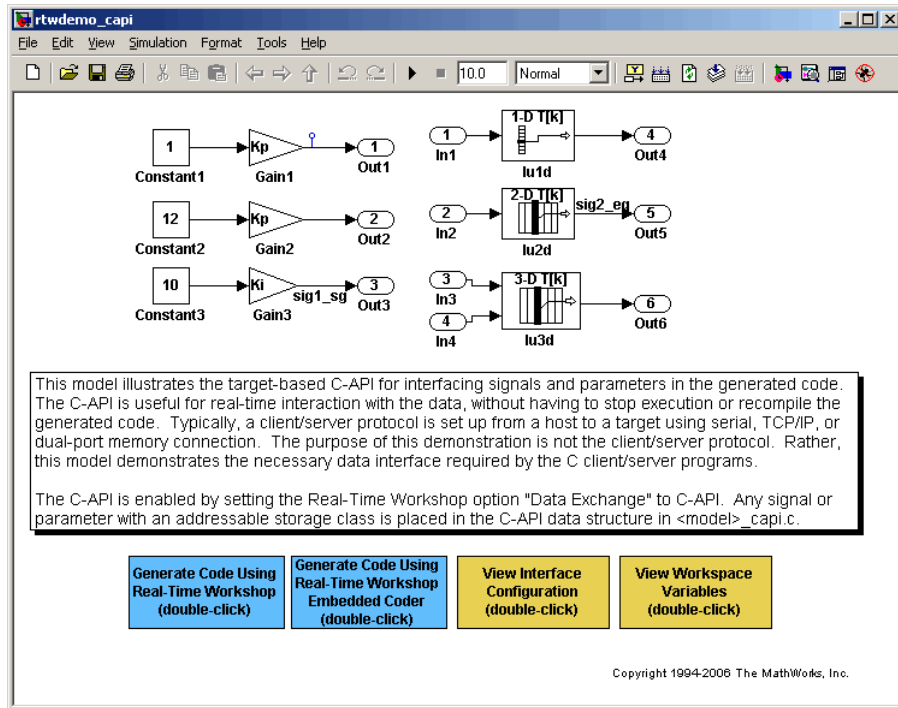
type name, size of the data type, and information on whether or not the data is complex.

- `rtDimensionMap` array contains information about the various data dimensions in the model. Each element of this array is of type `struct rtwC_API_DimensionsMap`. The members of this structure provide information on the number of dimensions in the data, the orientation of the data (whether it is scalar, vector, or a matrix), and the actual dimensions of the data.
- `rtFixPtMap` array contains fixed-point information about the signals and parameters. Each element of this array is of type `struct rtwC_API_FixPtMap`. The members of this structure provide information about the data's scaling, bias, exponent, and whether or not the fixed-point data is signed. If the model does not have fixed-point data (signal or parameter), Real-Time Workshop assigns NULL or zero values to the elements of the `rtFixPtMap` array.
- `rtSampleTimeMap` array contains sampling information about the model's global signals. (This array contains no information about parameters.) Each element of this array is of type `struct rtwC_API_SampleTimeMap`. The members of this structure provide information about the sample period, offset, and whether or not the data is frame-based or sample-based.

Example `model_capi.c` File

This section discusses the generated C-API structures for the demo model `rtwdemo_capi`. This model is located in `matlabroot/toolbox/rtw/rtwdemos` directory.

Open the model by clicking the link above or by typing `rtwdemo_capi` on the MATLAB command line. The model appears as shown in the next figure.



This model has three global signals, two named and one unnamed: sig1_sg and sig2_eg, and the unnamed signal is the test point at the output of the Gain1 block. There are five parameters: Kp (Gain1 and Gain2 blocks share), Ki (Gain3 block), p1 (lookup table lu1d), p2 (lookup table lu2d), p3 (lookup table lu3d).

C-API Signals

The `rtwC_API_Signals` structure captures the signal's description, address, data type information, dimensions information, and sample-time information.

Here is the section of code in `rtwdemo_capi_capi.c` that provides information on C-API signals:

```

15 /* Block output signal information */
16 static const rtwC_API_Signals rtBlockSignals[] = {
17

```



```

18  /* addrMapIndex, sysNum, blockPath,
19  * signalLabel, portNumber, dataTypeIndex, dimIndex,
20  * fxpIndex, sampTimeIndex
21  */
22  {0, 0, "rtwdemo_capi/Gain1",
23   "NULL", 0, 0, 0, 0, 0},
24  {1, 0, "rtwdemo_capi/Gain3",
25   "sig1_sg", 0, 0, 0, 0, 0},
26  {2, 0, "rtwdemo_capi/lu2d",
27   "sig2_eg", 0, 0, 1, 0, 0},
28  {
29   0, 0, NULL, NULL, 0, 0, 0, 0, 0
30  }
31  };

```

Note To better understand the code, be sure to read the file's comments. Notice the comment that begins on line 18 above, for example. This comment lists the members of the `rtwC_API_Signals` structure, in order. This tells you the order in which the assigned values for each member appear for a signal. In this example, the comment tells you that `signalLabel` is the fourth member of the structure. Lines 26 and 27 describe the third signal. Thus, from line 27, you infer that this signal name (label) is `sig2_eg`.

Each array element, except the last, describes one output port for a block signal. The final array element is a sentinel, with all elements set to null values. Take the second signal, described by the code in lines 24 and 25, for example:

```

24  {1, 0, "rtwdemo_capi/Gain3",
25   "sig1_sg", 0, 0, 0, 0, 0}

```

This signal, named `sig1_sg`, is the output signal of the first port of the block `rtwdemo_capi/Gain3`. (It is the first port because the index for `portNumber` on line 25 is assigned the value 0.) The address of this signal is given by the `addrMapIndex`, which, in this example, is 1 on line 24. This gives the index to the `rtDataAddrMap` array, found later in `rtwdemo_capi_capi.c`.

The first member value on line 24 is 1. This is the value of `addrMapIndex` for the signal described on lines 24 to 25. The index of 1 points to the second element in the `rtDataAddrMap` array. So, from the `rtDataAddrMap` array, you can infer that the address of this signal is `&rtwdemo_capi_B.sig1_sg`.

This level of indirection is provided to support multiple code instances of the same model. For multiple instances, the signal information remains constant, except for the address. In this case, the model is a single instance. Therefore, the `rtDataAddrMap` is declared statically. If you choose to generate reusable code, an initialize function is generated that initializes the addresses dynamically per instance. (For details on generating reusable code, see “Configuring Model Interfaces” and “Model Entry Points” in the Real-Time Workshop Embedded Coder documentation.)

The `dataTypeIndex` provides the index to the `rtDataTypeMap` array indicating the data type of the signal:

```
/* Data Type Map - Use dataTypeMapIndex to access this
 * structure */
static const rtwCAPI_DataTypeMap rtDataTypeMap[] = {
    /* cName, mwName, numElements, elemMapIndex, dataSize,
     * sldataId, isComplex, isPointer */
    {"double", "real_T", 0, 0, sizeof(real_T), SS_DOUBLE, 0, 0}
};
```

Because this index is 0 for `sig1_sg`, it points to the first structure element in the array. So you can infer that the signal’s data type is double. The value of `isComplex` is 0, indicating that the signal is not complex. Rather than providing the data type information directly in the `rtwCAPI_Signals` structure, a level of indirection is introduced. The indirection allows multiple signals that share the same data type to point to one map structure. This saves memory for each signal.

The `dimIndex` provides the index to the `rtDimensionMap` array indicating the dimensions of the signal. Because this index is 0 on line 25, it points to the first element in the `rtDimensionMap` array:

```
/* dataOrientation, dimArrayIndex, numDims */
{rtwCAPI_SCALAR, 0, 2}
```

From this structure you can infer that this is a scalar signal having a dimension of 2.

The `fixPtIndex` provides the index to the `rtFixPtMap` array indicating any fixed-point information about the signal. Your code can use the scaling information provided to compute the real-world value of the signal, using the equation $V = SQ + B$, where V is “real-world” (that is, base-10) value, S is user-specified slope, Q is “quantized fixed-point value” or “stored integer,” and B is user-specified bias. (For details, see “Scaling” in the Fixed-Point Toolbox documentation.)

Because this index is 0 on line 25, the signal has no fixed-point information. A fixed-point map index of zero always means that the signal has no fixed-point information.

The `sampTimeIndex` provides the index to the `rtSampleTimeMap` array indicating task information about the signal. The sampling information can be useful if you log multirate signals or conditionally executed signals.

`model_capi.c` and `model_capi.cpp` include `rtw_capi.h`. Any source file that references the `rtBlockSignals` array also should include `rtw_capi.h`.

C-API Parameters

The `rtCAPI_ModelParameter` structure captures the parameter’s description, address, data type information, and dimensions information. Each element in the `rtModelParameters` array corresponds to a tunable parameter in the model. The code below is an example of elements in this array:

```

49  /* Tunable variable parameters */
50
51  static const rtwCAPI_ModelParameters rtModelParameters[] = {
52
53  /* addrMapIndex, varName, dataTypeIndex, dimIndex,
54   * fixPtIndex */
55
56  {3, "Ki", 0, 0, 0},
57  {4, "Kp", 0, 0, 0},
58  {5, "p1", 0, 2, 0},
59  {6, "p2", 0, 3, 0},

```

```
60 {7, "p3", 0, 4, 0},  
61 {0, NULL, 0, 0, 0 }  
62 };
```

Notice line 58, for example. The `varName` (variable name) of the line 58 parameter is `p2`. The address of this parameter is given by the `addrMapIndex` which, in this example, is 6. This is the index to the `rtDataAddrMap` array, found later in `model_capi.c` or `model_capi.cpp`. Because the index is zero based, 6 corresponds to the seventh element in `rtDataAddrMap`, `&(p2)`. The `dataTypeIndex` is 0, which corresponds to a double and noncomplex parameter. The `dimIndex` (dimension index) is 3. So it points to the fourth element in the `rtDimensionMap` array. Later in the generated C-API file, this fourth element appears as

```
{rtwCAPI_Matrix_COL_MAJOR, 6, 2}
```

As mentioned in “Structure Arrays Generated in the C-API File” on page 17-8, `rtBlockParameters` is an array of structures of type `struct rtwCAPI_Parameters`. In the example, all the members of the structure `rtwCAPI_BlockParameters` are assigned `NULL` and zero values. This is because the **Inline parameters** check box on the **Optimization** pane of the Configuration Parameters dialog box is selected. If you clear this check box, the block parameters are generated in the `rtwCAPI_BlockParameters` structure.

In this manner, the **Inline parameters** check box affects the information generated in the `rtBlockParameters` and `rtModelParameters` arrays.

If **Inline parameters** is cleared,

- The `rtBlockParameters` array contains an entry for every modifiable parameter of every block in the model.
- The `rtModelParameters` array contains only Stateflow data of machine scope. Real-Time Workshop assigns its elements only `NULL` or zero values in the absence of such data.

If **Inline parameters** is selected,

- The `rtBlockParameters` array is empty. Real-Time Workshop assigns its elements only NULL or zero values.
- The `rtModelParameters` array contains entries for all workspace variables that are referenced as tunable Simulink block parameters or Stateflow data of machine scope.

Mapping C-API Data Structures to Real-Time Model

The real-time model data structure encapsulates model data and associated information necessary to describe the model fully. For details, see “The Real-Time Model Data Structure” on page 7-31. When you select the C-API feature and generate code, Real-Time Workshop adds another member to the real-time model data structure:

```
struct {
    rtwCAPI_ModelMappingInfo mmi;
} DataMapInfo;
```

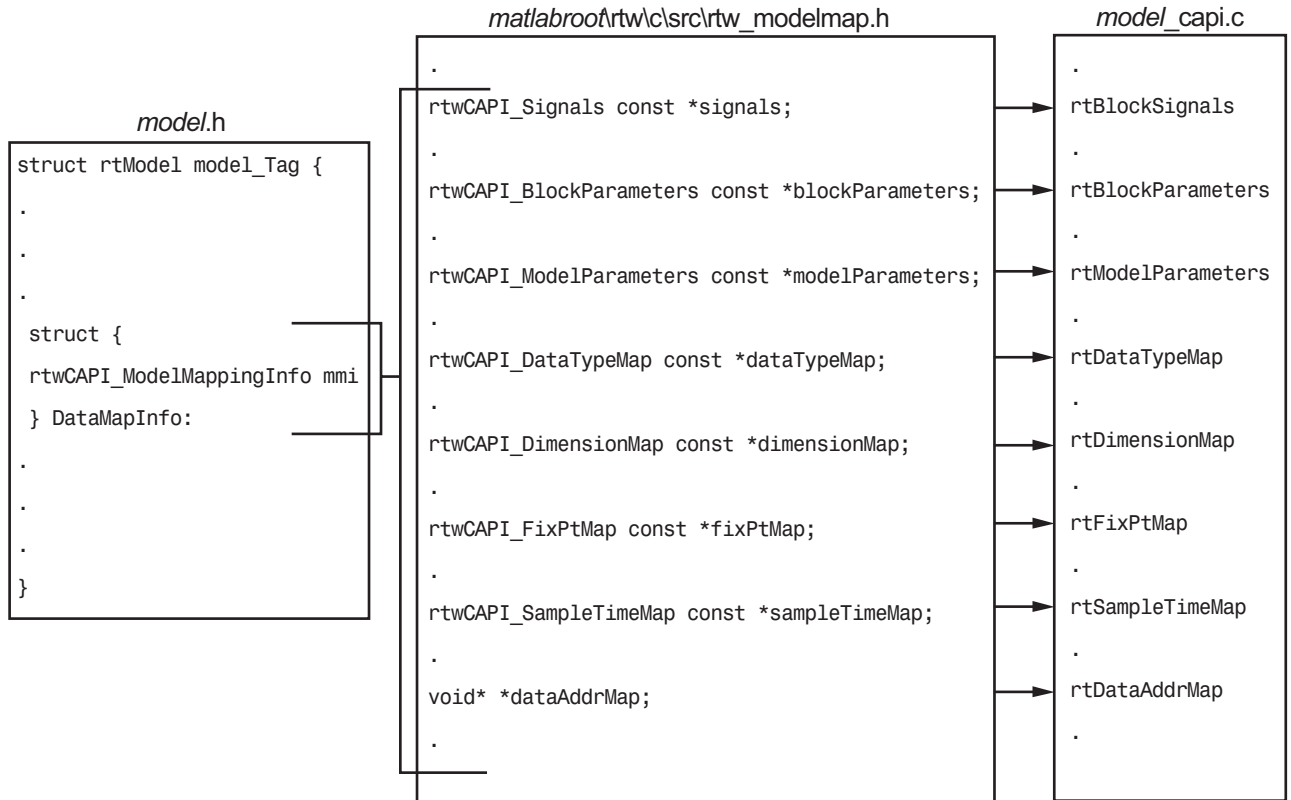
This member defines `mmi` (for model mapping information) of type `struct rtwCAPI_ModelMappingInfo`. The structure is provided in `matlabroot/rtw/c/src/rtw_modelmap.h`. The `mmi` substructure defines the interface between the model and the C-API files. More specifically, members of `mmi` map the real-time model data structure to the structures in the `model_capi.c`.

Initializing values of `mmi` members to the arrays accomplishes the mapping. See the next figure. Each member points to one of the arrays of structures in the generated C-API file. For example, the address of the `rtBlockSignals` array of structures is allocated to the first member of the `mmi` substructure in `model.c`, using the following code in the `rtwmodelmap.h` file:

```
/* signals */
struct {
    rtwCAPI_Signals const *signals; /* Signals Array */
    uint_T numSignals; /* Num Signals */
} Signals;
```

The model initialize function in `model.c` or `model.cpp` performs the initializing during model initialization. It does so by calling the C-API initialize function:

```
rtwdemo_capi_InitializeDataMapInfo(rtwdemo_capi_M).
```



Mapping Between Model and C-API Arrays of Structures

Using the C-API in an Application

The C-API provides you with the flexibility of writing your own application code to interact with the signals and parameters. Your target-based application code is compiled with the Real-Time Workshop generated code into an executable. The target-based application code accesses the C-API structure arrays in `model_capi.c` or `model_capi.cpp`. You might have host-based code that interacts with your target-based application code. Or you might have other target-based code that interacts with your target-based

application code. The `rtw_modelmap.h` file provides macros for accessing the structures in these arrays and their members.

An example application is provided below that prints the parameter values of all tunable parameters in a model to the standard output. This code is intended as a starting point for accessing parameter addresses. You can extend the code to perform parameter tuning. The application

- Uses the `rtmGetDataMapInfo` macro to access the mapping information in the `mmi` substructure of the real-time model structure

```
rtwCAPI_ModelMappingInfo* mmi = &(rtmGetDataMapInfo(rtm).mmi);
```

where `rtm` is the pointer to the real-time model structure in `model.c` or `model.cpp`.

- Uses `rtwCAPI_GetNumModelParameters` to get the number of model parameters in mapped C-API:

```
uint_T nModelParams = rtwCAPI_GetNumModelParameters(mmi);
```

- Uses `rtwCAPI_GetModelParameters` to access the array of all model parameter structures mapped in C-API:

```
rtwCAPI_ModelParameters* capiModelParams = \
    rtwCAPI_GetModelParameters(mmi);
```

- Loops over the `capiModelParams` array to access individual parameter structures. A call to the function `capi_PrintModelParameter` displays the value of the parameter.

The example application code is provided below:

```
{
/* Get CAPI Mapping structure from Real-Time Model structure */
rtwCAPI_ModelMappingInfo* capiMap = \
&(rtmGetDataMapInfo(rtwdemo_capi_M).mmi);

/* Get number of Model Parameters from capiMap */
uint_T nModelParams = rtwCAPI_GetNumModelParameters(capiMap);
printf("Number of Model Parameters: %d\n", nModelParams);

/* If the model has Model Parameters, print them using the
```

```
application capi_PrintModelParameter */
if (nModelParams == 0) {
    printf("No Tunable Model Parameters in the model \n");
}
else {
    unsigned int idx;

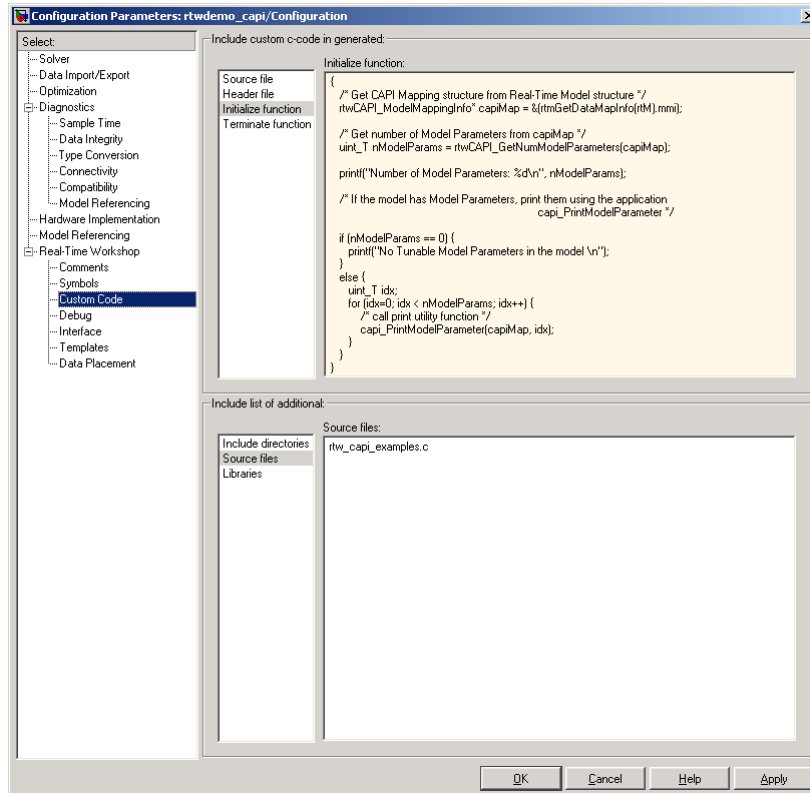
    for (idx=0; idx < nModelParams; idx++) {
        /* call print utility function */
        capi_PrintModelParameter(capiMap, idx);
    }
}
}
```

The print utility function is provided in `matlabroot/rtw/c/src/rtw_capi_examples.c`. This file contains utility functions for accessing the C-API structures.

To become familiar with the example code, try building a model that displays all the tunable block parameters and MATLAB variables. You can use `rtwdemo_capi.mdl`, the C-API demo model, for this purpose. The steps below apply to both `grt.tlc` and `ert.tlc` targets, unless otherwise indicated:

- 1 Open the model `rtwdemo_capi.mdl` by typing `rtwdemo_capi` at the MATLAB command line.
- 2 In the open model, open the Configuration Parameters dialog box by selecting **Configuration Parameters** on the **Simulation** menu.
- 3 Select the **Optimization** pane and verify that the **Inline parameters** option is selected.
- 4 If you want to use `ert.tlc` instead of the default `grt.tlc`, select an `ert.tlc` target in the **System target file** field on the **Real-Time Workshop** pane and click **OK**.
- 5 Use the **Custom Code** pane to embed your custom application code in the generated code: Select the **Custom Code** pane, and then click **Initialize function**. The **Initialize function** input field appears on the right.

- 6 In the **Initialize function** input field, type or copy the example application code provided above. This embeds the application code in the `MdlStart` function. (If you are using `ert.tlc`, the code appears in the `model_initialize` function.)
- 7 Click **Include directories**, and type `matlabroot/rtw/c/src`, where `matlabroot` is the directory where MATLAB is installed on your system.
- 8 In the **Include list of additional** subpane, click **Source files**, and type `rtw_capi_examples.c`, as shown in the figure below. Click the **Apply** button.



- 9 If you are using `ert.tlc`, select the following options on the **Real-Time Workshop > Interface** pane, and then click **Apply**:

- **C-API** in the **Interface** list
 - **MAT-file logging**
 - **Support complex numbers**
- 10** Go to the **Real-Time Workshop** pane and clear the **Generate code only** check box if it is not already cleared.
- 11** Click the **Build** button. Real-Time Workshop generates the executable.
- 12** Type `!rtwdemo_capi` at the MATLAB command line to run the executable. Parameter information is displayed in the Command Window.

C-API Limitations

The C-API feature has the following limitations.

- The following code formats are not supported:
 - S-function
 - Accelerated simulation
- For ERT-based targets, the C-API requires that support for floating-point code be enabled.
- The following signals are not supported:
 - External inputs
 - External outputs
 - Local block outputs
- Parameters local to Stateflow are not supported.
- The following custom storage class objects are not supported:
 - Objects without the package `csc_registration` file are not supported.
 - `BitPackBoolean` objects, grouped custom storage classes, and objects defined by using macro are not supported.
- Customized data placement is disabled when you are using the C-API. The interface looks for global data declaration in `model.h` and `model_private.h`. Declarations placed in any other file by customized data placement result in code that does not compile.

Note Custom Storage Class objects take effect in code generation only if you use the ERT target and clear the **Ignore custom storage classes** check box on the Configuration Parameters dialog box.

Generating C-API and ASAP2 Files

The C-API and ASAP2 interfaces are not mutually exclusive. Although the **Interface** option on the **Real-Time Workshop > Interface** pane of the Configuration Parameters dialog box allows you to select either the ASAP2 or C-API interface, you can instruct Real-Time Workshop to generate files for both interfaces. For details, see “Generating ASAP2 and C-API Files” on page B-21.

Target Language Compiler API for Signals and Parameters

Real-Time Workshop provides a TLC function library that lets you create a *global data map record*. The global data map record, when generated, is added to the `CompiledModel` structure in the `model.rtw` file. The global data map record is a database containing all information required for accessing memory in the generated code, including

- Signals (Block I/O)
- Parameters
- Data type work vectors (DWork)
- External inputs
- External outputs

Use of the global data map requires knowledge of the Target Language Compiler and of the structure of the `model.rtw` file. See the Target Language Compiler documentation for information on these topics.

The TLC functions that are required to generate and access the global data map record are contained in `matlabroot/rtw/c/tlc/mw/globalmaplib.tlc`. The comments in the source code fully document the global data map structures and the library functions.

The global data map structures and functions might be modified or enhanced in future releases.

Creating an External Mode Communication Channel

In this section...

“Introduction” on page 17-23

“The Design of External Mode” on page 17-23

“External Mode Communications Overview” on page 17-26

“External Mode Source Files” on page 17-28

“Guidelines for Implementing the Transport Layer” on page 17-31

Introduction

This section helps you to connect your custom target by using external mode using your own low-level communications layer. The topics include:

- An overview of the design and operation of external mode
- A description of external mode source files
- Guidelines for modifying the external mode source files and building an executable to handle the tasks of the default `ext_comm` MEX-file

This section assumes that you are familiar with the execution of Real-Time Workshop programs, and with the basic operation of external mode. These topics are described in Chapter 7, “Program Architecture” and Chapter 6, “External Mode”.

The Design of External Mode

External mode communication between Simulink and a target system is based on a client/server architecture. The client (Simulink) transmits messages requesting the server (target) to accept parameter changes or to upload signal data. The server responds by executing the request.

A low-level *transport layer* handles physical transmission of messages. Both Simulink and the model code are independent of this layer. Both the transport layer and code directly interfacing to the transport layer are isolated in separate modules that format, transmit, and receive messages and data packets.

This design makes it possible for different targets to use different transport layers. The GRT, GRT malloc, ERT, and RSim targets support host/target communication by using TCP/IP and RS-232 (serial) communication. The RTWin target supports shared memory communication. The Tornado target supports TCP/IP only. Serial transport is implemented only for Windows 32-bit architectures.

Real-Time Workshop provides full source code for both the client and server-side external mode modules, as used by the GRT, GRT malloc, ERT, Rapid Simulation, Real-Time Windows, xPC, and Tornado targets. The main client-side module is `ext_comm.c`. The main server-side module is `ext_svr.c`.

These two modules call the specified transport layer through the following source files.

Built-In Transport Layer Implementations

Protocol	Source File
TCP/IP client	<code>matlabroot/rtw/ext_mode/tcpip/ext_tcpip_transport.c</code>
TCP/IP server	<code>matlabroot/rtw/c/src/ext_mode/tcpip/ext_svr_tcpip_transport.c</code>
Serial client	<code>matlabroot/rtw/ext_mode/serial/ext_serial_transport.c</code>
Serial server	<code>matlabroot/rtw/c/src/ext_mode/serial/ext_svr_serial_transport.c</code>

The modules `ext_tcpip_transport.c` and `ext_serial_transport.c` implement the client-side transport functions. The modules `ext_svr_tcpip_transport.c` and `ext_svr_serial_transport.c` contain the corresponding server-side functions. You can edit copies of these files (but do not modify the originals). You can support external mode by using your own low-level communications layer by creating similar files using the following templates:

- `matlabroot/rtw/ext_mode/custom/ext_custom_transport.c`
- `matlabroot/rtw/c/src/ext_mode/custom/ext_svr_custom_transport.c`

Note Do not modify working source files. Use the templates provided in the /custom directory as starting points, guided by the comments within them.

You need only provide code that implements low-level communications. You need not be concerned with issues such as data conversions between host and target, or with the formatting of messages. Code provided by Real-Time Workshop handles these functions.

On the client (Simulink) side, communications are handled by `ext_comm` (for TCP/IP) and `ext_serial_win32_comm` (for serial) MEX-files. This component is implemented as a DLL on Windows, or as a shared library on UNIX.

On the server (target) side, external mode modules are linked into the target executable. This takes place automatically if the **External mode** code generation option is selected at code generation time, based on the **External mode transport** option selected in the target code generation options dialog box. These modules, called from the main program and the model execution engine, are independent of the generated model code.

Creating a Custom Client Transport Protocol

To implement your own *client-side* low-level transport protocol,

- 1 Edit the template `ext_custom_transport.c` to replace low-level TCP/IP calls with your own communication calls.
- 2 Save it as `ext_xxx_transport.c` (replacing `xxx` with some identifier meaningful to you).
- 3 Generate a customized version of `ext_comm` using the `mex` function, replacing the entry `ext_tcpip_transport.c` with your custom component's filename.

See the table *Commands to Rebuild ext_comm MEX-Files* on page 17-33 for examples of this `mex` function.

- 4 Finally, to make your new transport layer available to users, modify `matlabroot/toolbox/simulink/simulink/extmode_transports.m` according to instructions within it to add your new transport to the

Configuration Parameters Interface pane. The name of the transport will appear in the **Transport layer** menu, and the name of your customized transport file occupies the noneditable **MEX-file name** field when you update the model and select your custom transport.

Creating a Custom Server Transport Protocol

To implement your own *server-side* low-level transport protocol,

- 1 Replace low-level TCP/IP calls in `ext_svr_xxx_transport.c` with your own communication calls.
- 2 Modify all the template makefiles used to support the new transport. If you are writing your own template makefile, make sure that the `EXT_MODE` code generation option is defined. The generated makefile will then link `ext_svr_xxx_transport.c` and other server code into your executable.
- 3 Define symbols and functions common to both the client and server sides in the file you create from the template `ext_custom_utils.c` (replacing `ext_tcpip_utils.c`).

External Mode Communications Overview

This section gives a high-level overview of how a Real-Time Workshop generated program communicates with Simulink in external mode. This description is based on the TCP/IP version of external mode that ships with Real-Time Workshop. At this level of detail, however, there are no differences between the TCP/IP and serial implementations.

For communication to take place,

- The server (target) program must have been built with the conditional `EXT_MODE` defined. `EXT_MODE` is defined in the `model.mk` file if the **External mode** code generation option was selected at code generation time.
- Both the server program and Simulink must be executing. This does not mean that the model code in the server system must be executing. The server can be waiting for Simulink to issue a command to start model execution.

The client and server communicate by using bidirectional sockets carrying packets. Packets consist either of *messages* (commands, parameter downloads, and responses) or *data* (signal uploads).

If the target program was invoked with the `-w` command-line option, the program enters a wait state until it receives a message from the host. Otherwise, the program begins execution of the model. While the target program is in a wait state, Simulink can download parameters to the target and configure data uploading.

When the user chooses the **Connect to target** option from the **Simulation** menu, the host initiates a handshake by sending an `EXT_CONNECT` message. The server responds with information about itself. This information includes

- Checksums. The host uses model checksums to determine that the target code is an exact representation of the current Simulink model.
- Data format information. The host uses this information when formatting data to be downloaded, or interpreting data that has been uploaded.

At this point, host and server are connected. The server is either executing the model or in the wait state. (In the latter case, the user can begin model execution by selecting **Start real-time code** from the **Simulation** menu.)

During model execution, the message server runs as a background task. This task receives and processes messages such as parameter downloads.

Data uploading comprises both foreground execution and background servicing of the signal packets. As the target computes model outputs, it also copies signal values into data upload buffers. This occurs as part of the task associated with each task identifier (`tid`). Therefore, data collection occurs in the foreground. Transmission of the collected data, however, occurs as a background task. The background task sends the data in the collection buffers to Simulink by using data packets.

The host initiates most exchanges as messages. The target usually sends a response confirming that it has received and processed the message. Examples of messages and commands are

- Connection message / connection response

- Start target simulation / start response
- Parameter download / parameter download response
- Arm trigger for data uploading / arm trigger response
- Terminate target simulation / target shutdown response

Model execution terminates when the model reaches its final time, when the host sends a terminate command, or when a Stop Simulation block terminates execution. On termination, the server informs the host that model execution has stopped, and shuts down its socket. The host also shuts down its socket, and exits external mode.

External Mode Source Files

Host MEX-file Interface Source Files

The source files for the MEX-file interface component are located in the directory *matlabroot/rtw/ext_mode*:

- *common/ext_comm.c*

This file is the core of external mode communication. It acts as a relay station between the target and Simulink. *ext_comm.c* communicates to Simulink by using a shared data structure, *ExternalSim*. It communicates to the target by using calls to the transport layer.

Tasks carried out by *ext_comm.c* include establishment of a connection with the target, downloading of parameters, and termination of the connection with the target.

- *tcpip/ext_tcpip_transport.c* (or *serial/ext_serial_transport.c*)

This file implements required transport layer functions. *ext_tcpip_transport.c* includes *ext_tcpip_utils.c*, which lives in *matlabroot/rtw/c/src/ext_mode/tcpip* and contains functions common to client and server sides; similarly, *ext_serial_transport.c* includes *ext_serial_utils.c*, which lives in *matlabroot/rtw/c/src/ext_mode/serial* and contains functions common to client and server sides. The version of *ext_tcpip_transport.c* shipped with Real-Time Workshop uses TCP/IP functions including *recv()*, *send()*, and *socket()*.

- `common/ext_main.c`

This file is a MEX-file wrapper for external mode. `ext_main.c` interfaces to Simulink by using the standard `mexFunction` call. (See the `mexFunction` reference page and External Interfaces in the MATLAB online documentation for more information.) `ext_main.c` contains a function dispatcher, `esGetAction`, that sends requests from Simulink to `ext_comm.c`.

- `common/ext_convert.c` and `ext_convert.h`

This file contains functions used for converting data from host to target formats (and vice versa). Functions include byte-swapping (big to little-endian), conversion from non-IEEE floats to IEEE doubles, and other conversions. These functions are called both by `ext_comm.c` and directly by Simulink (by using function pointers).

Note You do not need to customize `ext_convert` to implement a custom transport layer. However, it might be necessary to customize `ext_convert` for the intended target. For example, if the target represents the float data type in Texas Instruments (TI) format, `ext_convert` must be modified to perform a TI to IEEE conversion.

- `common/extsim.h`

This file defines the `ExternalSim` data structure and access macros. This structure is used for communication between Simulink and `ext_comm.c`.

- `common/extutil.h`

This file contains only conditionals for compilation of the `assert` macro.

- `common/ext_transport.h`

This file defines functions that must be implemented by the transport layer.

Target (Server) Source Files

These files are part of the run-time interface and are linked into the `model.exe` executable. They are located within `matlabroot/rtw/c/src/ext_mode/`.

- `common/ext_svr.c`

`ext_svr.c` is analogous to `ext_comm.c` on the host, but generally is responsible for more tasks. It acts as a relay station between the host and the generated code. Like `ext_comm.c`, `ext_svr.c` carries out tasks such as establishing and terminating connection with the host. `ext_svr.c` also contains the background task functions that either write downloaded parameters to the target model, or extract data from the target data buffers and send it back to the host.

- `tcPIP/ext_svr_tcpip_transport.c`

This file implements required transport layer functions. `ext_svr_tcpip_transport.c` includes `ext_tcpip_utils.c`, which contains functions common to client and server sides, and `ext_serial_transport.c` includes helper functions from `ext_serial_utils.c`. The version of `ext_svr_tcpip_transport.c` shipped with Real-Time Workshop uses TCP/IP functions including `recv()`, `send()`, and `socket()`.

- `common/updown.c`

`updown.c` handles the details of interacting with the target model. During parameter downloads, `updown.c` does the work of installing the new parameters into the model's parameter vector. For data uploading, `updown.c` contains the functions that extract data from the model's `blockio` vector and write the data to the upload buffers. `updown.c` provides services both to `ext_svr.c` and to the model code (for example, `grt_main.c`). It contains code that is called by using the background tasks of `ext_svr.c` as well as code that is called as part of the higher priority model execution.

- `dt_info.h` and `model.dt`

These files contain data type transition information that allows access to multi-data type structures across different computer architectures. This information is used in data conversions between host and target formats.

- `common/updown_util.h`

This file contains only conditionals for compilation of the `assert` macro.

Other Files

- `common/ext_share.h`

Contains message code definitions and other definitions required by both the host and target modules.

- `tcpip/ext_tcpip_utils.c` and `serial/ext_serial_utils.c`
Contains functions and data structures for communication, MEX link, and generated code required by both the host and target modules of the transport layer for TCP/IP and serial protocols, respectively.
- `ext_svr_transport.h`
This file defines functions that must be implemented by the transport layer.
- The serial transport implementation includes the additional files
 - `ext_serial_pkt.c` and `ext_serial_pkt.h`
 - `ext_serial_port.h`
 - `ext_serial_win32_port.c`

Guidelines for Implementing the Transport Layer

If you wish to implement a customized serial transport layer, the easiest way is to modify files provided with Real-Time Workshop. Copy and rename the file `ext_serial_win32_port.c` to `ext_serial_<your_transport>_port.c`, and modify it as needed. Then edit your new transport layer into `matlabroot/toolbox/simulink/simulink/extmode_transports.m` and change your template makefiles to point to your source files.

Requirements

- By default, `ext_svr.c` and `updown.c` use `malloc` to allocate buffers in target memory for messages, data collection, and other purposes, although there is also an option to preallocate static memory. If your target uses another memory allocation scheme, you must modify these modules appropriately.
- The target is assumed to support both `int32_T` and `uint32_T` data types.

Modifying `ext_tcpip_transport.c` and `ext_serial_transport.c`

Function prototypes in `common/ext_transport.h` define the calling interface for the host (client-side) transport layer functions. The implementations are in `ext_tcpip_transport.c` and `ext_serial_transport.c`. These, like other

protocol-specific files described below, occupy parallel directories, /tcpip and /serial.

Host Transport Layer. To implement the host side of your transport layer,

- 1 Replace the functions in the “Visible Functions” section of template file *matlabroot/rtw/c/src/ext_mode/custom/ext_custom_transport.c* with functions that call your low-level communications primitives. The visible functions are called from other external mode modules such as *ext_comm.c*.

You must implement *all* the functions defined in template file *ext_custom_utils.c*, and those implementations must conform to the prototypes defined in *ext_custom_utils.c*.

- 2 Supply a definition for the UserData structure in *ext_tcpip_transport.c* and *ext_serial_transport.c*. This structure is required. If a UserData structure is not necessary for your external mode implementation, define a UserData structure with one dummy field.
- 3 Replace the functions in *matlabroot/rtw/c/src/ext_mode/tcpip/ext_tcpip_utils.c* and/or *matlabroot/rtw/c/src/ext_mode/serial/ext_serial_utils.c* with functions that call your low-level communications primitives, or remove these functions. Functions defined in these files are common to the host and target, and are not part of the public interface to the transport layer.
- 4 Build the customized MEX-file executable using the MATLAB *mex* function. Do not replace the existing *ext_comm* MEX-file if you want to preserve its existing function. Instead, use the *-output* option to name the resulting executable (for example, *mex-output ext_myserial_comm ...* builds *ext_myserial_comm.mexext*, on Windows). Then edit *matlabroot/toolbox/simulink/simulink/extmode_transports.m* and change your template makefiles to make your new transport available.

The following table lists the commands for building the standard *ext_comm* module on PC and UNIX platforms.

Commands to Rebuild ext_comm MEX-Files

Platform	Commands
UNIX, TCP/IP	<pre>mex matlabroot/rtw/ext_mode/common/ext_comm.c matlabroot/rtw/ext_mode/common/ext_convert.c matlabroot/rtw/ext_mode/tcpip/ext_tcpip_transport.c -Imatlabroot/rtw/c/src/ext_mode/common -Imatlabroot/rtw/c/src/ext_mode/tcpip -Imatlabroot/rtw/ext_mode/common -output rtw/ext_comm</pre>
PC, TCP/IP	<pre>mex matlabroot\rtw\ext_mode\common\ext_comm.c matlabroot\rtw\ext_mode\common\ext_convert.c matlabroot\rtw\ext_mode\tcpip\ext_tcpip_transport.c -Imatlabroot\rtw\c\src\ext_mode\common -Imatlabroot\rtw\c\src\ext_mode\tcpip -Imatlabroot\rtw\ext_mode\common -output rtw\ext_comm -DWIN32 compiler_library_path\wsock32.lib</pre>
PC, serial	<pre>mex matlabroot\rtw\ext_mode\common\ext_comm.c matlabroot\rtw\ext_mode\common\ext_convert.c matlabroot\rtw\ext_mode\serial\ext_serial_transport.c matlabroot\rtw\c\src\ext_mode\serial\ext_serial_pkt.c matlabroot\rtw\c\src\ext_mode\serial\ext_serial_win32_port.c -Imatlabroot\rtw\c\src\ext_mode\common -Imatlabroot\rtw\c\src\ext_mode\serial -Imatlabroot\rtw\ext_mode\common -output rtw\ext_serial_win32 -DWIN32 compiler_library_path\wsock32.lib</pre>

See comments in the `ext_custom_transport.c` and `ext_custom_utils.c` source code modules for more details.

Note mex requires a compiler supported by the MATLAB API. See the mex reference page and External Interfaces in the MATLAB online documentation for more information about the mex function.

Guidelines for Modifying `ext_svr_custom_transport`

The function prototypes in `ext_svr_transport.h` define the calling interface for the target (server) side transport layer functions. The implementations are in `ext_svr_tcpip_transport.c` and `ext_svr_serial_transport.c`.

To implement the target side of your transport layer,

- Supply code for the dummy functions in `ext_svr_custom_transport.c` to call your low-level communications primitives. These are the functions called from other target modules such as the main program. Use `ext_svr_tcpip_transport.c` and `ext_svr_serial_transport.c` for guidance as needed. You must implement all the functions defined in `ext_svr_transport.h`. Your implementations must conform to the prototypes defined in that file.
- Supply a definition for the `ExtUserData` structure in `ext_svr_transport.c`. This structure is required. If `ExtUserData` is not necessary for your external mode implementation, define an `ExtUserData` structure with one dummy field.
- Define the `EXT_BLOCKING` conditional in your implementation of `ext_svr_tcpip_transport.c` or `ext_svr_serial_transport.c` as needed:
 - Define `EXT_BLOCKING` as 0 to poll for a connection to the host (appropriate for single-threaded applications).
 - Define `EXT_BLOCKING` as 1 in multithreaded applications where tasks are able to block for a connection to the host without blocking the entire program.

See also the comments on `EXT_BLOCKING` in `ext_svr_transport.c`.

The `ext_svr_transport` source code modules are fully commented. See these files for more details.

Combining Multiple Models

If you want to combine several models (or several instances of the same model) into a single executable, Real-Time Workshop offers several options.

The most powerful solution to use Model blocks. Each instance of a Model block represents another model, called a *referenced model*. For code generation, the referenced model effectively replaces the Model block that references it. For details, see “Referencing a Model” and “Generating Code for Model Referencing” on page 4-26.

If the models to be combined are completely independent of one another and not hierarchically related, other approaches might be more appropriate.

When developing embedded systems using Real-Time Workshop Embedded Coder, you can interface the code for several models to a common harness program by directly calling the entry points to each model. However, Real-Time Workshop Embedded Coder target has certain restrictions that might not be appropriate for your application. For more information, see the Real-Time Workshop Embedded Coder documentation.

The GRT malloc target is another possible solution. Using it is appropriate in situations where you want to do any or all of the following:

- Selectively control calls to more than one model
- Use dynamic memory allocation
- Include models that employ continuous states
- Log data to multiple files
- Run one of the models in external mode

To summarize by targets, your options are as follows:

Target	Support for Combining Independent Multiple Models?
GRT	No (except by using Model blocks)
GRT Malloc	Yes
ERT	Yes
S-Function	No

Using GRT Malloc to Combine Models

This section discusses how to use the GRT malloc target to combine models into a single program. Before reading this section, you should become familiar with model execution in Real-Time Workshop programs. (See Chapter 7, “Program Architecture” and Chapter 8, “Models with Multiple Sample Rates”). It will be helpful to refer to `grt_malloc_main.c` while reading these chapters.

Building a multiple-model executable is fairly straightforward:

- 1 Generate and compile code from each of the models that are to be combined.
- 2 Combine the makefiles for each of the models into one makefile for creating the final multimodel executable.
- 3 Create a combined simulation engine by modifying `grt_malloc_main.c` to initialize and call the models correctly.
- 4 Run the combination makefile to link the object files from the models and the main program into an executable.

Sharing Data Across Models

It is safest to use unidirectional signal connections between models. This affects the order in which models are called. For example, if an output signal from `modelA` is used as input to `modelB`, `modelA`'s output computation should be called first.

Timing Issues

You must generate all the models you are combining with the same solver mode (either all single-tasking or all multitasking.) In addition, if the models employ continuous states, the same solver should be used for all models.

Because each model has its own model-specific definition of the `rtModel` data structure, you must use an alternative mechanism to control model execution, as follows:

- The file `rtw/c/src/rtmcmacros.h` provides an `rtModel` API clue that can be used to call the `rt_OneStep` procedure.
- The `rtmcmacros.h` header file defines the `rtModelCommon` data structure, which has the minimum common elements in the `rtModel` structure required to step a model forward one time step.
- The `rtmcsetCommon` macro populates an object of type `rtModelCommon` by copying the respective similar elements in the model's `rtModel` object. Your main routine must create one `rtModelCommon` structure for each model being called by the main routine.
- The main routine will subsequently invoke `rt_OneStep` with a pointer to the `rtModelCommon` structure instead of a pointer to the `rtModel` structure.

If the base rates for the models are not the same, the main program (such as `grt_malloc_main`) must set up the timer interrupt to occur at the greatest common divisor rate of the models. The main program is responsible for calling each of the models at the appropriate time interval.

Data Logging and External Mode Support

A multiple-model program can log data to separate MAT-files for each model (as in the example program discussed below).

Only one of the models in a multiple-model program can use external mode.

Working with Embedded MATLAB Coder

About Embedded MATLAB Coder (p. 18-3)	Describes what you can do with the Embedded MATLAB Coder and how it processes M-files
Workflows for Converting M-Code to C Code (p. 18-5)	Describes what you need to do to prepare M-code and convert it to C code
Installing Prerequisite Products for Embedded MATLAB Coder (p. 18-8)	Describes the prerequisite products for Embedded MATLAB Coder and how to install them
Setting Up the C Compiler (p. 18-9)	Explains how to install and set up a C compiler for use with Embedded MATLAB Coder
File Paths and Naming Conventions (p. 18-10)	Explains how Embedded MATLAB Coder uses file paths and enforces naming conventions
Making M-Code Compliant with Embedded MATLAB (p. 18-13)	Presents code verification methods and the trade-offs between two strategies: bottom-up and top-down
Configuring Your Environment for Code Generation (p. 18-16)	Explains how to use configuration objects for customizing your environment for code generation
Specifying Properties of Primary Function Inputs (p. 18-22)	Describes why and how to specify the properties of primary function inputs

Choosing Your Target (p. 18-37)	Explains how to select the appropriate target for code generation.
Compiling Your M-File (p. 18-41)	Describes how to run Embedded MATLAB Coder
Working with Compilation Reports (p. 18-44)	Explains how to generate and interpret compilation reports from Embedded MATLAB Coder
Calling Generated C Functions (p. 18-51)	Describes special coding requirements for calling C functions generated from your M-files
Integrating Custom C Code with Generated Code (p. 18-57)	Explains how to integrate custom source code, header files, and libraries with embeddable C code generated from your M-file.

About Embedded MATLAB Coder

In this section...

“Converts M-Code to C Code” on page 18-3

“Running a Demo of Embedded MATLAB Coder” on page 18-4

“How Embedded MATLAB Coder Resolves Function Calls” on page 18-4

Converts M-Code to C Code

Embedded MATLAB Coder works with Real-Time Workshop to automatically convert M-code to C code. With Embedded MATLAB Coder, you can:

- Package generated C code as an executable, library, or MEX function

Note MEX-files are dynamically linked subroutines that the MATLAB interpreter can automatically load and execute. For more information, see “Using MEX-Files to Call C and Fortran Programs” in the MATLAB External Interfaces documentation.

- Verify that your M-code complies with the Embedded MATLAB syntax and semantics.
- Accelerate MATLAB code that uses Fixed-Point Toolbox.

Note The generated code contains optimizations that automatically accelerate fixed-point arithmetic operations.

Note For information about Embedded MATLAB language semantics and syntax, see “Working with Embedded MATLAB” in the Embedded MATLAB documentation.

Running a Demo of Embedded MATLAB Coder

Real-Time Workshop ships with a demo of how to generate embeddable C code from M-code. The demo uses standard MATLAB library functions to detect edges in an image. As part of the demo, you can compile, run, and view the generated C code, and display the results.

If you have a license for Real-Time Workshop, you can run the demo by following these steps:

- 1 At the MATLAB prompt, type this command:

```
democs
```

The Help browser appears, listing categories of demos in the left pane.

- 2 In the left pane, navigate to **Simulink > Real-Time Workshop > Application Samples > Embeddable C-Code Generation Using Embedded MATLAB Coder**.
- 3 Follow the instructions in the right pane of the Help browser.

How Embedded MATLAB Coder Resolves Function Calls

Embedded MATLAB Coder resolves function calls by first searching the Embedded MATLAB path and then the MATLAB path. By default, Embedded MATLAB Coder tries to compile and generate code for functions it finds on the path unless you explicitly declare the function to be extrinsic. Embedded MATLAB does not compile extrinsic functions, but rather dispatches them to MATLAB for execution. For more information, see “How Embedded MATLAB Resolves Function Calls” in the Embedded MATLAB documentation.

To learn about calling MATLAB functions from Embedded MATLAB, see “Calling MATLAB Functions” in the Embedded MATLAB documentation.

Workflows for Converting M-Code to C Code

In this section...

“Workflow for Converting M-Code to Embeddable C Code” on page 18-5

“Workflow for Converting M-Code to a C-MEX Function” on page 18-6

Workflow for Converting M-Code to Embeddable C Code

Follow these steps for converting your M-code to an embeddable C executable or library:

Step	Action	Details
1	Install prerequisite products.	See “Installing Prerequisite Products for Embedded MATLAB Coder” on page 18-8.
2	Set up your C compiler.	See “Setting Up the C Compiler” on page 18-9.
3	Set up your file infrastructure based on compile search paths and naming conventions.	See “File Paths and Naming Conventions” on page 18-10.
4	Make your M-code compliant with Embedded MATLAB.	See “Making M-Code Compliant with Embedded MATLAB” on page 18-13.
5	Configure your environment for code generation.	See “Configuring Your Environment for Code Generation” on page 18-16.
6	Specify properties of primary function inputs.	See “Specifying Properties of Primary Function Inputs” on page 18-22.
7	Choose your target.	See “Choosing Your Target” on page 18-37.

Step	Action	Details
8	Run Embedded MATLAB Coder with the appropriate command line options.	<p>At a minimum, you must specify:</p> <ul style="list-style-type: none"> -T rtw:exe to generate a C code executable or -T rtw:lib to generate a C code library A C file that contains the main function to use for generating a C executable <p>See “Compiling Your M-File” on page 18-41.</p>
9	Generate and interpret compilation reports.	See “Working with Compilation Reports” on page 18-44.
10	Modify your code as necessary to meet special requirements for calling generated C functions from your application.	See “Calling Generated C Functions” on page 18-51.

Workflow for Converting M-Code to a C-MEX Function

Follow these steps for converting your M-code to a C-MEX function:

Step	Action	Details
1	Install prerequisite products.	See “Installing Prerequisite Products for Embedded MATLAB Coder” on page 18-8.
2	Set up your C compiler.	See “Setting Up the C Compiler” on page 18-9.
3	Set up your file infrastructure based on compile search paths and naming conventions.	See “File Paths and Naming Conventions” on page 18-10.
4	Make your M-code compliant with Embedded MATLAB.	See “Making M-Code Compliant with Embedded MATLAB” on page 18-13.

Step	Action	Details
5	Specify properties of primary function inputs.	See “Specifying Properties of Primary Function Inputs” on page 18-22.
6	Run Embedded MATLAB Coder with the appropriate command-line options.	See “Compiling Your M-File” on page 18-41.

Installing Prerequisite Products for Embedded MATLAB Coder

Embedded MATLAB Coder ships with Real-Time Workshop. To use Embedded MATLAB Coder, you must install Real-Time Workshop and its prerequisite products:

- MATLAB
- Simulink
- C Compiler

For instructions on installing MathWorks products, see the MATLAB installation documentation for your platform. If you have installed MATLAB and want to check which other MathWorks products are installed, enter `ver` in the MATLAB Command Window.

For instructions on installing and setting up a C compiler, see “Setting Up the C Compiler” on page 18-9.

Setting Up the C Compiler

Before using Embedded MATLAB Coder, you must set up your C compiler by running the `mex -setup` command, as described in the documentation for `mex` in the MATLAB Function Reference. You must run this command even if you use the default C compiler that comes with MATLAB for Windows platforms. You can also use `mex` to choose and configure a different C compiler, as described in “Compiler Requirements” in the MATLAB External Interfaces documentation.

File Paths and Naming Conventions

In this section...
“Compile Path Search Order” on page 18-10
“Can I Add Files to the Embedded MATLAB Path?” on page 18-10
“When to Use the Embedded MATLAB Path” on page 18-10
“Adding Directories to Search Paths” on page 18-11
“Naming Conventions” on page 18-11

Compile Path Search Order

Embedded MATLAB Coder resolves M-functions by searching first on the Embedded MATLAB path and then on the MATLAB path. See “How Embedded MATLAB Resolves Function Calls” in the Embedded MATLAB documentation.

Can I Add Files to the Embedded MATLAB Path?

With Embedded MATLAB Coder, you can prepend directories and files to the Embedded MATLAB path, as described in “Adding Directories to Search Paths” on page 18-11. By default, the Embedded MATLAB path contains the current directory and the Embedded MATLAB libraries.

When to Use the Embedded MATLAB Path

Use the Embedded MATLAB path to override a MATLAB function with a customized version. Since Embedded MATLAB Coder searches the Embedded MATLAB path first, an M-file on the Embedded MATLAB path always shadows an M-file of the same name on the MATLAB path. To override a MATLAB function with a version implemented in Embedded MATLAB libraries, follow these steps:

- 1 Create each version of the M-function in identically-named M-files.
- 2 Add the MATLAB version to the MATLAB path.
- 3 Add the Embedded MATLAB version to the Embedded MATLAB path.

See “Adding Directories to Search Paths” on page 18-11.

Adding Directories to Search Paths

The following table explains how to add directories to search paths:

To add directories to:	Do this:
Embedded MATLAB path	Prepend directories to the Embedded MATLAB path using the compiler option <code>-I</code> . See “-I Add Directories to Embedded MATLAB Path” using <code>emlc</code> in the Real-Time Workshop Function Reference.
MATLAB path	Follow the instructions in “Adding a Directory to the Search Path” in the MATLAB Programming documentation.

Naming Conventions

Embedded MATLAB Coder enforces naming conventions for M-functions and generated files.

- “Reserved Prefixes” on page 18-11
- “Conventions for Naming Generated files” on page 18-11

Reserved Prefixes

Embedded MATLAB reserves the prefix `eml` for global C functions and variables in generated code. For example, Embedded MATLAB runtime library function names all begin with the prefix `emlrt`, such as `emlrtCallMATLAB`. To avoid naming conflicts, do not name C functions or primary M-functions with the prefix `eml`.

Conventions for Naming Generated files

The following table describes how Embedded MATLAB names generated files. Embedded MATLAB Coder follows MATLAB conventions by providing platform-specific extensions for C-MEX files.

Platform	MEX File Extension	Real-Time Workshop Library Extension	Real-Time Workshop Executable Extension
Linux (32-bit)	.mexglx	.a	None
Linux x86-64	.mexa64	.a	None
Windows (32-bit)	.mexw32	.lib	.exe
Window x64	.mexw64	.lib	.exe

Making M-Code Compliant with Embedded MATLAB

In this section...
“Debugging Strategies” on page 18-13
“Detecting Embedded MATLAB Syntax Violations at Compile Time” on page 18-15

Debugging Strategies

Before you perform code verification, The MathWorks recommends that you choose a debugging strategy for detecting and correcting noncompliant code in your MATLAB applications, especially if they consist of a large number of M-files that call each other's functions. Here are two best practices:

Debugging Strategy	What to Do	Pros	Cons
Bottom-up verification	<ol style="list-style-type: none"> 1 Verify that your lowest-level (leaf) functions are compliant. 2 Work your way up the function hierarchy incrementally to compile and verify each function, ending with the top-level function. 	<ul style="list-style-type: none"> • Efficient • Safe • Easy to isolate Embedded MATLAB syntax violations 	Requires application tests that work from the bottom up
Top-down verification	<ol style="list-style-type: none"> 1 Declare all functions called by the top-level function to be extrinsic so Embedded MATLAB Coder does not compile them (see “Declaring MATLAB Functions as Extrinsic Functions” in the Embedded MATLAB documentation). 2 Verify that your top-level function is compliant. 3 Work your way down the function hierarchy incrementally by removing extrinsic declarations one by one to compile and verify each function, ending with the leaf functions. 	Lets you retain your top-level tests	Introduces extraneous code that you must remove after code verification, including: <ul style="list-style-type: none"> • Extrinsic declarations • Additional assignment statements as necessary to convert opaque values returned by extrinsic functions to nonopaque values (see “Working with mxArray” in the Embedded MATLAB documentation)

Detecting Embedded MATLAB Syntax Violations at Compile Time

Before you can successfully convert an M-file to C code, you must verify that your M-code complies with Embedded MATLAB syntax and semantics, as defined in “Working with Embedded MATLAB”.

Embedded MATLAB Coder checks for all potential Embedded MATLAB syntax violations at compile time. When Embedded MATLAB Coder detects errors or warnings, it automatically generates a compilation report that describes the issues and provides links to the offending M-code. See “Working with Compilation Reports” on page 18-44.

If your M-code calls functions on the MATLAB path, Embedded MATLAB Coder attempts to compile these functions unless you declare them to be extrinsic (see “How Embedded MATLAB Resolves Function Calls” in the Embedded MATLAB documentation). To get detailed diagnostics, add the `%%eml` compiler directive to each external function that you want Embedded MATLAB Coder to compile, as described in “Adding the Compilation Directive `%%eml`” in the Embedded MATLAB documentation.

Configuring Your Environment for Code Generation

In this section...

“Types of Configuration Objects” on page 18-16

“Working with Configuration Objects” on page 18-17

“Creating Configuration Objects” on page 18-18

“Modifying Configuration Objects” on page 18-19

“Saving Configuration Objects” on page 18-20

Types of Configuration Objects

Embedded MATLAB Coder provides configuration objects for customizing your environment for code generation. You can create three types of configuration objects:

Configuration Object	Description	Default Target	Parameter Reference
emlcoder.MEXConfig	Specifies parameters for C-MEX code generation (for C-MEX builds only)	mex (generates C-MEX code unless you specify a different target)	See “Automatic C MEX Generation Dialog Box for Embedded MATLAB Coder” in the Real-Time Workshop Reference documentation.

Configuration Object	Description	Default Target	Parameter Reference
emlcoder.RTWConfig	Specifies parameters for embeddable C code generation (for Real-Time Workshop builds only).	rtw:lib (generates an embeddable C library unless you specify a different target)	See “Real-Time Workshop Dialog Box for Embedded MATLAB Coder” in the Real-Time Workshop Reference documentation.
emlcoder.Hardware-Implementation	Specifies parameters of the target hardware implementation (for Real-Time Workshop builds only). If not specified, Embedded MATLAB Coder generates code that is compatible with the MATLAB host computer.		See “Hardware Implementation Dialog Box for Embedded MATLAB Coder” in the Real-Time Workshop Reference documentation.

For more information about the association between configuration objects and targets, see “Choosing Your Target” on page 18-37.

Working with Configuration Objects

To use configuration objects to customize your environment for code generation, follow these steps:

- 1 Define configuration object variables in the MATLAB workspace, as described in “Creating Configuration Objects” on page 18-18.

For example, the following command defines a Real-Time Workshop configuration object variable called `rtwcfg`:

```
rtwcfg = emlcoder.RTWConfig
```

- 2 Modify the parameters of the configuration object as necessary, using one of these methods:
 - Interactive commands, as described in “Modifying Configuration Objects at the Command Line Using Dot Notation” on page 18-19
 - Graphical user interface, as described in “Modifying Configuration Objects Using Dialog Boxes” on page 18-20
- 3 Invoke Embedded MATLAB Coder with the `-s` option and specify the configuration object as its argument.

The `-s` option instructs Embedded MATLAB Coder to generate code for the target, based on the configuration property values. In the following example, Embedded MATLAB Coder generates a C code library from an M-file `myMfile.m`, based on the parameters of a Real-Time Workshop configuration object `rtwcfg` defined in the first step:

```
emlc -T rtw:lib -s rtwcfg myMfile
```

Note that the `-T` option specifies the type of target you want to build — in this case, a library of embeddable C code. For more information about invoking Embedded MATLAB Coder, see `emlc` in the Real-Time Workshop Function Reference.

Creating Configuration Objects

You can define a configuration object in the MATLAB workspace, as follows:

To Create:	Use a Constructor Command Like This
C-MEX configuration object	<code>mexcfg = emlcoder.MEXConfig</code>

To Create:	Use a Constructor Command Like This
Real-Time Workshop configuration object for generating embeddable C code	<code>rtwcfg = emlcoder.RTWConfig</code>
Hardware implementation configuration object	<code>hwcfg = emlcoder.HardwareImplementation</code>

Each configuration object comes with a set of parameters, initialized to default values (see “Embedded MATLAB Coder Configuration Parameters” in the Real-Time Workshop Reference documentation). You can change these settings as described in “Modifying Configuration Objects” on page 18-19.

Modifying Configuration Objects

This topic describes how to modify the values of configuration objects in Embedded MATLAB Coder and.

- “Modifying Configuration Objects at the Command Line Using Dot Notation” on page 18-19
- “Modifying Configuration Objects Using Dialog Boxes” on page 18-20

Modifying Configuration Objects at the Command Line Using Dot Notation

You can use dot notation to modify the value of one configuration object parameter at a time, using this syntax:

```
configuration_object.property = value
```

Dot notation uses assignment statements to modify configuration object properties:

- To specify a main function during C code generation, enter this code at the command line:

```
rtwcfg = emlcoder.RTWConfig
rtwcfg.CustomInclude = 'c:\myfiles';
rtwcfg.CustomSource = 'main.c';
```

```
emlc -T rtw:exe -s rtwcfg myFun
```

- To automatically generate and launch HTML reports after generating a C library, enter this code:

```
rtwcfg = emlcoder.RTWConfig  
rtwcfg.GenerateReport= true  
rtwcfg.LaunchReport = true  
emlc -T rtw:lib -s rtwcfg myFun
```

Modifying Configuration Objects Using Dialog Boxes

Besides using commands, you can modify code generation parameters using dialog boxes. To learn how to work with these dialog boxes, see “Embedded MATLAB Coder Configuration Parameters” in the Real-Time Workshop Reference documentation.

Saving Configuration Objects

Configuration objects do not automatically persist between MATLAB sessions, but there are two ways to preserve your settings:

- Save a configuration object to a MAT-file and then load the MAT-file at your next session to retrieve your custom settings.

For example, assume you create and customize a C-MEX configuration object `mexcfg` in the MATLAB workspace. To save the configuration object, type this command at the MATLAB prompt:

```
save mexcfg.mat mexcfg
```

MATLAB saves `mexcfg` to the file `mexcfg.mat` in the current directory.

To restore `mexcfg` in a new MATLAB session, type this command at the MATLAB prompt:

```
load mexcfg.mat
```

MATLAB loads the objects defined in `mexcfg.mat` to the MATLAB workspace.

- Write a script that creates the configuration object and sets its properties. You can rerun the script whenever you need to use the configuration object again.

Specifying Properties of Primary Function Inputs

In this section...

“Why You Must Specify Input Properties” on page 18-22

“Properties to Specify” on page 18-22

“Rules for Specifying Properties of Primary Inputs” on page 18-24

“Methods for Defining Properties of Primary Inputs” on page 18-24

“Defining Input Properties by Example at the Command Line” on page 18-25

“Defining Input Properties Programmatically in the M-File” on page 18-28

Why You Must Specify Input Properties

Because C is a statically typed language, Embedded MATLAB Coder must determine the properties of all variables in the M-files at compile time. To infer variable properties in M-files, Embedded MATLAB Coder must be able to identify the properties of the inputs to the *primary* function, also known as the *top-level* or *entry-point* function. Therefore, if your primary function has inputs, you must specify the properties of these inputs, also called *preconditions*, to Embedded MATLAB Coder. If your primary function has no input parameters, Embedded MATLAB Coder can compile your M-file without modification. You do not need to specify properties of inputs to subfunctions or external functions called by the primary function.

Properties to Specify

If your primary function has inputs, you must specify the following properties for each input:

For:	Specify Properties:				
	Class	Size	Complexity	numericType	fimath
Fixed-point inputs	✓	✓	✓	✓	✓

For:	Specify Properties:				
Each field in a structure input	<p>Specify properties for each field according to its class</p> <p>When a primary input is a structure, Embedded MATLAB Coder treats each field as a separate input. Therefore, you must specify properties for all fields of a primary structure input in the order that they appear in the structure definition, as follows:</p> <ul style="list-style-type: none"> • For each field of input structures, specify class, size, and complexity. • For each field that is fixed-point class, also specify numericity, and fimath. 				
All other inputs	✓	✓	✓		

Default Property Values

Embedded MATLAB Coder assigns the following default values for properties of primary function inputs:

Property	Default
class	double
size	scalar
complexity	real
numericity	No default
fimath	No default

Note In most cases, Embedded MATLAB Coder uses defaults when you don't explicitly specify values for properties — except for structure fields. The only way to name a field in a structure is to set at least one of its properties. Therefore, you may need to specify default values for properties of structure fields. For examples, see “Example: Specifying Class and Size of Scalar Structure” on page 18-35 and “Example: Specifying Class and Size of Structure Array” on page 18-36.

Supported Classes

The following table presents the class names supported by Embedded MATLAB Coder:

Class Name	Description
logical	Logical array of true and false values
char	Character array
int8	8-bit signed integer array
uint8	8-bit unsigned integer array
int16	16-bit signed integer array
uint16	16-bit unsigned integer array
int32	32-bit signed integer array
uint32	32-bit unsigned integer array
single	Single-precision floating-point or fixed-point number array
double	Double-precision floating-point or fixed-point number array
struct	Structure array
embedded.fi	Fixed-point number array

Rules for Specifying Properties of Primary Inputs

Follow these rules when specifying the properties of primary inputs:

- For each primary function input whose class is fixed point (fi), you must specify the input's `numericType` and `fimath` properties.
- For each primary function input whose class is `struct`, you must specify the properties of each of its fields in the order that they appear in the structure definition.

Methods for Defining Properties of Primary Inputs

Use one of the following methods to define the properties of primary function inputs:

Method	Pros	Cons
“Defining Input Properties by Example at the Command Line” on page 18-25	<ul style="list-style-type: none"> • Easy to use • Does not alter original M-code • Designed for prototyping a function that has a small number of primary inputs 	<ul style="list-style-type: none"> • Must be specified at the command line every time you invoke Embedded MATLAB Coder (unless you use a script) • Not efficient for specifying memory-intensive inputs such as large structures and arrays
“Defining Input Properties Programmatically in the M-File” on page 18-28	<ul style="list-style-type: none"> • Integrated with M-code so you do not need to redefine properties each time you invoke Embedded MATLAB Coder • Provides documentation of property specifications in the M-code • Efficient for specifying memory-intensive inputs such as large structures 	<ul style="list-style-type: none"> • Uses complex syntax

Note To specify the properties of inputs for any given primary function, use one of these methods, but not both.

Defining Input Properties by Example at the Command Line

- “Command Line Option -eg” on page 18-26
- “Rules for Using the -eg Option” on page 18-26
- “Examples: Specifying Properties of Primary Inputs by Example” on page 18-26
- “Examples: Specifying Properties of Primary Fixed-Point Inputs by Example” on page 18-27

Command Line Option `-eg`

The command that invokes Embedded MATLAB Coder — `emlc` — provides a command-line option `-eg` for specifying the properties of primary function inputs as a cell array of example values. The cell array can be a variable or literal array of constant values. Using this option, you specify the properties of inputs at the same time as you compile the M-file with Embedded MATLAB Coder.

See “`-eg` Specify Input Properties by Example” for `emlc` in the Real-Time Workshop Function Reference.

Rules for Using the `-eg` Option

Follow these rules when using the `-eg` command-line option to define properties by example:

- The cell array of sample values must contain the same number of elements as primary function inputs.
- The order of elements in the cell array must correspond to the order in which inputs appear in the primary function signature — for example, the first element in the cell array defines the properties of the first primary function input.

Examples: Specifying Properties of Primary Inputs by Example

Consider an M-function that adds its two inputs:

```
function y = emcf(u,v)
y = u + v;
```

The following examples show how to specify different properties of the primary inputs `u` and `v` by example at the command line:

- Use a literal cell array of constants to specify that both inputs are real scalar doubles:

```
emlc -o emcfx emcf -eg {0,0}
```

- Use a literal cell array of constants to specify that input `u` is an unsigned 16-bit, 1-by-4 vector and input `v` is a scalar double:

```
emlc -o emcfx emcf -eg {zeros(1,4,'uint16'),0}
```

- Assign sample values to a cell array variable to specify that both inputs are real, unsigned 8-bit integer vectors:

```
a = uint8([1;2;3;4])
b = uint8([5;6;7;8])
ex = {a,b}
emlc -o emcfx emcf -eg ex
```

Examples: Specifying Properties of Primary Fixed-Point Inputs by Example

Consider an M-function that calculates the square root of a fixed-point number:

```
function y = sqrtfi(x)
y = sqrt(x);
```

To specify the properties of the primary fixed-point input *x* by example on the MATLAB command line, follow these steps:

- 1 Define the `numericType` properties for *x*, as in this example:

```
T = numericType('WordLength',32,
               'FractionLength',23,
               'Signed',true);
```

- 2 Define the `fimath` properties for *x*, as in this example:

```
F = fimath('SumMode','SpecifyPrecision',
          'SumWordLength',32,
          'SumFractionLength',23,
          'ProductMode','SpecifyPrecision',
          'ProductWordLength',32,
          'ProductFractionLength',23);
```

- 3 Create a fixed-point variable with the `numericType` and `fimath` properties you just defined, as in this example:

```
myeg = { fi(4.0,T,F) };
```

- 4 Compile the function `sqrtfi` using the `emlc` command, passing the variable `myeg` as the argument to the `-eg` option, as in this example:

```
emlc sqrtfi -eg myeg;
```

Defining Input Properties Programmatically in the M-File

Embedded MATLAB Coder lets you use the MATLAB `assert` function to define properties of primary function inputs directly in your M-file.

- “How to Use `assert` with Embedded MATLAB Coder” on page 18-28
- “Rules for Using `assert` Function” on page 18-33
- “Example: Specifying General Properties of Primary Inputs” on page 18-33
- “Example: Specifying Properties of Primary Fixed-Point Inputs” on page 18-34
- “Example: Specifying Class and Size of Scalar Structure” on page 18-35
- “Example: Specifying Class and Size of Structure Array” on page 18-36

How to Use `assert` with Embedded MATLAB Coder

Use the `assert` function to invoke standard MATLAB functions for specifying the class, size, and complexity of primary function inputs.

Specify Any Class (p. 18-29)	<code>assert (isa (param, 'class_name'))</code>
Specify fi Class (p. 18-29)	<code>assert (isfi (param))</code>
Specify Structure Class (p. 18-30)	<code>assert (isstruct (param))</code>
Specify Any Size (p. 18-30)	<code>assert (all (size(param) == [dims]))</code>
Specify Scalar Size (p. 18-31)	<code>assert (isscalar((param))</code>
Specify Real Input (p. 18-31)	<code>assert (isreal((param))</code>
Specify Complex Input (p. 18-31)	<code>assert (~isreal((param))</code>
Specify numeric type of Fixed-Point Input (p. 18-32)	<code>assert (isequal (numeric type(fi param), T))</code>

Specify fimath of Fixed-Point Input (p. 18-32)	<code>assert (isequal (fimath(<i>fiparam</i>),<i>F</i>))</code>
Specify Multiple Properties of Input (p. 18-32)	<code>assert (<i>function1</i>(<i>params</i>) && <i>function2</i>(<i>params</i>) && <i>function3</i>(<i>params</i>) && ...)</code>

Specify Any Class.

```
assert ( isa ( param, 'class_name' ) )
```

Sets the input parameter *param* to the MATLAB class *class_name*. For example, to set the class of input U to a 32-bit signed integer, call:

```
...
assert(isa(U, 'int32'));
...
```

Note If you set the class of an input parameter to *fi*, you must also set its *numericType* and *fimath* properties (see “Specify numericType of Fixed-Point Input” on page 18-32 and “Specify fimath of Fixed-Point Input” on page 18-32).

If you set the class of an input parameter to *struct*, you must specify the properties of all fields in the order that they appear in the structure definition.

Specify fi Class.

```
assert ( isfi ( param ) )
assert ( isa ( param, 'embedded.fi' ) )
```

Sets the input parameter *param* to the MATLAB class *fi* (fixed-point numeric object). For example, to set the class of input U to *fi*, call:

```
...
assert(isfi(U));
...
```

or

```
...
```

```
assert(isa(U, 'embedded.fi'));  
...
```

Note If you set the class of an input parameter to `fi`, you must also set its `numericType` and `fimath` properties (see “Specify `numericType` of Fixed-Point Input” on page 18-32 and “Specify `fimath` of Fixed-Point Input” on page 18-32).

If you set the class of an input parameter to `struct`, you must specify the properties of all fields in the order they appear in the structure definition.

Specify Structure Class.

```
assert ( isstruct ( param ) )  
assert ( isa ( param, 'struct' ) )
```

Sets the input parameter *param* to the MATLAB class `struct` (structure). For example, to set the class of input `U` to a `struct`, call:

```
...  
assert(isstruct(U));  
...
```

or

```
...  
assert(isa(U, 'struct'));  
...
```

Note If you set the class of an input parameter to `struct`, you must specify the properties of all fields in the order they appear in the structure definition.

Specify Any Size.

```
assert ( all ( size (param) == [dims] ) )
```

Sets the input parameter *param* to the size specified by dimensions *dims*. For example, to set the size of input `U` to a 3-by-2 matrix, call:

```
...
assert(all(size(U)== [3 2]));
...
```

Specify Scalar Size.

```
assert ( isscalar (param ) )
assert ( all ( size (param == [ 1 ] ) ) )
```

Sets the size of input parameter *param* to scalar. For example, to set the size of input *U* to scalar, call:

```
...
assert(isscalar(U));
...
```

or

```
...
assert(all(size(U)== [1]));
...
```

Specify Real Input.

```
assert ( isreal (param ) )
```

Specifies that the input parameter *param* is real. For example, to specify that input *U* is real, call:

```
...
assert(isreal(U));
...
```

Specify Complex Input.

```
assert ( ~isreal (param ) )
```

Specifies that the input parameter *param* is complex. For example, to specify that input *U* is complex, call:

```
...
assert(~isreal(U));
```

```
...
```

Specify numericity of Fixed-Point Input.

```
assert ( isequal ( numericity ( fiparam ), T ) )
```

Sets the numericity properties of `fi` input parameter *fiparam* to the numericity object *T*. For example, to specify the numericity property of fixed-point input *U* as a signed numericity object *T* with 32-bit word length and 30-bit fraction length, use the following code:

```
...
% Define the numericity object.
T = numericity(1, 32, 30);

% Set the numericity property of input U to T.
assert(isequal(numericity(U),T));
...
```

Specify fimath of Fixed-Point Input.

```
assert ( isequal ( fimath ( fiparam ), F ) )
```

Sets the `fimath` properties of `fi` input parameter *fiparam* to the `fimath` object *F*. For example, to specify the `fimath` property of fixed-point input *U* so that it saturates on integer overflow, use the following code:

```
...
% Define the fimath object.
F = fimath('OverflowMode','saturate');

% Set the fimath property of input U to F.
assert(isequal(fimath(U),F));
...
```

Specify Multiple Properties of Input.

```
assert ( function1 ( params ) &&
         function2 ( params ) &&
         function3 ( params ) && ... )
```

Specifies the class, size, and complexity of one or more inputs using a single `assert` function call. For example, the following code specifies that input `U` is a double, complex, 3-by-3 matrix, and input `V` is a 16-bit unsigned integer:

```
...
assert(isa(U, 'double') &&
       ~isreal(U) &&
       all(size(U) == [3 3]) &&
       isa(V, 'uint16'));
...
```

Rules for Using `assert` Function

Follow these rules when using the `assert` function to specify the properties of primary function inputs:

- Call `assert` functions at the beginning of the primary function, before any control-flow operations such as `if` statements or subroutine calls.
- Do not call `assert` functions inside conditional constructs, such as `if`, `for`, `while`, and `switch` statements.
- Use the `assert` function with Embedded MATLAB Coder only for specifying properties of primary function inputs before converting your M-code to C code.
- If you set the class of an input parameter to `fi`, you must also set its `numericType` and `fimath` properties (see “Specify `numericType` of Fixed-Point Input” on page 18-32 and “Specify `fimath` of Fixed-Point Input” on page 18-32).
- If you set the class of an input parameter to `struct`, you must specify the class, size, and complexity of all fields in the order they appear in the structure definition.

Example: Specifying General Properties of Primary Inputs

In the following code excerpt, a primary MATLAB function `emcspecgram` takes two inputs: `pennywhistle` and `win`. The code specifies the following properties for these inputs:

Input	Property	Value
pennywhistle	class	int16
	size	220500-by-1 vector
	complexity	real (by default)
win	class	double (by default)
	size	1024-by-1 vector
	complexity	real (by default)

```
function y = emcspecgram(pennywhistle,win)
nx = 220500;
nfft = 1024;
assert(isa(pennywhistle,'int16'));
assert(all(size(pennywhistle) == [nx 1]));
assert(isa(win, 'double'));
assert(all(size(win) == [nfft 1]));
...
```

Alternatively, you can combine property specifications for one or more inputs inside `assert` commands, as follows:

```
function y = emcspecgram(pennywhistle,win)
nx = 220500;
nfft = 1024;
assert(isa(pennywhistle,'int16') && all(size(pennywhistle) == [nx 1]));
assert(isa(win, 'double') && all(size(win) == [nfft 1]));
...
```

Example: Specifying Properties of Primary Fixed-Point Inputs

In the following example, the primary MATLAB function `emcsqrtfi` takes one fixed-point input: `x`. The code specifies the following properties for this input:

Property	Value
class	fi
numerictype	numerictype object <code>T</code> , as specified in the primary function

Property	Value
fimath	fimath object F, as specified in the primary function
size	scalar (by default)
complexity	real (by default)

```
function y = emcsqrtfi(x)
    T = numericitytype('WordLength',32,'FractionLength',23,
        'Signed',true);
    F = fimath('SumMode','SpecifyPrecision',
        'SumWordLength',32,'SumFractionLength',23,
        'ProductMode','SpecifyPrecision',
        'ProductWordLength',32,'ProductFractionLength',23);
    assert(isfi(x));
    assert(isequal(numericitytype(x),T));
    assert(isequal(fimath(x),F));

    y = sqrt(x);
```

Example: Specifying Class and Size of Scalar Structure

Assume you have defined S as the following scalar MATLAB structure:

```
S = struct('r',double(1),'i',int8(4));
```

Here is code that specifies the class and size of S and its fields when passed as an input to your M-function:

```
function y = fcn(S)

% Specify the class of the input as struct.
assert(isstruct(S));

% Specify the class and size of the fields r and i
% in the order in which you defined them.
assert(isa(S.r,'double'));
assert(isa(S.i,'int8'));
...
```

Note In most cases, Embedded MATLAB Coder uses defaults when you don't explicitly specify values for properties — except for structure fields. The only way to name a field in a structure is to set at least one of its properties. Therefore in the example above, an `assert` function specifies that field `S.r` is of type `double`, even though `double` is the default.

Example: Specifying Class and Size of Structure Array

For structure arrays, you must choose a representative element of the array for specifying the properties of each field. For example, assume you have defined `S` as the following 2-by-2 array of MATLAB structures:

```
S = struct('r',{double(1), double(2)},'i',{int8(4), int8(5)});
```

The following code specifies the class and size of each field of structure input `S` using the first element of the array:

```
function y = fcn(S)

% Specify the class of the input S as struct.
assert(isstruct(S));

% Specify the size of the fields r and i
% based on the first element of the array.
assert(all(size(S) == [2 2]));
assert(isa(S(1).r,'double'));
assert(isa(S(1).i,'int8'));
```

Note In most cases, Embedded MATLAB Coder uses defaults when you don't explicitly specify values for properties — except for structure fields. The only way to name a field in a structure is to set at least one of its properties. Therefore in the example above, an `assert` function specifies that field `S(1).r` is of type `double`, even though `double` is the default.

Choosing Your Target

In this section...
“Types of Targets” on page 18-37
“Specifying the Target to the Compiler” on page 18-38
“Relationship of Targets and Configuration Objects” on page 18-38
“Location of Generated Files” on page 18-39
“Specifying main Functions for C Executables” on page 18-39

Types of Targets

Before compiling your M-file with Embedded MATLAB Coder, you must choose the appropriate target for code generation. Embedded MATLAB Coder provides reserved words that represent each possible target.

To Generate:	Use Target Reserved Word:
C-MEX function	mex (the default)
Embeddable C code and compile it to an executable <hr/> Note When you choose this target, you must provide a C file that contains the main function for generating the executable, as described in “Specifying main Functions for C Executables” on page 18-39.	rtw:exe
Embeddable C code and compile it to a library	rtw:lib or rtw

Specifying the Target to the Compiler

After choosing your target, invoke Embedded MATLAB Coder with the `-T` option and pass the appropriate reserved word as its argument (see “-T Specify Target” for `emlc` in the Real-Time Workshop Reference). For example, suppose you have a primary function called `MyFcn`. The following table shows how to specify different targets when compiling `MyFcn`:

To Generate:	Use This Command:
C-MEX function	<pre>emlc -T mex MyFcn or emlc MyFcn</pre> (translates M-function to C-MEX function by default)
Embeddable C code and compile it to an executable	<pre>rtwcfg = emlcoder.RTWConfig; rtwcfg.CustomSource = 'main.c'; rtwcfg.CustomInclude = 'c:\myfiles'; emlc -T rtw:exe -s rtwcfg MyFcn</pre> <hr/> <p>Note You must specify a main function for generating an embeddable C executable. See “Specifying main Functions for C Executables” on page 18-39.</p> <hr/>
Embeddable C code and compile it to a library	<pre>emlc -T rtw:lib MyFcn or emlc -T rtw MyFcn</pre>

Relationship of Targets and Configuration Objects

There is a relationship between targets and configuration objects. For example, there is a Real-Time Workshop configuration object, `emlcoder.RTWConfig`, that allows you to define properties for the `rtw:lib` and `rtw:exe` targets, that is, for generating embeddable code as a C library or executable. The best practice is to match your configuration object with your target when you invoke Embedded MATLAB Coder, as in this example:

```
rtwcfg = emlcoder.RTWConfig;
emlc -T rtw:lib -s rtwcfg myMFcn
```

However, if you do not specify a target, but do provide a configuration object, Embedded MATLAB Coder determines the target from the configuration object. For example, consider these sample commands:

```
rtwcfg = emlcoder.RTWConfig;
emlc -s rtwcfg myMFcn
```

Normally, when you do not specify a target explicitly, Embedded MATLAB Coder assumes the default target, `mex`, and generates C-MEX code. However in this case, Embedded MATLAB Coder assumes the desired target is `rtw:lib`, based on the configuration object `rtwcfg`, and therefore, generates embeddable C code as a library instead of generating C-MEX code.

For more information about configuration objects, see “Configuring Your Environment for Code Generation” on page 18-16. For more information about invoking Embedded MATLAB Coder, see “Compiling Your M-File” on page 18-41.

Location of Generated Files

By default, Embedded MATLAB Coder generates files in output directories based on your target, as follows:

Target	Default Output Directory
<code>mex</code>	<code>emcprj/mexfcn/function_name</code>
<code>rtw:exe</code>	<code>emcprj/rtwexe/function_name</code>
<code>rtw:lib</code> or <code>rtw</code>	<code>emcprj/rtwlib/function_name</code>

Note You can change the name and location of generated files by using the options “-o Specify Output File Name” and “-d Specify Output Directory” when you run Embedded MATLAB Coder.

Specifying main Functions for C Executables

When you choose `rtw:exe` as your target, you must provide a C file that contains the `main` function for generating your C executable. You can specify the C file by using the `CustomSource` and `CustomInclude` properties of the

Real-Time Workshop configuration object (see “Configuring Your Environment for Code Generation” on page 18-16). The `CustomInclude` property indicates the location of C files specified by `CustomSource`.

To specify a main function for a C executable, follow these steps:

- 1** Create a Real-Time Workshop configuration object, as in this command:

```
rtwcfg = emlcoder.RTWConfig;
```

- 2** Set the `CustomSource` property to the name of the C source file that contains the main function, as in this command:

```
rtwcfg.CustomSource = 'main.c';
```

- 3** Set the `CustomInclude` property to the location of `main.c`, as in this command:

```
rtwcfg.CustomInclude = 'c:\myfiles';
```

- 4** Generate the C executable using the appropriate command line options, as in this example:

```
emlc -T rtw:exe -s rtwcfg myMFunction
```

Embedded MATLAB Coder compiles and links `main.c` with the C code it generates from `myMFunction.m`.

Compiling Your M-File

In this section...

“Before Compiling Your M-Code” on page 18-41

“Running Embedded MATLAB Coder” on page 18-41

“Generated Files and Locations” on page 18-42

“Specifying Custom Files to Build” on page 18-42

Before Compiling Your M-Code

Before compiling M-code, make sure you have followed the prerequisite steps in “Workflows for Converting M-Code to C Code” on page 18-5 or “Workflow for Converting M-Code to a C-MEX Function” on page 18-6.

Running Embedded MATLAB Coder

You run Embedded MATLAB Coder from the MATLAB command prompt by using the `emlc` function. The basic command is:

```
emlc M_fcn
```

By default, `emlc` performs the following actions on the `M_fcn.m`:

- Searches for the function `M_fcn` stored in the file `M_fcn.m` as specified in “Compile Path Search Order” on page 18-10.
- Compiles `M_fcn`, checking for compliance with Embedded MATLAB.
- If there are no errors or warnings, generates a platform-specific C-MEX file in the current directory, using the naming conventions described in “Naming Conventions” on page 18-11.
- If there are errors, does not generate a C-MEX file, but produces an error report in a default output directory, as described in “Generated Files and Locations” on page 18-42. Error reports are described in “Working with Compilation Reports” on page 18-44.
- If there are warnings, but no errors, generates a platform-specific C-MEX file in the current directory, but does report the warnings.

You can modify this default behavior by specifying one or more compiler options with `emlc`, separated by spaces on the command line. For example, to generate a C code executable you must specify the target `rtw:exe` and the location of a main function, as in this example:

```
emlc -T rtw:exe C:\custom\myMain.c M_fcn
```

See `emlc` in the Real-Time Workshop Function Reference.

Generated Files and Locations

By default, Embedded MATLAB Coder generates files in the following locations:

Generates:	In:
Platform-specific C-MEX files	Current directory
C-MEX, C, header, and object files	Default output directory: <code>emcprj/mexfcn/M_fcn_name/</code>
HTML reports (if errors or warnings occur during compilation or you explicitly request a report)	Default output directory: <code>emcprj/mexfcn/M_fcn_name/html</code>

You can change the name and location of generated files by using the options “-o Specify Output File Name” and “-d Specify Output Directory” when you run Embedded MATLAB Coder (see `emlc` in the Real-Time Workshop Function Reference).

Specifying Custom Files to Build

In addition to your M-file, you can specify the following types of custom *files* to include in the build for embeddable C code generation:

File Extension	Description
.c	Custom C file
.h	Custom header file

File Extension	Description
.o , .obj	Custom object file
.a , .lib, .so	Library
.tmf	Template makefile for custom Real-Time Workshop buildsSee “Template Makefiles and Tokens” in the Real-Time Workshop Embedded Coder Developing Embedded Targets documentation.

Working with Compilation Reports

In this section...

“About Compilation Reports” on page 18-44

“Generating Compilation Reports” on page 18-44

“Names and Locations of Compilation Reports” on page 18-44

“Description of Compilation Reports” on page 18-45

“Examples of Reports” on page 18-47

About Compilation Reports

Embedded MATLAB Coder produces reports in HTML format at compile time to help you debug your M-code and verify compliance with the Embedded MATLAB subset.

Generating Compilation Reports

Embedded MATLAB Coder automatically reports errors and warnings. You can also use the “-report Generate Compilation Report” to request reports even when there are no errors or warnings.

Names and Locations of Compilation Reports

Embedded MATLAB Coder produces compilation reports in the following locations:

- For C-MEX targets (mex):

```
output_directory/mexfcn/  
primary_function_name/html/  
primary_function_name_report.html
```

- For C executable targets (rtw:exe):

```
output_directory/rtwexe/  
primary_function_name/html/  
primary_function_name_report.html
```


- For C library targets (rtw:lib):

```
output_directory/rtwlib/  
primary_function_name/html/  
primary_function_name_report.html
```

Note The default output directory is `emcprj`, but you can specify a different directory with the “-d Specify Output Directory” option (see `emlc` in the Real-Time Workshop Function Reference).

Description of Compilation Reports

When you compile M-files with the `-report` option, Embedded MATLAB Coder generates an HTML report that contains the following information:

- Summary of compilation results, including type of target and number of warnings or errors
- Target build log that records compilation and linking activities
- Links to generated files
- Error and warning messages

Embedded MATLAB Coder automatically reports errors and warnings. If errors occur during compilation, Embedded MATLAB Coder does not generate code. If compilation produces warnings, but no errors, Embedded MATLAB Coder does generate code.

Reports present error and warning messages in two views:

- Tree view (default)

For example:



In the tree view, clicking on the document icon brings you to the offending code in the source file.

- List view

For example:

Type	Location	Message
Warning	emcsin1.m:2:1	Unsupported: GLOBAL variables.
Error	emcsin1.m:6:1	Unsupported: GLOBAL variables.
Error	emcsin1.m:7:1	Undefined function or variable 'plot'.

In the list view, clicking on the location link brings you to the offending code in the source file.

When you click on an error or warning message, the report highlights the location of the offending code in the source listing, as in this example:

Contents

[Summary](#)

[Message List View](#)

[Message Tree View](#)

Embedded MATLAB Coder Message List View

Type	Location	Message
Warning	emcsin1.m:2:1	Unsupported: GLOBAL variables.
Error	emcsin1.m:6:1	Unsupported: GLOBAL variables.
Error	emcsin1.m:7:1	Undefined function or variable 'plot'.

Highlight the error line in this report.

Function emcsin1

```

1 function r = emcsin1(num)
2 global x;
3 assert(isa(num,'double'));
4 assert(all(size(num) == [1 10]));
5 r = sin(num);
6 x = cos(num);
7 plot(num,r);

```

Examples of Reports

The topic shows examples of the following reports:

- “Example: Summary Report” on page 18-48
- “Example: Error Report” on page 18-49

Example: Summary Report

Contents	Embedded MATLAB Coder Report Summary
Summary Target Build Log Target Source Files emcsin1.c emcsin1.h rt_nonfinite.c rt_nonfinite.h rtwtypes.h	Embedded MATLAB code generation for M-function emcsin1 C source code generated on: 08-Jun-2007 19:33:52 Coding target: RTW Library Number of errors: 0 Number of warnings: 0

This report summarizes C library code generation for the following M-file:

```
function r = emcsin1(num)

% Declare MATLAB function "plot" extrinsic
% so it is not compiled and instead executed
% in MATLAB
eml.extrinsic('plot')

% Define size and type of input "num"
assert(isa(num,'single'));
assert(all(size(num) == [1 10]));

r = sin(num);
plot(num,r);
```

Embedded MATLAB Coder does not generate reports automatically unless warnings or errors occur during compilation. To request a report, use the “-report Generate Compilation Report” option, as in this example command:

```
emlc -T rtw:lib -report emcsin1
```

Example: Error Report

Contents

[Summary](#)

[Message List View](#)

[Message Tree View](#)

Embedded MATLAB Coder Message Tree View

Open all
Close all

- ☐
📁 emcsin1
 - 📄 [Unsupported: GLOBAL variables.](#)
 - 📄 [Undefined function or variable 'plot'.](#)

Function emcsin1

```

1  function r = emcsin1(num)
2  global x;
3  assert(isa(num,'single'));
4  assert(all(size(num) == [1 10]));
5  r = sin(num);
6  x = cos(num);
7  plot(num,r);

```

This report, produced by the command `emlc -T rtw:lib emcsin1`, displays errors encountered during compilation of the M-code shown in the source listing in the bottom right pane. In this case, there are two errors:

- Embedded MATLAB does not support the MATLAB construct `global`.
- Embedded MATLAB does not support the MATLAB function `plot`.

Note Even though you cannot call unsupported MATLAB functions such as `plot` directly from Embedded MATLAB, you can call them as extrinsic functions or using `feval` (see “Calling MATLAB Functions” in the Embedded MATLAB documentation).

Calling Generated C Functions

In this section...

“Calling C Functions from the Embedded MATLAB Subset” on page 18-51

“Calling Initialize and Terminate Functions” on page 18-52

“Calling C Functions with Multiple Outputs” on page 18-56

“Calling C Functions that Return Arrays” on page 18-56

Calling C Functions from the Embedded MATLAB Subset

You can call the C functions generated for `rtw:lib` targets as custom C code from M functions that comply with the Embedded MATLAB subset. In this scenario, you must use the Embedded MATLAB interface `eml.ceval` to wrap the function calls, as in this example:

```
function y = callmyCFunction
y = 1.5;
y = eml.ceval('myCFunction',y);
```

Here, the Embedded MATLAB function `callmyCFunction` calls the custom C function `myCFunction`, which takes one input argument. For more information about `eml.ceval`, see “Calling C Functions from Embedded MATLAB” in the Embedded MATLAB documentation.

Note `eml.ceval` is part of the Embedded MATLAB language, but is not supported in native MATLAB.

There are additional requirements for calling C functions from the Embedded MATLAB subset in the following situations:

- You want to call generated C libraries (`rtw:lib` targets) or executables (`rtw:exe` targets) from an Embedded MATLAB function. In this case, you must call housekeeping functions generated by Embedded MATLAB Coder, as described in “Calling Initialize and Terminate Functions” on page 18-52.

- You want to call C functions that are generated from M-functions that have more than one output, as described in “Calling C Functions with Multiple Outputs” on page 18-56.
- You want to call C functions that are generated from M-functions that return arrays, as described in “Calling C Functions that Return Arrays” on page 18-56.

Calling Initialize and Terminate Functions

When you convert an M-function to a C library function for `rtw:lib` targets or a C executable for `rtw:exe` targets, Embedded MATLAB Coder automatically generates two housekeeping functions that you must call along with the C function, as follows:

Housekeeping Function	When to Call
<i>primary_function_name_initialize</i>	Before you call your C executable or library function for the first time
<i>primary_function_name_terminate</i>	After you call your C executable or library function for the last time

Note From C code, you can call these functions directly. However, to call them from M code that conforms to the Embedded MATLAB subset, you must use the `eml.ceval` interface, as described in “Calling C Functions from Embedded MATLAB” in the Embedded MATLAB documentation. `eml.ceval` is part of the Embedded MATLAB subset, but not supported by native MATLAB. Therefore, if your M-code uses this interface, you must compile your M-code on the Embedded MATLAB path (see “Adding Directories to Search Paths” on page 18-11).

Example: Calling a C Library Function from M-Code

This example shows how to call a C library function from M-code that conforms to the Embedded MATLAB subset.

Suppose you have an M-file `absval.m` that contains the following M-function:


```
function y = absval(u)
y = abs(u);
```

To generate a C library function and call it from an M-code, follow these steps:

- 1 Generate the C library for `absval.m` by invoking Embedded MATLAB Coder, as follows:

```
emlc -T rtw:lib absval -eg {0.0}
```

Note Here are key points about this command:

- The `-T rtw:lib` option instructs Embedded MATLAB Coder to generate `absval` as a C library function.
 - Embedded MATLAB Coder creates the library `absval.lib` (or `absval.a` on Linux) and header file `absval.h` in the directory `/emcprj/rtwlib/absval`. It also generates the functions `absval_initialize` and `absval_terminate` in the C library.
 - The `-eg` option specifies the class, size, and complexity of the primary function input `u` by example, as described in “Defining Input Properties by Example at the Command Line” on page 18-25.
-

- 2 Write an M-function to call the generated library, as follows:

```
function y = callabsval

% Call the initialize function before
% calling the C function for the first time
eml.ceval('absval_initialize');

y = -2.75;
y = eml.ceval('absval',y);

% Call the terminate function after
% calling the C function for the last time
eml.ceval('absval_terminate');
```

Note The M-function `callabsval` uses the interface `eml.ceval` to call the generated C functions `absval_initialize`, `absval`, and `absval_terminate`. You must use this interface to call C functions from the Embedded MATLAB language subset, as described in “Calling C Functions from Embedded MATLAB” in the Embedded MATLAB documentation.

3 Convert the M-code in `callabsval.m` to a C-MEX function so you can call the C library function `absval` directly from the MATLAB prompt. Follow these steps:

a Generate the C-MEX function by invoking Embedded MATLAB Coder as follows:

On Windows, use this command:

```
emlc -T mex callabsval emcprj/rtwlib/absval/absval.lib
      emcprj/rtwlib/absval/absval.h
```

On Linux, use this command:

```
emlc -T mex callabsval emcprj/rtwlib/absval/absval.a
      emcprj/rtwlib/absval/absval.h
```

b Call the C library by running the C-MEX function from the MATLAB prompt, like this:

```
callabsval
```

Example: Calling a C Library Function from C Code

This example shows how to call a generated C library function from C code. It uses the C library function `absval` described in “Example: Calling a C Library Function from M-Code” on page 18-52.

To call a C library function from a C file, follow these steps:

1 Write a main function in C that does the following:

- Includes the generated header file, which contains the function prototypes for the library function

- Calls the initialize function before calling the library function for the first time
- Calls the terminate function after calling the library function for the last time

Here is an example of a C main function that can be used to call the library function `absval`:

```

/*
** main.c
*/
#include <stdio.h>
#include <stdlib.h>
#include "absval.h"

int main(int argc, char *argv[])
{
    absval_initialize();

    printf("absval(-2.75)=%g\n", absval(-2.75));

    absval_terminate();

    return 0;
}

```

- 2** Configure your target to integrate this custom C main function with your generated code, as described in “Integrating Custom C Code with Generated Code” on page 18-57.

For example, you can define a Real-Time Workshop configuration object that points to the custom C code by following these steps:

- a** Create a Real-Time Workshop configuration object, by entering a command like this at the MATLAB prompt:

```
rtwcfg = emlcoder.RTWConfig;
```

- b** Set custom code properties on the configuration object, as in these example command lines:

```
rtwcfg.CustomSource = 'main.c';  
rtwcfg.CustomInclude = 'c:\myfiles';
```

- 3** Generate the C executable, by entering a command like this at the MATLAB prompt:

```
emlc -T rtw:exe -s rtwcfg absval;
```

- 4** Call the executable, as in this example command:

```
absval(-2.75);
```

Calling C Functions with Multiple Outputs

Although Embedded MATLAB Coder can generate C code from M-functions that have multiple outputs, the generated C code cannot return multiple outputs directly because the C language does not support multiple return values. Instead, you can achieve the effect of returning multiple outputs from your C function by using the construct with `eml.ceval`, as described in “Returning Multiple Values from C Functions” in the Embedded MATLAB documentation.

Calling C Functions that Return Arrays

Although Embedded MATLAB Coder can generate C code from M-functions that return values as arrays, the generated code cannot return arrays *by value* because the C language is limited to returning single, scalar values. Instead, you can return arrays from your C function *by reference* as pointers by using the construct with `eml.ceval`, as described in “Calling C Functions from Embedded MATLAB” in the Embedded MATLAB documentation.

Integrating Custom C Code with Generated Code

In this section...

“About Custom C Code Integration in Embedded MATLAB” on page 18-57

“Specifying Custom C Files on the Command Line” on page 18-57

“Specifying Custom C Files with Configuration Objects” on page 18-57

About Custom C Code Integration in Embedded MATLAB

You integrate custom C code with generated C code by specifying the locations of your external source files, header files, and libraries to Embedded MATLAB Coder. You can specify custom C files on the command line or with configuration objects.

Specifying Custom C Files on the Command Line

When you compile an M-function with Embedded MATLAB Coder, you can specify custom C files — such as source, header, and library files — on the command line along with your M-file. For example, suppose you want to generate an embeddable C code executable that integrates a custom C function `myCfcn` with an M-function `myMfcn`. The custom source and header files for `myCfcn` reside in the directory `C:\custom`. You can use the following command to generate the code:

```
emlc -T rtw:exe C:\custom\myCfcn.c C:\custom\myCfcn.h myMfcn
```

Specifying Custom C Files with Configuration Objects

You can specify custom C files by setting custom code properties on Real-Time Workshop configuration objects (as described in “Real-Time Workshop Dialog Box Overview” in the Real-Time Workshop Reference documentation). Follow these steps:

- 1 Define a Real-Time Workshop configuration object, as described in “Creating Configuration Objects” on page 18-18.

For example:

```
cc = emlcoder.RTWConfig;
```

2 Set one or more of the custom code properties as needed:

Custom Code Property	Description
CustomInclude	<p>Specifies a list of directories that contain custom header, source, object, or library files.</p> <hr/> <p>Note If your directory path name contains spaces, you must enclose it in double quotes, as in this example:</p> <pre>cc.CustomInclude = 'C:\Program Files\MATLAB\work'</pre> <hr/>
CustomSource	Specifies additional custom C files to be compiled with the M-file.
CustomLibrary	Specifies the names of object or library files to be linked with the generated code.
CustomSourceCode	Specifies code to insert at the top of each generated C source file.
CustomHeaderCode	Specifies custom code to insert at the top of each generated C header file.

For example:

```
cc.CustomInclude = 'C:\custom\src C:\custom\lib';
cc.CustomSource = 'cfunction.c';
cc.CustomLibrary = 'chelper.obj clibrary.lib';
cc.CustomSourceCode = '#include "cgfunction.h"';
```

3 Compile the M-code with the Real-Time Workshop configuration object.

For example:

```
emlc -T rtw:lib -s cc myFunc
```

4 Call custom C functions as follows:

From:	Call:
C source code	Custom C functions directly
M-code, compiled on the Embedded MATLAB path	Custom C functions using <code>eml.ceval</code> , as described in “Calling C Functions from Embedded MATLAB” in the Embedded MATLAB documentation.

For example (from M-code):

```
...  
y = 2.5;  
y = eml.ceval('myFunc',y);  
...
```

For more information, see “Configuring Your Environment for Code Generation” on page 18-16.

Blocks That Depend on Absolute Time

Some Simulink blocks use the value of absolute time (that is, the time from the beginning of the program to the present time) to calculate their outputs. If you are designing a program that is intended to run indefinitely, then you must take care when using blocks that have a dependency on absolute time.

The problem arises when the value of time reaches the largest value that can be represented by the data type used by the timer to store time. At that point, the timer overflows and the output of the block is no longer correct. If the target uses rtModel, you can avoid this by setting an appropriate **Application life span** option, see “Integer Timers in Generated Code” on page 15-3 for more information.

Note In addition to the blocks listed below, logging **Time** (in the **Data import/export** pane of the Configuration Parameters dialog box) also requires absolute time.

The following Simulink blocks depend on absolute time:

- Backlash
- Chirp Signal
- Clock
- Derivative
- Digital Clock

- Discrete-Time Integrator (when used in triggered subsystems)
- From File
- From Workspace
- Pulse Generator
- Ramp
- Rate Limiter
- Repeating Sequence
- Signal Generator
- SineWave
- Step
- To File
- To Workspace (only if logging to StructureWithTime format)
- Transport Delay
- Variable Time Delay
- Variable Transport Delay

Note The Sine Wave block is dependent on absolute time only when the **Sine type** parameter is set to Time-based. Set this parameter to Sample-based to avoid absolute time computations.

In addition to the Simulink block above:

- Blocks in other blocksets may reference absolute time. See the documentation for the blocksets that you use.
- Stateflow charts that use time are dependent on absolute time.

Generating ASAP2 Files

ASAP2 is a data definition standard proposed by the Association for Standardization of Automation and Measuring Systems (ASAM). ASAP2 is a standard description you use for data measurement, calibration, and diagnostic systems.

Overview (p. B-3)	Discusses topics with which you should be familiar before working with ASAP2 file generation
Targets Supporting ASAP2 (p. B-4)	Identifies Real-Time Workshop targets with built-in ASAP2 support
Defining ASAP2 Information (p. B-5)	Discusses signal and parameter information of a Simulink model you need to create an ASAP2 file
Generating an ASAP2 File (p. B-8)	Explains the procedure for creating an ASAP2 file from a Simulink model
Customizing an ASAP2 File (p. B-12)	Discusses Target Language Compiler (TLC) files you can change to customize the ASAP2 file generated from a Simulink model

Structure of the ASAP2 File (p. B-19)	Summarizes the parts of the ASAP2 file and the Target Language Compiler functions used to write each part
Generating ASAP2 and C-API Files (p. B-21)	Explains the procedure for generating ASAP2 and C-API files during a single code generation operation

Overview

Real-Time Workshop lets you export an ASAP2 file containing information about your model during the code generation process.

To make use of ASAP2 file generation, you should become familiar with the following topics:

- ASAM and the ASAP2 standard and terminology. See the ASAM Web site at <http://www.asam.de>.
- Simulink data objects. Data objects are used to supply information not contained in the model. For an overview, see “Working with Data” in the Simulink documentation.
- Storage and representation of signals and parameters in generated code. See Chapter 5, “Working with Data Structures”.
- Signal and parameter objects and their use in code generation. See Chapter 5, “Working with Data Structures”.

If you are reading this document online in the MATLAB Help browser, you can run an interactive demo of ASAP2 file generation.

Alternatively, you can access the demo by typing the following command at the MATLAB command prompt:

```
rtwdemo_asap2
```

Targets Supporting ASAP2

ASAP2 file generation is available to all Real-Time Workshop target configurations. You can select these target configurations from the System Target File Browser. For example,

- The Generic Real-Time Target lets you generate an ASAP2 file as part of the code generation and build process.
- Any of the Real-Time Workshop Embedded Coder Target selections also lets you generate an ASAP2 file as part of the code generation and build process.
- The ASAM-ASAP2 Data Definition Target lets you generate only an ASAP2 file, without building an executable.

Procedures for generating ASAP2 files by using these target configurations are given in “Generating an ASAP2 File” on page B-8.

Defining ASAP2 Information

The ASAP2 file generation process requires information about your model's parameters and signals. Some of this information is contained in the model itself. You must supply the rest by using Simulink data objects with the necessary properties.

You can use built-in Simulink data objects to provide the necessary information. For example, you can use `Simulink.Signal` objects to provide information about MEASUREMENTS and `Simulink.Parameter` objects to provide information about CHARACTERISTICS. Also, you can use data objects from data classes that are derived from `Simulink.Signal` and `Simulink.Parameter` to provide the necessary information. For details, see “Working with Data” in the Simulink documentation.

The following table contains the minimum set of data attributes required for ASAP2 file generation. Some data attributes are defined in the model; others are supplied in the properties of objects. For attributes that are defined in `Simulink.Signal` or `Simulink.Parameter` objects, the table gives the associated property name.

Data Attribute	Defined In	Property Name
Name (symbol)	Data object	Inherited from the handle of the data object to which parameter or signal name resolves
Description	Data object	Description
Data type	Model	Not applicable
Scaling (if fixed-point data type)	Model	Data type (for signals) Inherited from value (for parameters)
Minimum allowable value	Data object	Min
Maximum allowable value	Data object	Max

Data Attribute	Defined In	Property Name
Units	Data object	DocUnits
Memory address (optional)	Data object	MemoryAddress_ASAP2 (optional; see “Memory Address Attribute” on page B-6.)

Memory Address Attribute

If the memory address attribute is unknown before code generation, a placeholder string is inserted in the generated ASAP2 file. You can substitute an actual address for the placeholder by postprocessing the generated file. See the file `matlabroot/toolbox/rtw/targets/asap2/asap2/asap2post.m` for an example.

If the memory address attribute is known before code generation, it can be defined in the data object. By default, the `MemoryAddress_ASAP2` property does not exist in the `ASAP2.Signal` or `ASAP2.Parameter` data object classes. If you want to add the attribute, add a property called `MemoryAddress_ASAP2` to a custom class that is a subclass of the `Simulink` or `ASAP2` class. For information on subclassing Simulink data classes, see “Subclassing Simulink Data Classes” in the Simulink documentation.

Note In previous releases, for ASAP2 file generation, it was necessary to define objects explicitly as `ASAP2.Signal` and `ASAP2.Parameter`. This is no longer a limitation. As explained above, you can use built-in Simulink objects for generating an ASAP2 file. If you have been using an earlier release, you can continue to use the ASAP2 objects. If one of these ASAP2 objects was created in the previous release, and you use it in this release, MATLAB displays a warning the first time the objects are loaded.

The following table indicates the Simulink object properties that have replaced the ASAP2 object properties of the previous release:

Differences Between ASAP2 and Simulink Parameter and Signal Object Properties

ASAP2 Object Properties (Previous)	Simulink Object Properties (Current)
LONGIG_ASAP2	Description
PhysicalMin_ASAP2	Min
PhysicalMax_ASAP2	Max
Units_ASAP2	DocUnits

Generating an ASAP2 File

In this section...
“Introduction” on page B-8
“Using Generic Real-Time Target or Embedded Coder Target” on page B-8
“Using the ASAM-ASAP2 Data Definition Target” on page B-10

Introduction

You can generate an ASAP2 file from your model in one of the following ways:

- Use the Generic Real-Time target or a Real-Time Workshop Embedded Coder target to generate an ASAP2 file as part of the code generation and build process.
- Use the ASAM-ASAP2 Data Definition target to generate only an ASAP2 file, without building an executable.

This section discusses how to generate an ASAP2 file by using the targets that have built-in ASAP2 support. For an example, see the ASAP2 demo, `rtwdemo_asap2.mdl`.

Using Generic Real-Time Target or Embedded Coder Target

The procedure for generating a model’s data definition in ASAP2 format using the generic Real-Time target or a Real-Time Workshop Embedded Coder target is as follows:

- 1** Create the desired model. Use appropriate parameter names and signal labels to refer to CHARACTERISTICS and MEASUREMENTS, respectively.
- 2** Define the desired parameters and signals in the model to be `Simulink.Parameter` and `Simulink.Signal` objects in the MATLAB workspace. A convenient way of creating multiple signal and parameter data objects is to use the Data Object Wizard. Alternatively, you can create data objects one at a time from the MATLAB command line. For details on

how to use the Data Object Wizard, see the Real-Time Workshop Embedded Coder Module Packaging Features documentation documentation.

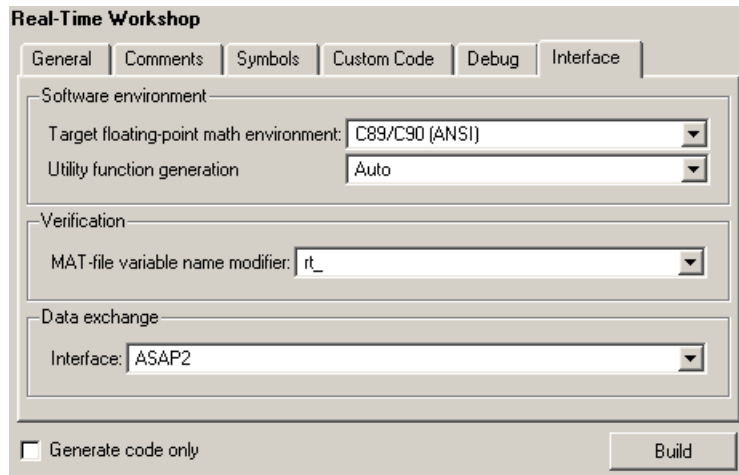
- 3 For each data object, configure the **Storage class** property to a setting other than Auto or SimulinkGlobal. This ensures that the data object is declared as global in the generated code. For example, a storage class setting of ExportedGlobal configures the data object as unstructured global in the generated code.

Note If you set the storage class to Custom and custom storage class settings cause Real-Time Workshop to generate a macro or non-addressable variable, the data object is not represented in the ASAP2 file.

- 4 Configure the remaining properties as desired for each data object.
- 5 On the **Optimization** pane of the Configuration Parameters dialog box, select the **Inline parameters** check box.

You should *not* configure the parameters associated with your data objects as Simulink global (tunable) parameters in the Model Parameter Configuration dialog box. If a parameter that resolves to a Simulink data object is configured using the Model Parameter Configuration dialog box, the dialog box configuration is ignored. You can, however, use the Model Parameter Configuration dialog box to configure other parameters in your model.

- 6 On the **Real-Time Workshop** pane, click **Browse** to open the System Target File Browser. In the browser, select Generic Real-Time Target or any embedded real-time target and click **OK**.
- 7 In the **Interface** field on the **Interface** pane, select ASAP2. The next figure shows the **Interface** pane when the Generic Real-Time Target is selected. If you select an embedded real-time target, the **Interface** pane looks different.



8 Select the **Generate code only** check box on the **Real-Time Workshop** pane.

9 Click **Apply**.

10 Click **Generate code**.

Real-Time Workshop writes the ASAP2 file to the build directory. By default, the file is named *model.a21*, where *model* is the name of the model. The ASAP2 filename is controlled by the ASAP2 setup file. For details see “Customizing an ASAP2 File” on page B-12.

Using the ASAM-ASAP2 Data Definition Target

The procedure for generating a model’s data definition in ASAP2 format using the ASAM-ASAP2 Data Definition Target is as follows:

- 1** Create the desired model. Use appropriate parameter names and signal labels to refer to CHARACTERISTICS and MEASUREMENTS, respectively.
- 2** Define the desired parameters and signals in the model to be Simulink.Parameter and Simulink.Signal objects in the MATLAB workspace. A convenient way of creating multiple signal and parameter data objects is to use the Data Object Wizard. Alternatively, you can create

data objects one at a time from the MATLAB command line. For details on how to use the Data Object Wizard, see the Real-Time Workshop Embedded Coder Module Packaging Features documentation.

- 3 For each data object, configure the **Storage class** property to a setting other than Auto or SimulinkGlobal. This configures the data objects so that their corresponding declarations in the generated code are unstructured global storage declarations.

Note If you set the storage class to Custom and custom storage class settings cause Real-Time Workshop to generate a macro or non-addressable variable, the data object is not represented in the ASAP2 file.

- 4 Configure the remaining properties as desired for each data object.
- 5 On the **Optimization** pane of the Configuration Parameters dialog box, select the **Inline parameters** check box.

You should *not* configure the parameters associated with your data objects as global (tunable) parameters in the Model Parameter Configuration dialog box. If a parameter that resolves to a Simulink data object is configured using the Model Parameter Configuration dialog box, the dialog box configuration is ignored.

- 6 On the **Real-Time Workshop** pane, click **Browse** to open the System Target File Browser. In the browser, select ASAM-ASAP2 Data Definition Target and click **OK**.
- 7 Select the **Generate code only** check box on the **Real-Time Workshop** pane.
- 8 Click **Apply**.
- 9 Click **Generate code**.

Real-Time Workshop writes the ASAP2 file to the build directory. By default, the file is named *model.a21*, where *model* is the name of the model. The ASAP2 filename is controlled by the ASAP2 setup file. For details see “Customizing an ASAP2 File” on page B-12.

Customizing an ASAP2 File

In this section...
“Introduction” on page B-12
“ASAP2 File Structure on the MATLAB Path” on page B-12
“Customizing the Contents of the ASAP2 File” on page B-13
“ASAP2 Templates” on page B-14

Introduction

Real-Time Workshop Embedded Coder provides a number of TLC files to enable you to customize the ASAP2 file generated from a Simulink model.

ASAP2 File Structure on the MATLAB Path

The ASAP2 related files are organized within the directories identified below:

- TLC files for generating ASAP2 file

The *matlabroot/rtw/c/tlc/mw* directory contains TLC files that generate ASAP2 files, *asamlib.tlc*, *asap2lib.tlc*, and *asap2main.tlc*. These files are included by the selected **System target file**. (See “Targets Supporting ASAP2” on page B-4.)

- ASAP2 target files

The *matlabroot/toolbox/rtw/targets/asap2/asap2* directory contains the ASAP2 system target file and other control files.

- Customizable TLC files

The *matlabroot/toolbox/rtw/targets/asap2/asap2/user* directory contains files that you can modify to customize the content of your ASAP2 files.

- ASAP2 templates

The *matlabroot/toolbox/rtw/targets/asap2/asap2/user/templates* directory contains templates that define each type of CHARACTERISTIC in the ASAP2 file.

Customizing the Contents of the ASAP2 File

The ASAP2 related TLC files enable you to customize the appearance of the ASAP2 file generated from a Simulink model. Most customization is done by modifying or adding to the files contained in the `matlabroot/toolbox/rtw/targets/asap2/asap2/user` directory. This section refers to this directory as the `asap2/user` directory.

The user-customizable files provided are divided into two groups:

- The *static* files define the parts of the ASAP2 file that are related to the environment in which the generated code is used. They describe information specific to the user or project. The static files are not model dependent.
- The *dynamic* files define the parts of the ASAP2 file that are generated based on the structure of the source model.

The procedure for customizing the ASAP2 file is as follows:

- 1** Make a copy of the `asap2/user` directory before making any modifications.
- 2** Remove the old `asap2/user` directory from the MATLAB path, or add the new `asap2/user` directory to the MATLAB path above the old directory. This ensures that MATLAB uses the ASAP2 setup file, `asap2setup.tlc` (new for Release 14).

`asap2setup.tlc` specifies the directories and files to include in the TLC path during the ASAP2 file generation process. Modify `asap2setup.tlc` to control the directories and folders included in the TLC path.

- 3** Modify the static parts of the ASAP2 file. These include
 - Project and header symbols, which are specified in `asap2setup.tlc`
 - Static sections of the file, such as file header and tail, `A2ML`, `MOD_COMMON`, and so on. These are specified in `asap2userlib.tlc`.
 - Specify the appearance of the dynamic contents of the ASAP2 file by modifying the existing ASAP2 templates or by defining new ASAP2 templates. Sections of the ASAP2 file affected include
`RECORD_LAYOUTS`: modify appropriate parts of the ASAP2 template files.

CHARACTERISTICS: modify appropriate parts of the ASAP2 template files. For more information on modifying the appearance of **CHARACTERISTICS**, see “ASAP2 Templates” on page B-14.

- **MEASUREMENTS:** These are specified in `asap2userlib.tlc`.
- **COMPU_METHODS:** These are specified in `asap2userlib.tlc`.

ASAP2 Templates

The appearance of **CHARACTERISTICS** in the ASAP2 file is controlled using a different template for each type of **CHARACTERISTIC**. The `asap2/user` directory contains template definition files for scalars, 1-D Lookup Table blocks and 2-D Lookup Table blocks. You can modify these template definition files, or you can create additional templates as required.

The procedure for creating a new ASAP2 template is as follows:

- 1** Define a parameter group. See “Defining Parameter Groups” on page B-14.
- 2** Create a template definition file. See “Creating Template Definition Files” on page B-16.
- 3** Include the template definition file in the TLC path. The path is specified in the ASAP2 setup file, `asap2setup.tlc`.

Defining Parameter Groups

In some cases you must group multiple parameters together in the ASAP2 file (for example, the `x` and `y` data in a 1-D Lookup Table block). Parameter groups enable Simulink blocks to define an associative relationship among some or all of their parameters. The following example shows the `Lookup1D` parameter group and describes how to create and use parameter groups in conjunction with the ASAP2 file generation process.

The `BlockInstanceSetup` function, within a block’s TLC file, creates parameter groups. There are two built-in TLC functions that facilitate this process: `SLibCreateParameterGroup` and `SLibAddMember`. The following code creates the `Lookup1D` parameter group in `look_up.tlc`. Similar syntax is used to create parameter groups for the Look-Up Table (2-D) block.

```
%if GenerateInterfaceAPI
```



```

%% Create a parameter group for ASAP2 data definition
%assign group = SLibCreateParameterGroup(block,"Lookup1D")
%assign tmpVar = SLibAddMember(block,group,InputValues)
%assign tmpVar = SLibAddMember(block,group,OutputValues)
%endif

```

ParameterGroup records are not written to the *model.rtw* file, but are included as part of the relevant block records in the compiled model. The following code shows the Lookup1D parameter group. The Lookup1D parameter group has two member records. The reference fields of these records refer to the relevant x and y data records in GlobalMemoryMap:

```

Block {
  Type          Lookup
  Name          "<Root>/Look-Up Table"
  ...
  NumParameterGroups  1
  ParameterGroup {
    Name          Lookup1D
    NumMembers    2
    Member {
      NumMembers  0
      Reference   ...
    }
    Member {
      NumMembers  0
      Reference   ...
    }
  }
}

```

The Lookup1D parameter group is used by the function ASAP2UserFcnWriteCharacteristic_Lookup1D, which is defined in the template definition file, *asap2lookup1d.tlc*. This function uses the parameter group to obtain the references to the associated x and y data records in the GlobalMemoryMap, as shown in the following code.

```

%function ASAP2UserFcnWriteCharacteristic_Lookup1D(paramGroup)\
    Output
%assign xParam = paramGroup.Member[0].Reference

```

```
    %assign yParam = paramGroup.Member[1].Reference
    ...
%endfunction
```

Creating Template Definition Files

This section describes the components that make up an ASAP2 template definition file. This description is in the form of code examples from `asap2lookup1d.tlc`, the template definition file for the Lookup1D template. This template corresponds to the Lookup1D parameter group.

Note When creating a new template, use the corresponding parameter group name in place of Lookup1D in the code shown.

Template Registration Function

The input argument is the name of the parameter group associated with this template:

```
%<LibASAP2RegisterTemplate("Lookup1D")>
```

RECORD_LAYOUT Name Definition Function

Record layout names (aliases) can be arbitrarily specified for each data type. This function is used by the other components of this file.

```
%function ASAP2UserFcnRecordLayoutAlias_Lookup1D(dtId) void
    %switch dtId
    %case tSS_UINT8
        %return "Lookup1D_UBYTE"
    ...
    %endswitch
%endfunction
```

Function to Write RECORD_LAYOUT Definitions

This function writes RECORD_LAYOUT definitions associated with this template. The function is called by the built-in functions involved in the ASAP2 file generation process. The function name must be defined as shown, with the appropriate template name after the underscore:

```
%function ASAP2UserFcnWriteRecordLayout_Lookup1D() Output
  /begin RECORD_LAYOUT
  %<ASAP2UserFcnRecordLayoutAlias_Lookup1D(tSS_UINT8)>
  ...
  /end RECORD_LAYOUT
%endfunction
```

Function to Write the CHARACTERISTIC

This function writes the CHARACTERISTIC associated with this template. The function is called by the built-in functions involved in the ASAP2 file generation process. The function name must be defined as shown, with the appropriate template name after the underscore.

The input argument to this function is a pointer to a parameter group record. The example shown is for a Lookup1D parameter group that has two members. The references to the associated x and y data records are obtained from the parameter group record as shown.

This function calls a number of built-in functions to obtain the required information. For example, LibASAP2GetSymbol returns the symbol (name) for the specified data record:

```
%function ASAP2UserFcnWriteCharacteristic_Lookup1D(paramGroup)
Output
  %assign xParam = paramGroup.Member[0].Reference
  %assign yParam = paramGroup.Member[1].Reference
  %assign dtId = LibASAP2GetDataTypeId(xParam)
  /begin CHARACTERISTIC
    /* Name */           %<LibASAP2GetSymbol(xParam)>
    /* Long identifier */ %<LibASAP2GetLongID(xParam)>"
    ...
  /end CHARACTERISTIC
%endfunction
```


Structure of the ASAP2 File

The following table outlines the basic structure of the ASAP2 file and describes the Target Language Compiler functions and files used to create each part of the file:

- Static parts of the ASAP2 file are shown in **bold**.
- Function calls are indicated by %<FunctionName()>.

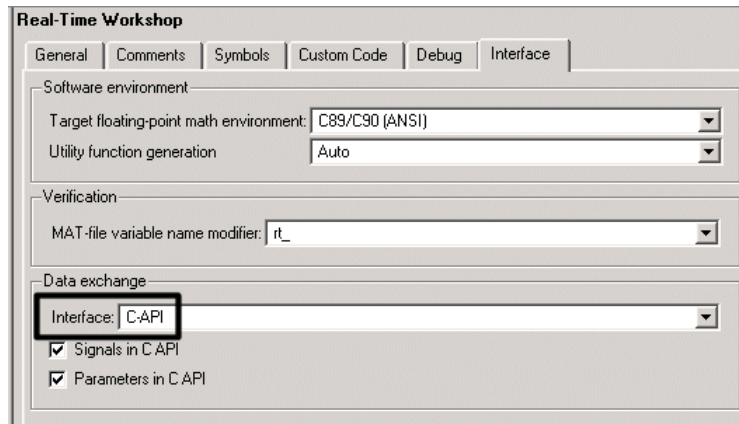
File Section	Contents of asap2main.tlc	TLC File Containing Function Definition
File header	%<ASAP2UserFcnWriteFileHead()>	asap2userlib.tlc
/begin PROJECT "	/begin PROJECT "%<ASAP2ProjectName>"	asap2setup.tlc
/begin HEADER " HEADER contents	/begin HEADER "%<ASAP2HeaderName>" %<ASAP2UserFcnWriteHeader()>	asap2setup.tlc asap2userlib.tlc
/end HEADER	/end HEADER	
/begin MODULE " MODULE contents:	/begin MODULE "%<ASAP2ModuleName>"}	asap2setup.tlc asap2userlib.tlc
- A2ML - MOD_PAR - MOD_COMMON ...	%<ASAP2UserFcnWriteHardwareInterface()>	
Model-dependent MODULE contents:	%<SLibASAP2WriteDynamicContents()> Calls user-defined functions:	asap2lib.tlc
- RECORD_LAYOUTs - CHARACTERISTICS - ParameterGroups - ModelParameters	...WriteRecordLayout_TemplateName() ...WriteCharacteristic_TemplateName() ...WriteCharacteristic_Scalar()	user/templates/...
- MEASUREMENTS - ExternalInputs - BlockOutputs	...WriteMeasurement()	asap2userlib.tlc
- COMPU_METHODS	...WriteCompuMethod()	asap2userlib.tlc

File Section	Contents of asap2main.tlc	TLC File Containing Function Definition
/end MODULE	/end MODULE	
File footer/tail	%<ASAP2UserFcnWriteFileTail(>	asap2userlib.tlc

Generating ASAP2 and C-API Files

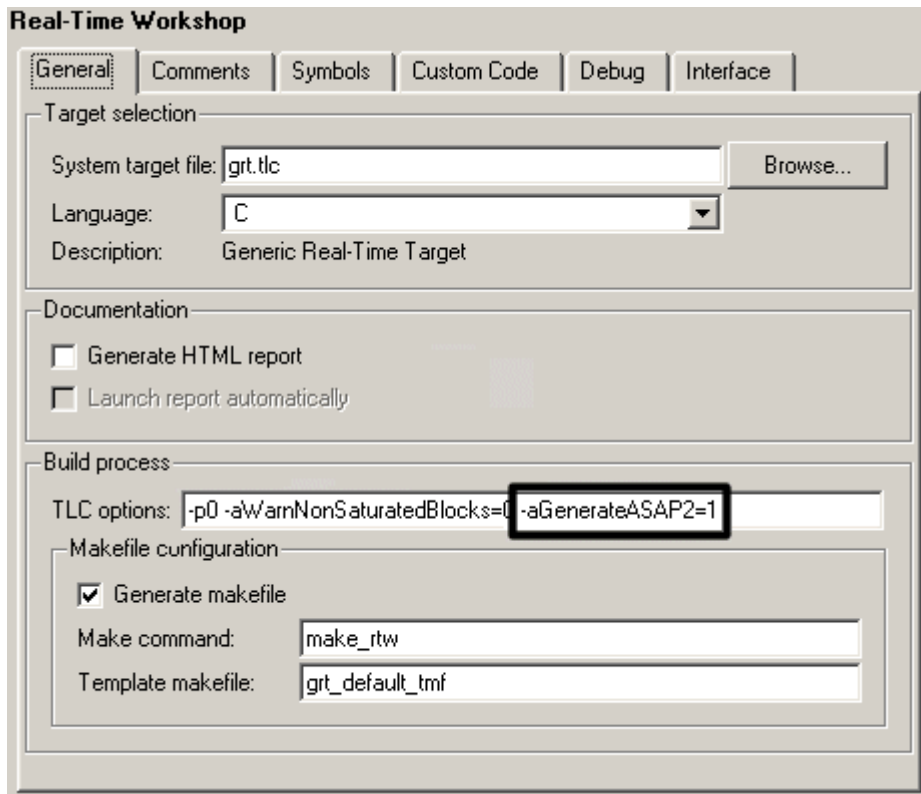
The ASAP2 and C-API interfaces are not mutually exclusive. Although the **Interface** option on the **Real-Time Workshop > Interface** pane of the Configuration Parameters dialog box allows you to select either the ASAP2 or C-API interface, you can instruct Real-Time Workshop to generate files for both interfaces by doing the following:

- 1 In the **Data exchange** section of the **Real-Time Workshop > Interface** pane of the Configuration Parameters dialog box, select **C-API** for the **Interface** option.



- 2 In the **Build process** section of the **Real-Time Workshop** pane, add the following to the **TLC options** text box:

```
-aGenerateASAP2=1
```



3 Click **Generate** or **Build**. Real-Time Workshop generates the following ASAP2 and C-API files:

- *model.a21* — ASAP2 description file
- *model_capi.c* — C-API source file
- *model_capi.h* — C-API header file

For more information about using the C-API interface, see “C-API for Interfacing with Signals and Parameters” on page 17-2.

Examples

Use this list to find examples in the documentation.

Models

- “Block Execution Order” on page 2-44
- “Controlling Signal Object Code Generation By Using Typed Commands” on page 5-56
- “Single-Tasking and Multitasking Execution of a Model: an Example” on page 8-28
- “Other Optimization Tools and Techniques” on page 9-5
- “Inlining Invariant Signals” on page 9-41
- “Configuring a Loop Unrolling Threshold” on page 9-45
- “Dual-Model Approach: Simulation” on page 16-8
- “Spawning a VxWorks Task” on page 16-13

Model Code Packaging

- “Code Packaging Example” on page 2-137

Model Reference

- “Code Reuse and Model Blocks with Root Inport or Outport Blocks” on page 4-42

Data Management

- “Nontunable Parameter Storage” on page 5-3
- “Tunable Expressions in Masked Subsystems” on page 5-14
- “Signals with Auto Storage Class” on page 5-34
- “Symbolic Naming Conventions for Signals in Generated Code” on page 5-42

Optimizations

- “Expression Folding Example” on page 9-10
- “Ignore integer downcasts in folded expressions” on page 9-13
- “Multiple Tables with Common Inputs” on page 9-27
- “Optimizing Data Type Usage” on page 9-34
- “Expression Folding for Blocks with Multiple Outputs” on page 10-66

S-Functions

- “TLC S-Function Wrapper” on page 10-16
- “Writing Fully Inlined S-Functions” on page 10-22
- “Multiport S-Function Example” on page 10-22
- “S-Function RTWdata” on page 10-28
- “The Direct-Index Lookup Table Example” on page 10-30

Custom Code

- “Example: Using a Custom Code Block” on page 14-6

Timing Services

- “Elapsed Timer Code Generation Example” on page 15-10

Interfaces

- “Example model_capi.c File” on page 17-9
- “Using the C-API in an Application” on page 17-16

A

- absolute time computation 15-2
- addLibs field 10-92
- APIs
 - timer services 15-5
- application modules
 - application-specific components 7-35
 - definition of 7-24
 - system-independent components 7-29
- ASAP2 files
 - customizing B-12
 - data attributes required for B-5
 - generating B-8
 - structure of B-19
 - targets supporting B-4
- assertion blocks
 - in generated code 2-29
- asynchronous tasks
 - timers for 15-3
- atomic subsystem 4-2
- automatic S-function generation 11-15
 - See also* S-function target

B

- block states
 - Simulink data objects and 5-79
 - State Properties dialog box and 5-74
 - storage and interfacing 5-72
 - storage classes for 5-73
 - symbolic names for 5-76
- block-based code integration 2-129
 - with S-functions 10-81
- blocks
 - Async Interrupt 16-5
 - Custom Code 14-2
 - depending on absolute time A-1
 - Model Header 14-3
 - Model Source 14-3
 - Rate Transition 8-14

- scope 2-27
- to file 2-27
- to workspace 2-27

- Browse button
 - on Real-Time Workshop pane 2-51
- buffer reuse option 9-41
- build process
 - controlling 2-112
- build specification 10-91

C

- C language
 - selecting 2-52
- C++ language
 - selecting 2-52
- C-API
 - files used in 17-5
 - for S-functions 15-5
 - generating files 17-3
 - introduction 17-2
 - mapping to real-time model 17-15
 - using for your application 17-16
- checksums
 - and S-Function target 11-21
 - for models 11-21
 - subsystem 11-21
- code
 - integrating existing 2-129
 - block-based mechanisms for 2-129
 - build support for 10-81
 - mechanisms for 2-131
- code files
 - porting 2-134
 - relocating 2-134
- code format
 - choosing 3-10
 - embedded 3-18
 - real-time 3-14
 - real-time malloc 3-16

- S-function 3-18
 - code generation 2-1
 - and simulation parameters 2-23
 - from nonvirtual subsystems 4-2
 - code generation options
 - Application lifespan (days) 9-47
 - Boolean logic signals 9-40
 - buffer reuse 9-41
 - See also* signal storage reuse 9-41
 - Compiler optimization level 2-53
 - Custom compiler optimization flags 2-53
 - expression folding 9-9
 - generate HTML report 2-52
 - Generate makefile option 2-54
 - GRT compatible call interface 3-23
 - inline invariant signals 9-41
 - inline parameters 9-43
 - local block outputs 9-41
 - See also* signal storage reuse 9-41
 - loop rolling threshold 9-45
 - MAT-file variable name modifier 2-64
 - retain .rtw file 2-62
 - show eliminated blocks 2-56
 - signal storage reuse 9-40
 - See also* local block outputs 9-40
 - Solver pane 2-23
 - TLC options 2-53
 - verbose builds 2-62
 - Workspace I/O pane 2-25
 - code reuse
 - diagnostics for 4-16
 - enabling 4-12
 - code tracing
 - by using `hilite_system` command 2-125
 - by using HTML reports 2-125
 - combining models
 - by using `grt_malloc` target 17-35
 - in Real-Time Workshop Embedded Coder target 17-35
 - communication
 - external mode 6-2
 - external mode API for 17-23
 - compilation 2-108
 - customizing 2-109
 - compiler
 - configuring 2-19
 - compiler options
 - specifying 2-109
 - configuration parameters
 - TargetLibSuffix
 - controlling suffix applied to library names with 2-115
 - TargetPreComplibLocation
 - controlling location of precompiled libraries with 2-113
 - Configuration Parameters dialog box 2-23
 - Data Import/Export pane 2-25
 - Real-Time Workshop pane 2-50
 - configuring code generation parameters with 2-49
 - specifying nonvirtual code generation with 4-2
 - Solver options pane 2-23
- continuous states, integration of 7-28
 - counters
 - in triggered subsystems 15-4
 - time 15-2
 - cross-development
 - relocating files for 2-134
 - custcode command 14-2
 - custom code
 - block-based integration with generated code 2-129
 - build support for 10-81
 - integrating with C MEX S-functions 10-24
 - integrating with generated code 2-129
 - integration with generated code 2-131
 - Custom Code blocks 14-2
 - example 14-6
 - in subsystems 14-9

Custom Code library
overview 14-2

D

data logging 2-25
by using scope blocks 2-27
by using to file blocks 2-27
by using to workspace blocks 2-27
in single- and multitasking models 2-28
to MAT-files 2-25

Data Store Memory blocks
Simulink data objects and 5-84

data structures in generated code
block I/O 7-22
block parameters 7-22
block states 7-22
external inputs 7-22
external outputs 7-22

declaration code 14-5

direct-index lookup table
algorithm 10-29
example 10-30

directories
used in build process 2-19

directory
precompiled library 10-91

discrete states
initializing 5-60

dt_info.h 2-93

E

elapsed time computation 15-2
elapsed time counters 15-2
in triggered subsystems 15-4
elapsed timer

example 15-10

Embedded MATLAB blocks
and Stateflow optimizations 9-46

Embedded MATLAB Coder
combining property specifications 18-34
specifying general properties of primary
inputs 18-33

Euler integration algorithm 7-29

examples

direct-index lookup table 10-30
multiport S-function 10-22

execution code 14-5

exit code 14-5

Expression folding 9-9
configuring options for 9-13
in S-Functions 10-53

ext_work.h 2-93

external mode 6-2

architecture 6-30

baud rates 6-15

blocks compatible with 6-25

client-server architecture 17-23

command line options for target
program 6-38

communication channel creation 17-23

communications overview 17-26

configuration parameter options 6-3

control panel options 6-11

data archiving options 6-20

design of 17-23

download mechanism 6-28

ext_comm MEX-file

optional arguments to 6-34 6-36

rebuilding 17-1 17-33

host and target systems in 6-2

menu and toolbar items and keyboard
shortcuts 6-6

parameter downloading options 6-22

Signal Viewing Subsystems in 6-25

signals and triggering options 6-15

target communications options 6-13

TCP implementation 6-32

transport layer 17-26

- using with VxWorks 13-17
- external mode API
 - host source files 17-28
 - implementing transport layer 17-31
 - target source files 17-29
- External Target Interface dialog box
 - MEX-file arguments 6-15

F

- fixedpoint.h 2-93
- float.h 2-90
- From File block
 - specifying signal data file for 12-31
- functions
 - rtw_precompile_libs 10-90
 - ssSetChecksumVal 11-21

G

- general code appearance options
 - Maximum identifier length 2-57
- Generate HTML report 2-52
- generated code
 - compiling and linking 2-108
 - include path specification 2-101
 - operations performed by 7-30
 - profiling 2-105
- generated files
 - contents of 2-84
 - dependencies among 2-84
- generated S-functions
 - tunable parameters in 11-12

H

- hand-written code
 - block-based integration with generated code 2-129
 - build support for 10-81
 - integrating with generated code 2-129

- integration with generated code 2-131
- header files
 - dependencies of 2-89
- hook interface
 - for profiling generated code 2-105
- host
 - in external mode 6-2

I

- include paths
 - specifying 2-101
- initial values
 - tunable 5-68
- initialization
 - of signals and discrete states 5-60
- inlined S-functions 10-22
 - with mdlRTW routine 10-27
- Inport block
 - latch options
 - generated code for option 2-43
 - specifying signal data file for 12-33
- integration, code 2-131
 - block-based 2-129
 - build support for 10-81
- interrupt service routine
 - under VxWorks 8-5
- interrupt service routines 16-5
- interrupts
 - handling 16-5
- intOnlyBuild field 10-92

L

- Language option
 - description of 2-52
- Latch input by copying inside signal option
 - generated code for 2-43
- Latch input by delaying outside signal
 - generated code for 2-43

- latches
 - generated code for 2-43
 - legacy code
 - block-based integration with generated code 2-129
 - build support for 10-81
 - integrating with C MEX S-functions 10-24
 - integrating with generated code 2-129
 - integration with generated code 2-131
 - Legacy Code Tool
 - deploying S-functions generated with 10-26
 - generating code with 10-24
 - legacy_code function
 - addressing file dependencies for code generation 10-25
 - generating file for code generation support 10-25
 - LibAddToCommonIncludes function
 - using for S-function build support 10-84
 - LibAddToModelSources function
 - using for S-function build support 10-84
 - libraries
 - controlling suffix applied to names of 2-115
 - model reference
 - controlling the location of 2-114
 - precompiled
 - controlling the location of 2-113
 - S-function
 - precompiling 10-90
 - suffixes for 10-92
 - local block outputs option 9-41
- M**
- make_rtw 2-54
 - makefile
 - customizations 2-112
 - options for 10-92
 - makefile commands
 - USE_MDLREF_LIBPATHS
 - controlling location of model reference libraries with 2-114
 - makeInfo.precompile rtwmakecfg field 10-91
 - makeOpts field 10-92
 - MAT-files
 - file naming convention 2-26
 - logging data to 2-25
 - variable names in 2-26
 - math.h 2-91
 - mdlRTW routine
 - writing inlined S-functions 10-27
 - MEX S-function wrapper
 - definition 10-11
 - Model blocks
 - in Real-Time Workshop 4-26
 - model code
 - execution of 7-34
 - model execution
 - in real time 8-12
 - in Simulink 8-12
 - Simulink versus real-time 8-11
 - Model Header block 14-3
 - Model Parameter Configuration dialog box
 - tunable parameters and 5-2
 - using 5-10
 - model reference
 - code generation 4-26
 - compatibility of top and referenced models 4-30
 - inherited sample time and 4-40
 - parameter interfacing 4-37
 - project directory structure and 4-28
 - signal interfacing 4-36
 - subsystem code reuse and 4-41
 - model reference libraries
 - controlling location of 2-114
 - model registration function 7-34
 - Model Source block 14-3
 - model.h 2-89

- model_types.h 2-93
- models
 - checksums for 11-21
 - code files for
 - porting 2-134
 - relocating 2-134
- models code integration
 - code integration for 2-131
- multiple models
 - combining 17-35
- multiport S-function example 10-22
- multitasking
 - automatic rate transition 8-19
 - building program for 8-10
 - enabling 8-10
 - example model 8-28
 - execution 8-31
 - inserted rate transition block HTML
 - report 8-20
 - model execution 8-6
 - operation 8-13
 - task identifiers in 8-6
 - task priorities 8-6
 - versus single-tasking 8-4

N

- noninlined S-functions 10-9
- nonvirtual subsystem code generation
 - Auto option 4-4
 - Function option 4-8
 - Inline option 4-6
 - Reusable function option 4-12
- nonvirtual subsystems
 - atomic 4-2
 - categories of 4-2
 - conditionally executed 4-2
 - modularity of code generated from 4-14

O

- operating system
 - tasking primitives 7-10
- optimization pane
 - Stateflow and Embedded MATLAB options 9-46

P

- parameters
 - interfacing 5-2
 - storage declarations 5-2
 - TargetPreComplibLocation 10-91
 - tunable 5-2
 - tuning 5-2
- performance
 - of generated code 2-105
- periodic tasks
 - timers for 15-3
- persistent signals
 - initialization of 5-66
- precompiled libraries
 - controlling location of 2-113
- priority
 - of sample rates 8-7
- ProfileGenCode variable 2-106
- ProfilerTLC variable 2-106
- program architecture
 - embedded 7-37
 - initialization functions 7-26
 - main function 7-26
 - model execution 7-27
 - program execution 7-14
 - program termination 7-27
 - program timing 7-13
 - rapid prototyping 7-24
 - real-time 7-24
 - termination functions 7-34
- pseudomultitasking 8-7

R

- rapid prototyping 1-6
 - for control systems 1-11
 - for digital signal processing 1-10
- rapid simulation target 12-2
 - batch simulations (Monte Carlo) 12-25
 - command line options 12-26
 - limitations 12-40
 - output filename specification 12-38
 - parameter structure access 12-30
 - signal data file specification for From File block 12-31
 - signal data file specification for Inport block 12-33
 - Simulink license checkout 12-3
- rate transition block
 - and continuous sample time 8-21
- Rate Transition block 8-14
 - auto-insertion of 8-19
 - HTML report of automatically inserted 8-20
- rate transitions
 - faster to slower 8-21
 - slower to faster 8-24
- real time
 - executing models in 8-12
 - integrating continuous states in 7-28
- real-time malloc target 3-16
 - combining models with 17-35
- Real-time model
 - description 7-31
- real-time model data structure 3-19
- Real-Time Workshop
 - configuring code generation parameters 2-49
 - open architecture of 1-13
 - parameters
 - interfacing 5-2
 - storage 5-2
 - tuning 5-2
 - specifying nonvirtual code generation 4-2
- Real-Time Workshop pane 2-50
- Language option 2-52
- opening 2-50
- overview 2-49 4-2
- target configuration options
 - Browse button 2-51
 - generate code only option 2-55
 - Generate makefile 2-54
 - make command field 2-54
 - system target file field 2-52
 - template makefile field 2-55
 - TLC options 2-53
- referenced models
 - code generation incompatibilities 4-30
 - generating code for 4-26
- registration files
 - multiple
 - for code generation 10-26
- reset value
 - initial value as 5-67
- root models
 - Custom Code blocks in 14-3
- rsim
 - See* rapid simulation target 12-2
- rt_logging.h 2-93
- rt_nonfinite.h 2-93
- rtlibsrc.h 2-94
- rtm macros 3-19
- rtModel 3-19
- rtw_continuous.h 2-94
- rtw_extmode.h 2-94
- rtw_local_blk_outs 5-35
- rtw_matlogging.h 2-94
- rtw_precompile_libs function 10-90
- rtw_solver.h 2-94
- RTWdata structure
 - inlining an S-function 10-28
- rtwlib command 14-2
- rtwmakecfg field
 - TargetPreComplibLocation 10-91
- rtwmakecfg.m

- creating S-functions 10-85
- generating for C MEX S-functions 10-25
- using for S-functions 10-84
- rtwmakecfgDirs field 10-92
- rtwMakecftDirs field 10-92
- rtwtypes.h 2-86 2-95

S

S-Function blocks

- masked
 - configured to call existing external code 10-24

S-function libraries

- precompiling 10-90

S-function target

- applications of 11-3
- automatic S-function generation 11-15
- generating reusable components with 11-6
- intellectual property protection in 11-4
- tunable parameters in 11-12

S-Function target

- checksums and 11-21

S-functions

- API 7-34
- build support for 10-81
- creating rtwmakecfg.m for 10-85
- deploying generated 10-26
- fully inlined with mdlRTW routine 10-27
- generating automatically 11-15
- implicit build support for 10-82
- inlined 10-22
 - generated with Legacy Code Tool 10-24
- models containing 7-34
- modifying TMF for 10-88
- noninlined 7-34 10-9
- setting SFunctionModules parameter for 10-82
- that work with Real-Time Workshop 10-3

- types of 10-5

- using rtwmakecfg.m for 10-84
- using TLC library functions for 10-84
- wrapper 10-11

sample rate transitions 8-14

- faster to slower
 - in real-time 8-22
 - in Simulink 8-21
- slower to faster
 - in real-time 8-25
 - in Simulink 8-24

sample time constraints

- setting for multitasking 8-6

sample time properties

- setting for multitasking 8-6

SFunctionModules parameter

- setting 10-82

signal data

- specifying for From File block 12-31
- specifying for Inport block 12-33

signal initialization

- in generated code 5-66

signal objects

- initializing 5-60
- signal properties 5-28

- setting by using Signal Properties dialog box 5-28

signal storage reuse option 9-40

Signal Viewing Subsystems 6-25

signals

- initializing 5-60

simstruc.h 2-95

simstruc_types.h 2-95

SimStruct data structure

- and global registration function 7-34
- definition of 7-30

Simulink

- and Real-Time Workshop
 - adjusting configuration parameters 2-23
 - block execution order 2-44
 - interactions to consider 2-40
 - sample time propagation 2-42
 - using data objects 5-46
 - using parameter objects 5-47
 - using signal objects 5-55
 - simulation parameters
 - and code generation 2-23
 - Simulink data objects 5-46
 - parameter objects 5-47
 - signal objects 5-55
 - single-tasking 8-10
 - building program for 8-10
 - enabling 8-11
 - example model 8-28
 - execution 8-29
 - operation 8-13
 - ssSetChecksumVal function 11-21
 - states, discrete
 - initializing 5-60
 - <stddef.h> 2-91
 - <stdio.h> 2-91
 - <stdlib.h> 2-92
 - step size
 - of real-time continuous system 7-29
 - StethoScope
 - See* VxWorks 13-16
 - storage classes
 - required for signal initialization 5-61
 - <string.h> 2-92
 - subsystem
 - nonvirtual 4-2
 - subsystems
 - checksums for 11-21
 - custom code blocks in 14-9
 - suffixes
 - precompiled library 10-92
 - <sysran_types.h> 2-95
 - System Derivatives function block 14-5
 - System Disable function block 14-4
 - System Enable function block 14-4
 - System Initialize function block 14-4
 - System Outputs function block 14-4
 - System Start function block 14-4
 - System Target File Browser 2-4
 - system target files
 - selecting programmatically 2-5
 - System Terminate function block 14-4
 - System Update function block 14-4
- ## T
- target
 - rapid simulation
 - See* rapid simulation target 12-2
 - real-time malloc
 - See* real-time malloc target 3-16
 - Target function library option
 - relationship to TGT_FCYN_LIB
 - variable 2-109
 - target-based code integration 2-131
 - TargetLibSuffix parameter
 - controlling suffix applied to library names
 - with 2-115
 - TargetPreCompLibLocation parameter 10-91
 - controlling location of precompiled libraries
 - with 2-113
 - targets
 - available configurations 2-6
 - selecting programmatically 2-5
 - task
 - spawning 16-13
 - task identifier (tid) 8-6
 - template makefile
 - compiler-specific 2-10
 - template makefile options
 - Borland 2-15
 - LCC 2-16

- UNIX 2-12
- Visual C/C++ 2-12
- Watcom 2-14
- template makefile variables
 - TGT_FCN_LIB 2-109
- TGT_FCN_LIB template makefile variable 2-109
- time counters 15-2
 - in triggered subsystems 15-4
- timer, elapsed
 - example 15-10
- timers 15-2
 - allocation of 15-3
 - APIs for accessing 15-5
 - integer 15-3
- timing services 15-2
- TLC API
 - for code generation 15-8
- TLC block file
 - generating for C MEX S-functions 10-25
- TLC hook function interface
 - for profiling generated code 2-105
- TLC library functions
 - using for inlined S-functions 10-84
- TMFs
 - modifying for S-functions 10-88
- Tornado
 - See* VxWorks 13-1
- tunable expressions 5-2 5-14
 - in masked subsystems 5-14
 - operators, restrictions on 5-16
- tunable parameters
 - in signal initial values 5-68

U

- USE_MDLREF_LIBPATHS command
 - controlling location of model reference libraries with 2-114
- user code

- block-based integration with generated code 2-129
- build support for 10-81
- integrating with generated code 2-129
- integration with generated code 2-131
- utassert 2-29

V

Variables

- ProfileGenCode 2-106
- ProfilerTLC 2-106

VxWorks

- application
 - building 13-21
- application architecture 13-4
- application implementation 13-12
- automatic download 13-21
 - specifying 13-16
- automatic downloading
 - configuring for 13-20
- automatic execution 13-21
- base task priority
 - specifying 13-17
- block library 13-3
- code generation options
 - specifying 13-13
- communication tasks 13-8
- configuration 13-10
 - verifying 13-11
- CPU
 - specifying 13-19
- device driver blocks
 - adding 13-12
- execution tasks 13-7
- external mode tasks 13-9
- files
 - downloading 13-22
- generated code format
 - specifying 13-16

- GNU tools for 13-19
- hardware architecture 13-4
- header file paths
 - resolving 13-20
- host processes 13-6
- installation 13-10
- manual download 13-22
- manual execution 13-22
- MAT-file logging
 - specifying 13-15
- module architecture 13-6
- multitasking 13-8
- optStr
 - passing 13-25
- program
 - starting 13-23
- resetting 13-22
- resources for applications 13-2
- rt_main
 - calling 13-25
- Simulink external mode 13-17
- Simulink model
 - designing 13-12
- single-tasking 13-7
- software architecture 13-5
- solver
 - specifying 13-14

- StethoScope monitoring
 - specifying 13-16
- StethoScope tasks 13-8
- target 13-4
 - connecting to 13-10
 - downloading to 13-22
- target type
 - specifying 13-19
- target-specific options
 - setting 13-15
- task priority 13-8
- task stack size
 - specifying 13-17
- tasks created by 13-7
- template makefile 13-19
 - configuring 13-19
- tool locations 13-19
- Tornado environment 13-2
- Tornado target 13-3
 - selecting 13-13
- vxlib library obsolete 13-3
- VxWorks task
 - spawning 16-13

W

- wrapper S-functions 10-11