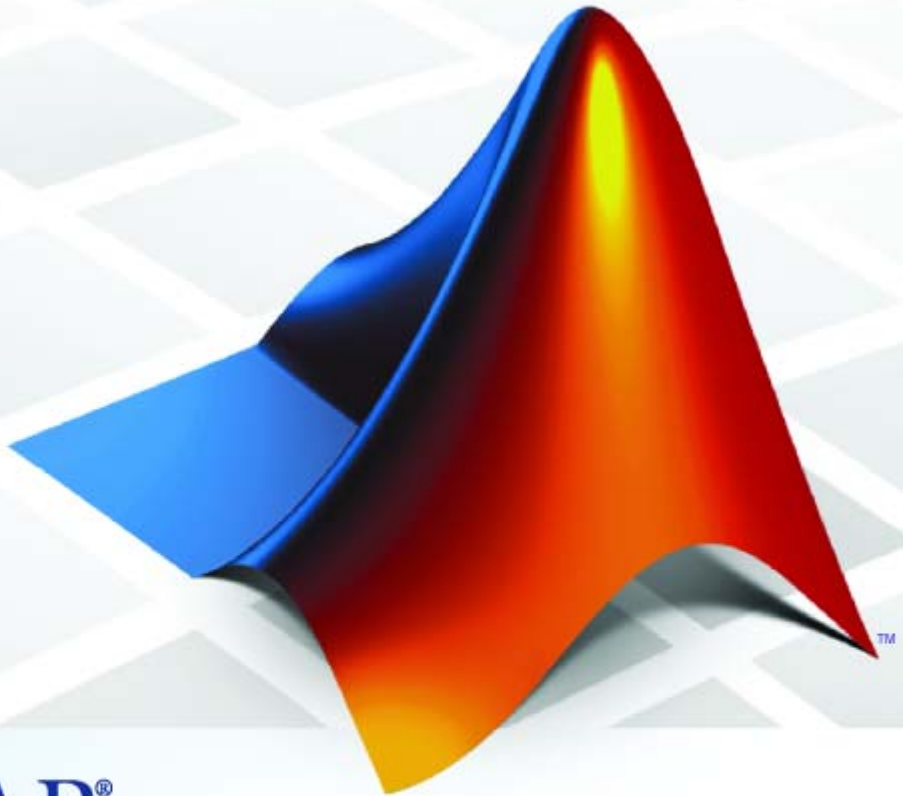


# Embedded IDE Link™ VS 2

## User's Guide



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*Embedded IDE Link™ VS User's Guide*

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# Getting Started

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## Product Overview

Embedded IDE Link™ VS software provides a connection between MATLAB® and the VisualDSP++® IDE to enable you to access the processor from MATLAB. You can, manipulate data on the processor, and manage projects within the IDE, while simultaneously utilizing the MATLAB tools of numerical analysis and simulation. Using Embedded IDE Link VS software, you can perform the following tasks, and others related to Model-Based Design:

- Function calls — Write scripts in MATLAB software to execute any function in the VisualDSP++ IDE
- Automation — Write automated tests in MATLAB software to be executed on your processor, including control and verification operations
- Host-Processor Communication — Communicate with the processor directly from MATLAB software, without going to the IDE
- Verification and Validation
  - Load and execute projects into the VisualDSP++ IDE from the MATLAB command line
  - Build and compile code, and then use vectors of test data and parameters to test the code
  - Build and compile your code, and then download the code to the processor and execute it
- Design models — Design models and algorithms in MATLAB and Simulink® software and run them on the processor
- Generate code— Generate executable code for your processor directly from the models designed in Simulink software, and execute it

Embedded IDE Link VS software connects MATLAB software and Simulink software with Analog Devices™ VisualDSP++® integrated development and debugging environment from Analog Devices™. Embedded IDE Link VS software enables you to use MATLAB and Simulink software to debug and verify embedded code running on all Analog Devices DSPs that VisualDSP++ software supports, such as the Analog Devices® Blackfin®, Analog Devices® SHARC® and Analog Devices® Tiger SHARC® processor families.

Embedded IDE Link VS software includes a project generator component. With the project generator component, you can generate a complete project file for the VisualDSP++ IDE from Simulink software models, using ANSI<sup>®</sup> C code generated with Real-Time Workshop<sup>®</sup> software. Thus, you use the Real-Time Workshop and Real-Time Workshop<sup>®</sup> Embedded Coder<sup>™</sup> software to generate generic ANSI C code projects for VisualDSP++ software from models, that you can then build and run on Blackfin<sup>®</sup>, SHARC<sup>®</sup>, and TigerSHARC<sup>®</sup> processors.

The following list suggests some of the uses for the capabilities of the software:

- Create test benches in MATLAB and Simulink software for testing your hand written or automatically generated code running on ADI DSPs
- Generate code and project files for VisualDSP++ software from Simulink models for rapid prototyping or deployment of a system or application
- Build, debug, and verify embedded code on ADI DSPs
- Perform processor-in-the-loop (PIL) testing of embedded code

# The Structure and Components of Embedded IDE Link VS Software

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“Project Generator” on page 1-5
“Verification” on page 1-5

Embedded IDE Link VS software comprises components—the Automation Interface component, the Project Generation component, and the Verification component. The Automation Interface component enables communication between MATLAB software and Embedded IDE Link VS software. The Project Generation component leverages Simulink software and lets you build models, simulate them, and generate code from the models directly to the processor.

The Verification component offers capabilities that help you use Model-Based Design to validate and verify your projects. With the Verification component, you can simulate algorithms and processes in Simulink models and concurrently on your processor. Comparing the results helps verify the fidelity of your model or algorithm code.

## Automation Interface

The Automation Interface component allows you to use Embedded IDE Link VS functions and methods to communicate with the VisualDSP++ IDE to perform the following tasks:

- Automate project management
- Debug programs
- Manipulate the data in the processor internal and external memory, and in the registers
- Communicate between the host and processor applications

The functionality provided by the automation interface component can be divided into the following categories:

- Debug Component — Methods and functions for project automation, debugging, and data manipulation.
- Host Processor Communication Component — Methods that support various standard communication protocols, such as BTC, TCP/IP, and UDP.

## **Project Generator**

The Project Generator component comprises methods that utilize the VisualDSP++ API to create projects in VisualDSP++ software and generate code with Real-Time Workshop and Real-Time Workshop Embedded Coder software. With the interface, you can do the following:

- Automatic project-based build process — Automatically create and build projects for code generated by Real-Time Workshop or Real-Time Workshop Embedded Coder software.
- Custom code generation — Use Embedded IDE Link VS software with any Real-Time Workshop System Target File (STF) to generate processor-specific and optimized code.
- Automatic downloading and debugging — Debug generated code in the VisualDSP++ debugger, using either the instruction set simulator or real hardware.
- Create and build projects for VisualDSP++ software from Simulink models — Project Generator uses Real-Time Workshop or Real-Time Workshop Embedded Coder software to build projects that work with Analog Devices processors.
- Generate custom code using the Configuration Parameters in your model with the system target files `vdspink_ert.tlc` and `vdspink_grt.tlc`.

## **Verification**

Verifying your processes and algorithms is an essential part of developing applications. The components of Embedded IDE Link VS software combine to provide the following verification tools for you to apply as you develop your code:

## **Processor-in-the-Loop Cosimulation**

Use cosimulation techniques to verify generated code running in an instruction set simulator or real hardware environment.

### **Task Execution and Stack Usage Profiling**

Gather execution profiling measurements with VisualDSP++ instruction set simulator to establish the timing requirements of your algorithm. Also, verify the stack usage is appropriate and as expected.

# Automation Interface

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## Getting Started with Automation Interface

In this section...
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### Introducing the Embedded IDE Link VS Tutorial

Embedded IDE Link VS software provides a connection between MATLAB software and a processor in VisualDSP++ software. You can use objects as a mechanism to control and manipulate a signal processing application using the computational power of MATLAB software. This approach can help you while you debug and develop your application. Another possible use for automation is creating MATLAB scripts that verify and test algorithms that run in their final implementation on your production processor.

---

**Note** Before using the functions available with the objects, you must select a session in the VisualDSP++ IDE. The object you create is specific to a designated session in VisualDSP++ IDE.

---

To get you started using objects for VisualDSP++ software, Embedded IDE Link VS software includes an example script `vdsp tutorial.m`. As you work



through this tutorial, you perform the following tasks that step you through creating and using objects for VisualDSP++ IDE.

- 1 Select your session.
- 2 Create and query objects to VisualDSP++ IDE.
- 3 Use MATLAB software to load files into VisualDSP++ software IDE.
- 4 Work with your VisualDSP++ IDE project from MATLAB software.
- 5 Close the connections you opened to VisualDSP++ IDE.

You use these tasks in any development work you do with signal processing applications. Thus, the tutorial provided here gives you a working process and best practice for using Embedded IDE Link VS software and your signal processing programs to develop programs for a range of Analog Devices processors.

The tutorial covers some methods and functions for Embedded IDE Link VS software. The functions listed first do not require an `adivdsp` object. The functions listed after that require an existing `adivdsp` object before you can use the function syntax.

### Functions for Working with VisualDSP++ Software

The following table shows functions that do not require an object.

Function	Description
<code>listsessions</code>	Return information about the boards that VisualDSP++ IDE recognizes as installed on your PC.
<code>adivdsp</code>	Construct an object that refers to a VisualDSP++ IDE session. When you construct the object you specify the session by processor.

## Methods for Working with adivdsp Objects in VisualDSP++ Software

The following table presents some of the methods that require an adivdsp object.

<b>Methods</b>	<b>Description</b>
add	Add a file to a project
address	Return the address and page for an entry in the symbol table in VisualDSP++ IDE
build	Build the project in VisualDSP++ software
cd	Change the working directory
display	Display the properties of an object that references a VisualDSP++ software session
halt	Terminate execution of a process running on the processor
info	Return information about the object or session
isrunning	Test whether the processor is executing a process
load	Load a built project to the processor
open	Open a file in the project
read	Retrieve data from memory on the processor
reset	Restore the program counter (PC) to the entry point for the current program
run	Execute the program loaded on the processor
save	Save files or projects
visible	Set whether VisualDSP++ IDE window is visible on the desktop while VisualDSP++ IDE is running
write	Write data to memory on the processor

## Running VisualDSP++ Software on Your Desktop – Visibility

When you create an `adivdsp` object in the tutorial in the next section, Embedded IDE Link VS starts VisualDSP++ software in the background.

If VisualDSP++ software is running in the background, it does not appear on your desktop, in your task bar, or on the **Applications** page in the Task Manager. It does appear as a process, `idde.exe`, on the **Processes** tab in Task Manager.

You can make the VisualDSP++ IDE visible with the function `visible`. The function `isvisible` returns the status of the IDE—is it visible on your desktop. To close the IDE when it is not visible and MATLAB is not running, use the **Processes** tab in Windows® Task Manager and look for `idde.exe`.

If an object that refers to VisualDSP++ software exists when you close VisualDSP++ software, the application does not close. Windows software moves it to the background (it becomes invisible). Only after you clear all objects that access VisualDSP++ IDE, or close MATLAB, does closing VisualDSP++ unload the application. You can see if VisualDSP++ IDE is running in the background by checking in the Windows Task Manager. When VisualDSP++ IDE is running, the entry `idde.exe` appears in the **Image Name** list on the **Processes** tab.

## Running the Interactive Tutorial

You have the option of running this tutorial from the MATLAB command line or entering the functions as described in the following tutorial sections.

To run the tutorial in MATLAB, click `run vdspautointtutorial`. This command launches the tutorial in an interactive mode where the tutorial program provides prompts and text descriptions to which you respond to move to the next section. The interactive tutorial covers the same information provided by the following tutorial sections. You can view the tutorial M-file used here by clicking `vdspautointtutorial.m`.

---

**Note** To run the interactive tutorial, you must have at least one session configured in VisualDSP++ software. If you do not yet have a session, use the Analog Devices VisualDSP++ Configurator to create a session to use for this tutorial.

---

### Selecting Your Session and Processor

Embedded IDE Link VS IDE requires that you have at least one session available for VisualDSP++ software. To help you select the session to use for this tutorial, and for any development work, Embedded IDE Link VS software provides a command line tool, called `listsessions`, which prints a list of the available sessions. So that you can use this function in a script, `listsessions` can return a MATLAB structure that you use when you want your script to select a session in the IDE without your help.

---

**Note** The session you select is used throughout the tutorial.

---

- 1 To see a list of the sessions that you can use, enter the following command at the MATLAB prompt:

```
session_list = listsessions
```

MATLAB returns a list that shows all the sessions that Embedded IDE Link VS IDE recognizes as available in your installation.

```
session_list =  
  
    'ADSP-21060 ADSP-2106x Simulator'  
    'ADSP-21362 ADSP-2136x Simulator'
```

- 2 `listsessions` has a verbose mode that provides further details about the sessions in a cell array. The array contains structures that describe each session—the target type, the platform, and the processor.

```
sessionsinfo = listsessions('verbose');  
  
echo off
```

```
sessionname: 'ADSP-21362 ADSP-2136x Simulator'  
targettype: 'ADSP-2136x Family Simulator'  
platformname: 'ADSP-2136x Simulator'  
processors: 'ADSP-21362'
```

- 3 Use `adivdsp` to create an object that accesses a session in VisualDSP++ IDE.

```
vd = adivdsp('sessionname','ADSP-21362 ADSP-2136x Simulator','procnum',0)
```

`Sessionname` and `procnum` are property names that specify the property to set. `ADSP-21362 ADSP-2136x Simulator` is the session to access, and `0` is the number of the processor to refer to in the session.

When you use `adivdsp`, you create an object, in this case `vd`, that refers to the session you specify in `sessionname`.

## Querying Objects for VisualDSP++ IDE

In this tutorial section you create the connection between MATLAB and VisualDSP++ IDE. This connection, or object, is a MATLAB object, which for this session you save as variable `vd`. You use function `adivdsp` to create objects. When you create objects, `adivdsp` input arguments let you define other object properties, such as the global time-out. Refer to the `adivdsp` reference information for more about the input arguments.

Use the generated object `vd` to direct actions to your session processor. In the following tasks, `vd` appears in all function syntax that interact with IDE session and the processor: The object `vd` identifies and refers to a specific session. You need to include the object in any method syntax you use to access and manipulate a project or files in a session in VisualDSP++ IDE.

- 1 Create an object that refers to your selected session and processor. Enter the following command at the prompt.

```
vd = adivdsp('sessionname','ADSP-21362 ADSP-2136x Simulator','procnum',0)
```

If you watch closely, and your machine is not too fast, you see VisualDSP++ software appear briefly when you call `adivdsp`. If VisualDSP++ was not running before you created the new object, VisualDSP++ software starts and runs in the background.

Usually, you need to interact with VisualDSP++ while you develop your application. The function `visible`, controls the state of VisualDSP++ software on your desktop. `visible` accepts Boolean inputs that make VisualDSP++ software either visible on your desktop (input to `visible`  $\geq 1$ ) or invisible on your desktop (input to `visible` = 0). For this tutorial, you need to interact with the development environment, so use `visible` to set the IDE visibility to 1.

- 2** To make VisualDSP++ IDE show on your desktop, enter the following command at the prompt:

```
visible(vd,1)
```

- 3** Next, enter `display(vd)` at the prompt to see the status information.

```
ADIVDSP Object:
  Session name      : ADSP-21362 ADSP-2136x Simulator
  Processor name    : ADSP-21362
  Processor type    : ADSP-21362
  Processor number  : 0
  Default timeout   : 10.00 secs
```

Embedded IDE Link VS software provides three methods to read the status of a processor:

- `info` — Return a structure of testable session conditions.
- `display` — Print information about the session and processor.
- `isrunning` — Return the state (running or halted) of the processor.

- 4** Type `procinfo = info(vd)`.

The `vd` link status information provides data about the hardware, as follows:

```
procinfo =

  procname: 'ADSP-21362'
  proctype: 'ADSP-21362'
  revision: ''
```

- 5** Verify that the processor is running by entering

```
runstatus = isrunning(vd)
```

MATLAB responds, indicating that the processor is stopped, as follows:

```
runstatus =  
  
0
```

## Loading Files into VisualDSP++ IDE

You have established the connection to a processor and board. Using three methods you learned about the hardware, whether it was running, its type, and whether VisualDSP++ IDE was visible. Next, give the processor something to do.

In this part of the tutorial, you load the executable code for the CPU in the IDE. Embedded IDE Link VS software includes a tutorial project file for VisualDSP++ IDE. Through the next commands in the tutorial, you locate the tutorial project file and load it into VisualDSP++ IDE. The open method directs VisualDSP++ software to load a project file or workspace file.

---

**Note** To continue the tutorial, you must identify or create a directory to which you have write access. Embedded IDE Link VS software cannot create a directory for you. If you do not have a writable directory, create one in Windows software before you proceed with the rest of this tutorial.

---

VisualDSP++ software has its own workspace and workspace files that are quite different from MATLAB workspace files and the MATLAB workspace. Remember to monitor both workspaces. The next steps change the working directory to your new writable directory.

- 1 Use `cd` to switch to the writable directory

```
prj_dir = cd('C:\vdsp_demo')
```

where the name and path to the writable directory is a string, such as `C:\vdsp_demo` as used in the example. Replace `C:\vdsp_demo` with the full path to your directory.

- 2 Change your working directory to the new directory by entering the following command:

```
cd(vd,prj_dir)
```

- 3 Next, use the following command to create a new VisualDSP++ software project named `dot_product.c.dpj` in the new directory:

```
new(vd, 'debug_demo.dpj')
```

Look in the IDE to verify that your new project exists. Next you need to add source files to your project.

- 4 Add the provided source file—`scalarprod.c` to the project `debug_demo.dpj` using the following command:

```
add(vd, 'matlabroot\toolbox\vdsp\link\vdspdemos\src\scalarprod.c')
```

The variable *matlabroot* indicates the root directory of your MATLAB installation. Replace *matlabroot* with the path to MATLAB on your machine. For more information about the MATLAB root directory, refer to *matlabroot* in the MATLAB documentation.

- 5 Open the file in the IDE from MATLAB by issuing the following command to open the file:

```
open(vd, 'matlabroot\toolbox\vdsp\link\vdspdemos\src\scalarprod.c')
```

Switch to the IDE to verify that the files are in your project and open.

- 6 Save your project.

```
save(vd, 'debug_demo.dpj', 'project')
```

Your IDE project is saved with the name `debug_demo.dpj` in your writable directory. The input string 'project' specifies that you are saving a project file.



## Running the Project

After you create `dot_project_c.dpj` in the IDE, you can use Embedded IDE Link VS functions to create executable code from the project and load the code to the processor.

The next steps in this tutorial build the executable and download and run it on your processor.

- 1 Use the following build command to build an executable module from the project `dot_product_c.dpj`.

```
build(vd,30) % The optional input argument 30 sets the time out period to 30 seconds.
```

At the end of the build process, Embedded IDE Link VS software returns a value of 1 to indicate that the build succeeded. If the build process returns a 0, the build failed.

```
ans =  
  
1
```

- 2 To load the new executable to the processor, use `load` with the project file name and the object name. The name of the executable is `debug_demo.dxe`, and it is stored with the project in your writable directory, in a subdirectory named `debug`.

```
load(vd, 'c:\vdsp_demo\debug\debug_demo.dxe', 30);
```

Embedded IDE Link VS software provides methods to control processor execution—`run`, `halt`, and `reset`. To demonstrate these methods, use `run` to start the program you loaded on the processor, and then use `halt` to stop the processor.

Try the following methods at the command prompt.

```
run(vd)      % Start the program running on the processor.  
halt(vd)    % Halt the processor.  
reset(vd)   % Reset the program counter to start of program.
```

## Working with Global Variables and Memory

After you load your program on the processor, you can access memory locations and variables. You can then read variables either from the program symbol table or directly from addresses in memory. Three methods—`address`, `read`, and `write`, let you get, read, and write to and from your project and processor.

Start by getting the address of the global variable `v1` from the `debug_demo` project symbol table.

- 1 Enter the following command to retrieve the address for `v1`.

```
address_v1 = address(vd, 'v1')  
  
address_v1 =  
  
753666      1
```

- 2 Convert the address from decimal format to hexadecimal.

```
dec2hex(address_v1(1))  
  
ans =  
  
B8002
```

The address of global data array `v1` is `0xB8002`, which is stored in type `1` memory on the processor

- 3 With the address of `v1` saved as `address_v1`, use `read` to return the data from that location. To specify the data type and the number of values to read, add the `datatype` (`'int32'`) and count (`32`) input arguments.

```
value_v1 = read(vd, address_v1, 'int32', 32) % Interpret the data as 32-bit integers.  
  
value_v1 =  
  
Columns 1 through 10  
  
-37    -133     31    -104     32     66    -123     19     140    -28  
  
Columns 11 through 20
```

```

    16    80    -2    83   -243   148    56   163    46    45

Columns 21 through 30

   -217   -11  -164    49    -3    99    21   -61   -26   101

Columns 31 through 32

   -101   -151

```

- 4** Repeat the read process for another global variable in the project—`v2`. Nest the `address` method inside the `read` method to reduce typing.

```

value_v2 = read(vd,address(vd,'v2'),'int32',32) % Read and address methods in one call.

value_v2 =

Columns 1 through 10

   -50     5   -17    28     5    31   -23  -156    68    -5

Columns 11 through 20

  -220     5   -14    57   214   183   213    40   175   144

Columns 21 through 30

   -12   -77   -18    77   130   -39   132   107    52   -59

Columns 31 through 32

   127   -117

```

## Working with Local Variables and Memory

If you examine the source files for `debug_demo` in the IDE, you can verify the values for `v1` and `v2` in the source file `scalarprod.c`. You can also use the `address` method to get the addresses of local variables on the stack, after the variable is in scope.

To get the variables in scope (on the stack), you run the program. Adding a breakpoint to the program allows you to read the stack contents when the program stops at the breakpoint. Without the breakpoint, the program runs to completion, and you cannot read the contents of the stack because it no longer exists.

Begin the process by adding a breakpoint to the project file `scalarprod.c`:

- 1** Insert a breakpoint on line 100 of program `scalarprod.c` with the following command:

```
insert(vd, 'scalarprod.c', 100)
```

- 2** Run the program to add the variable to the stack, and move the program counter to the breakpoint. Add the optional input argument `timeout` sets the time out value to 30s instead of the default 20s value:

```
run(vd, 'runtohalt', 30)
```

The program stops at the breakpoint on line 100.

- 3** Read the address of the local variable `result`, and convert it to its hexadecimal equivalent value.

```
address_result = address(vd, 'result', 'local') % address_result is a 'local' variable.  
  
address_result =  
  
    933884         1  
  
dec2hex(address_result(1))  
  
ans =  
  
E3FFC
```

`address` returns 933884 as the location of `result` in memory, in type 1 memory on the processor, stored in the MATLAB variable `address_result`.

- 4** Use the variable `address_result` to get the value stored at that address by issuing the following `read` command:

```
actual_value_result = read(vd, address_result, 'int32')  
  
actual_value_result =  
  
18875
```

Verify in the IDE Output Window that 18875 is the correct value for the dot product.

- 5 Use the following command to remove the breakpoint set on line 100.

```
remove(vd, 'scalarprod.c', 100)
```

MATLAB includes a dot product function to use to verify the value in `actual_value_result`. Called `dot`, the function calculates the dot product of two input vectors. In this case, the inputs are vectors `value_v1` and `value_v2`.

Comparing the two results—`expected_value_result` in MATLAB with `actual_value_result` from the processor implementation validates your simulation and implementation. With Automation Interface methods, you can create MATLAB M-file scripts to test and verify algorithms in their implementation on a processor.

- 1 Calculate the expected result by performing the dot function with two input vectors.

```
expected_value_result = dot(value_v1, value_v2)  
  
expected_value_result =  
  
18875
```

- 2 Test to see if the actual and expected results match.

```
isequal(expected_value_result, actual_value_result)  
  
ans =  
  
1
```

- 3 After verifying the result and removing the breakpoint, run the program to completion, and then halt and reset the processor.

```
run(vd)
halt(vd)
reset(vd)
```

### Closing Files and Projects

You can close files in your projects from the MATLAB command line. The method `close` works at the command line to close programs or projects in the IDE through the `adivdsp` object and input keywords that describe the kind of file to close.

To finish this tutorial, close the open documents or files in the IDE, and then close the project `debug_demo.dpj`.

- 1 Close all of the open files and documents in the IDE. All of the open files are text files, so use the `text` input argument.

```
close(vd, 'all', 'text')
```

- 2 Now, close the project.

```
close(vd, 'debug_demo.dpj', 'project')
```

### Closing the Connections or Cleaning Up VisualDSP++ Software

Objects that you create in Embedded IDE Link VS software have connections to VisualDSP++ software. Until you delete these handles, the VisualDSP++ process (`idde.exe` in the Windows Task Manager) remains in memory. Closing MATLAB removes these objects automatically, but there may be times when it helps to delete the handles manually, without quitting MATLAB.

---

**Note** When you clear the last `adivdsp` object, Embedded IDE Link VS software closes VisualDSP++ software. When it closes the IDE, the link software does not save current projects or files in the IDE, and it does not prompt you to save them. A best practice is to save all of your projects and files before you clear `adivdsp` objects from your MATLAB workspace.

---

- 1 Use the following command to make the IDE invisible if it is visible on your desktop.

```
visible(vd.0)
```

- 2 To delete your connection to VisualDSP++ IDE, use `clear vd`.

## **Tutorial Summary**

During the tutorial you performed the following tasks:

- 1 Selected your session.
- 2 Created and queried objects that refer to a session in Embedded IDE Link VS to get information about the session and processor.
- 3 Used MATLAB to load files into VisualDSP++ IDE, and used methods in MATLAB to run that file.
- 4 Accessed variables in the program symbol table and on the processor.
- 5 Used the Automation Interface methods to compare the results of a simulation in MATLAB with the same algorithm running on a processor.
- 6 Closed the files, projects, and connections you opened to VisualDSP++ IDE.

## Constructing Objects

When you create a connection to a session in VisualDSP++ software using the `adivdsp` function, you create an object. The object implementation relies on MATLAB object-oriented programming capabilities similar to the objects you find in MATLAB or Filter Design Toolbox.

The discussions in this section apply to the objects in Embedded IDE Link VS software. Because `adivdsp` objects use the MATLAB programming techniques, the information about working with the objects, such as how you get or set properties, or use methods, apply to the objects you create in Embedded IDE Link VS software.

Like other MATLAB structures, objects in Embedded IDE Link VS software have predefined fields referred to as *object properties*.

You specify object property values by one of the following methods:

- Specifying the property values when you create the object
- Creating an object with default property values, and changing some or all of these property values later

For examples of setting link properties, refer to “Setting Property Values with `set`”.

### Example – Constructor for `adivdsp` Objects

The easiest way to create an object is to use the function `adivdsp` to create an object with the default properties. Create an object named `vd` referring to a session in VisualDSP++ software by entering the following syntax:

```
vd = adivdsp
```

MATLAB responds with a list of the properties of the object `vd` you created along with the associated default property values.

```
ADIVDSP Object:  
  Session name      : ADSP-21362 ADSP-2136x Simulator  
  Processor name    : ADSP-21362  
  Processor type    : ADSP-21362
```



Processor number : 0  
Default timeout : 10.00 secs

The object properties are described in the `adivdsp` documentation.

---

**Note** These properties are set to default values when you construct links.

---

## Properties and Property Values

In this section...
“Setting and Retrieving Property Values” on page 2-20
“Setting Property Values Directly at Construction” on page 2-21
“Setting Property Values with set” on page 2-21
“Retrieving Properties with get” on page 2-22
“Direct Property Referencing to Set and Get Values” on page 2-22
“Overloaded Functions for adivdsp Objects” on page 2-23

Objects in this software have properties associated with them. Each property is assigned a value. You can set the values of most properties, either when you create the link or by changing the property value later. However, some properties have read-only values. Also, a few property values, such as the board number and the processor to which the link attaches, become read-only after you create the object. You cannot change those after you create your link.

### Setting and Retrieving Property Values

You can set adivdsp object property values by either of the following methods:

- Directly when you create the link — see “Setting Property Values Directly at Construction”
- By using the set function with an existing link — see “Setting Property Values with set”

Retrieve Embedded IDE Link VS software object property values with the get function.

Direct property referencing lets you either set or retrieve property values for adivdsp objects.

## Setting Property Values Directly at Construction

To set property values directly when you construct an object, include the following entries in the input argument list for the constructor method `adivdsp`:

- A string for the property name to set followed by a comma. Enclose the string in single quotation marks as you do any string in MATLAB.
- The associated property value. Sometimes this value is also a string.

Include as many property names in the argument list for the object construction command as there are properties to set directly.

### Example — Setting Object Property Values at Construction

Suppose that you want to create a link to a session in VisualDSP++ software and set the following object properties:

- Refer to the specified session.
- Connect to the first processor.
- Set the global time-out to 5 s. The default is 10 s.

Set these properties by entering

```
vd = adivdsp('sessionname','ADSP-21060 ADSP-2106x Simulator','procnum',0,'timeout',5);
```

The `sessionname`, `procnum`, and `timeout` properties are described in Link Properties, as are the other properties for links.

## Setting Property Values with `set`

After you construct an object, the `set` function lets you modify its property values.

Using the `set` function, you can change the value of any writable property of an object.

**Example — Setting Object Property Values Using set**

To set the time-out specification for the link `vd` from the previous section, enter the following syntax:

```
set(vd,'timeout',8);  
  
get(vd,'timeout');  
ans =  
  
      8
```

The display reflects the changes in the property values.

**Retrieving Properties with get**

You can use the `get` command to retrieve the value of an object property.

**Example — Retrieving Object Property Values Using get**

To retrieve the value of the `sessionname` property for `vd2`, and assign it to a variable, enter the following syntax:

```
session = get(vd2,'sessionname')  
  
session =  
  
ADSP-21060 ADSP-2106x Simulator
```

**Direct Property Referencing to Set and Get Values**

You can directly set or get property values using MATLAB structure-like referencing. Do this by using a period to access an object property by name, as shown in the following example.

**Example — Direct Property Referencing in Links**

To reference an object property value directly, perform the following steps:

- 1 Create a link with default values.
- 2 Change its time-out and number of open channels.

```
vd = adivdsp;  
vd.time = 6;
```

## Overloaded Functions for adivdsp Objects

Several methods and functions in Embedded IDE Link VS software have the same name as functions in other MathWorks™ products. These functions behave similarly to their original counterparts, but you apply them to an object. This concept of having functions with the same name operate on different types of objects (or on data) is called *overloading* of functions.

For example, the `set` command is overloaded for objects. After you specify your object by assigning values to its properties, you can apply the methods in this toolbox (such as `address` for reading an address in memory) directly to the variable name you assign to your object. You do not have to specify your object parameters again.

For a complete list of the methods that act on `adivdsp` objects, refer to the Chapter 6, “Functions — Alphabetical List” in the function reference pages.

## adivdsp Object Properties

### In this section...

“Quick Reference to adivdsp Properties” on page 2-24

“Details About adivdsp Object Properties” on page 2-25

Embedded IDE Link VS software provides links to your processor hardware so you can communicate with processors for which you are developing systems and algorithms. Because Embedded IDE Link VS software uses objects to create the links, the parameters you set are called properties and you treat them as properties when you set them, retrieve them, or modify them.

This section details the properties for the objects for VisualDSP++ software. First the section provides tables of the properties, for quick reference. Following the tables, the section offers in-depth descriptions of each property, its name and use, and whether you can set and get the property value associated with the property. Descriptions include a few examples of the property in use.

MATLAB users may find much of this handling of objects familiar. Objects in Embedded IDE Link VS software behave like objects in MATLAB and the other object-oriented toolbox products. C++ programmers may already understand the concepts described in this section.

### Quick Reference to adivdsp Properties

The following table lists the properties for the links in Embedded IDE Link VS software. The second column indicates the object to which the property belongs. Knowing which property belongs to each object tells you how to access the property.

Property Name	User Settable?	Description
sessionname	At construction only	Reports the name of the session in VisualDSP++ IDE that the object references.

Property Name	User Settable?	Description
procnum	At construction only	Stores the number of the processor in the session. If you have more than one processor, this number identifies the specific processor.
timeout	Yes/default	Contains the global time-out setting for the link.

Some properties are read only. Thus, you cannot set the property value. Other properties you can change at any time. If the entry in the User Settable column is “At construction only”, you can set the property value only when you create the object. Thereafter it is read only.

## Details About adivdsp Object Properties

To use the objects for VisualDSP++ interface, set values for the following:

- `sessionname` — Specify the session with which the object interacts.
- `procnum` — Specify the processor in the session. If the board has multiple processors, `procnum` identifies the processor to use.
- `timeout` — Specify the global time-out value. (Optional. Default is 10 s.)

Details of the properties associated with `adivdsp` objects appear in the following sections, listed in alphabetical order by property name.

### **procnum**

Property `procnum` identifies the processor referenced by an object for Embedded IDE Link VS IDE. Use `procnum` to specify the processor you are working with in the session specified by `sessionname`. The VisualDSP++ Configurator assigns a number to each processor installed in each session. To determine the value of `procnum` for a processor, use `listsessions` or the Configurator.

To identify a processor, you need the `sessionname` and `procnum` values. For sessions with one processor, `procnum` equals 0. VisualDSP++ IDE numbers the processors on multiprocessor boards sequentially from 0 to the total

number of processors. For example, on a board with four processors, the processors are numbered 0, 1, 2, and 3.

### **sessionname**

Property `sessionname` identifies the session referenced by a Embedded IDE Link VS software. When you create an object, you use `sessionname` to specify the session you are intending to interact with. To get the value for `sessionname`, use `listsessions` or the Analog Devices VisualDSP++ Configurator. The Configurator utility assigns the name for each session available on your system.

### **timeout**

Property `timeout` specifies how long VisualDSP++ software waits for any process to finish. You set the global time-out when you create an object for a session in VisualDSP++ IDE. The default global time-out value 10 s. The following example shows the `timeout` value for object `vd2`.

```
display(vd2)
```

```
ADIVDSP Object:
```

```
Session name      : ADSP-21060 ADSP-2106x Simulator  
Processor name    : ADSP-21060  
Processor type    : ADSP-21060  
Processor number  : 0  
Default timeout   : 10.00 secs
```



# Project Generator

---

- “Introducing Project Generator” on page 3-2
- “Using the Embedded IDE Link VS Blockset” on page 3-3
- “Schedulers and Timing” on page 3-10
- “Project Generator Tutorial” on page 3-17
- “Setting Real-Time Workshop Options for Analog Devices Processors” on page 3-24
- “Setting Real-Time Workshop Category Options” on page 3-27
- “Model Reference and Embedded IDE Link VS Software” on page 3-43

## Introducing Project Generator

Project generator provides the following features for developing projects and generating code:

- Automated project building for VisualDSP++ software that lets you create VisualDSP++ software projects from code generated by Real-Time Workshop and Real-Time Workshop Embedded Coder software. Project generator populates projects in the VisualDSP++ software development environment.
- Blocks in the library `vdspinklib` for controlling the scheduling and timing in generated code.
- Highly configurable code generation using model configuration parameters and target preferences block options.
- Capability to use Embedded IDE Link VS software with one of two system target files to generate code specific to your processor.
- Highly configurable project build process.
- Automatic downloading and running of your generated projects on your processor.

To configure your Simulink software models to use the Project Generator component, do one or both of the following tasks:

- Add a Target Preferences block from the Embedded IDE Link VS blockset (`vdspinklib`) to the model.
- To use the asynchronous scheduler capability in Embedded IDE Link VS software, add one or more hardware interrupt blocks or idle task block from the Embedded IDE Link VS blockset (`vdspinklib`).

The following sections describe the blockset and the blocks in it, the scheduler, and the Project Generator component.

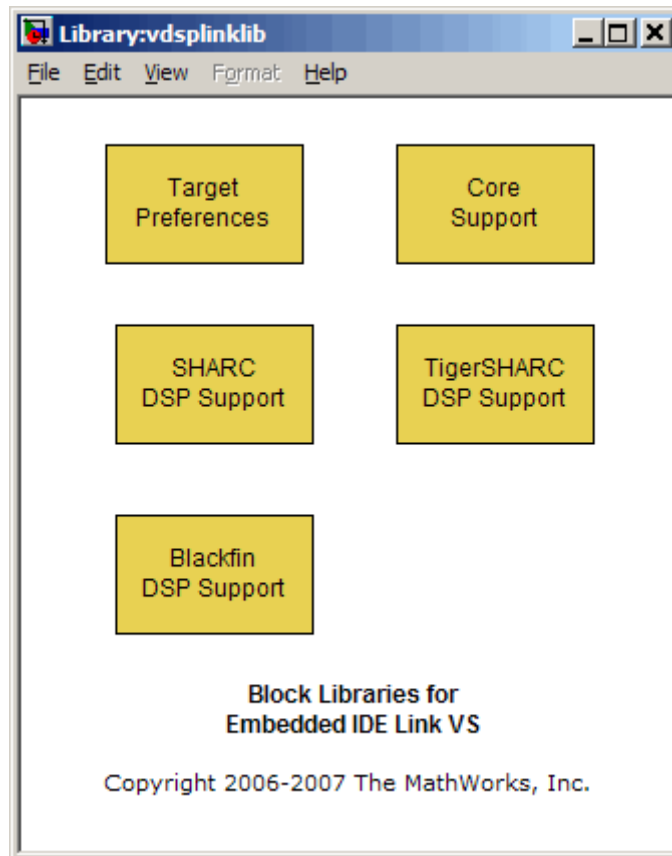
## Using the Embedded IDE Link VS Blockset

Embedded IDE Link VS block library `vdspinklib` comprises block libraries that contain blocks designed for generating projects for specific processors. The following table describes these libraries.

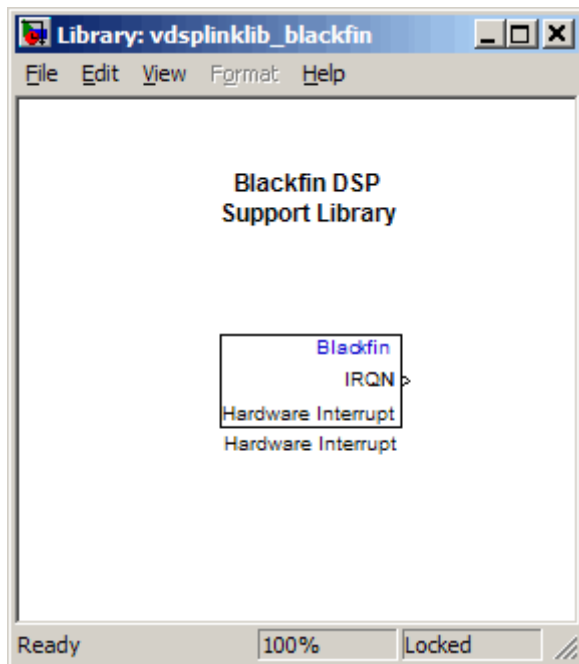
<b>Library</b>	<b>Description</b>
Blackfin DSP Support ( <code>vdspinklib_blackfin</code> )	Blocks for managing memory and task scheduling on Blackfin processors
Core Support ( <code>vdspinklib_coresupport</code> )	Blocks for task scheduling and manipulating memory on ADI processors
SHARC DSP Support ( <code>vdspinklib_sharc</code> )	Blocks for task scheduling on SHARC processors
Target Preferences ( <code>vdspinklib_tgtpref</code> )	Block that configures models for specific ADI processors
TigerSHARC DSP Support ( <code>vdspinklib_tigersharc</code> )	Blocks for task scheduling on Tiger SHARC® processors

Blocks for the processor families are almost identical. Each block has a reference page that describes the options for the block. Use the Help browser to get more information about a block shown in any of the following figures.

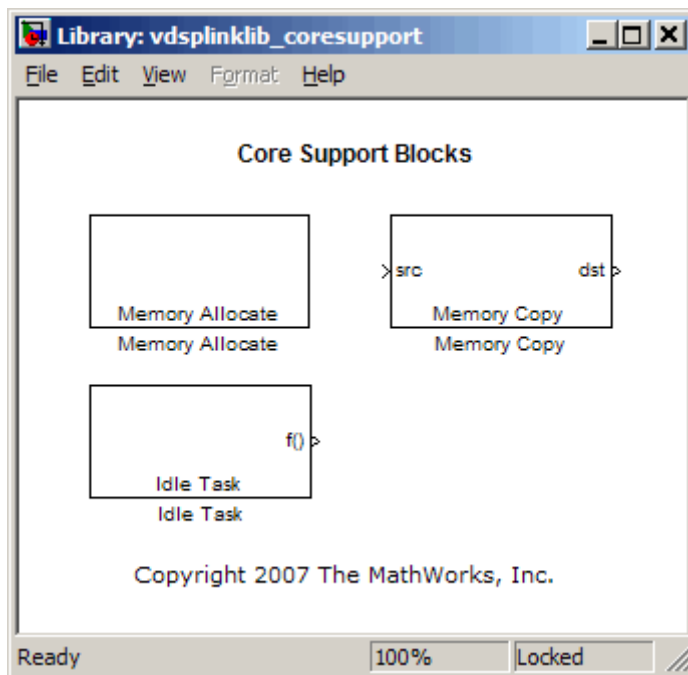
The first figure shows the main library of libraries in the software.



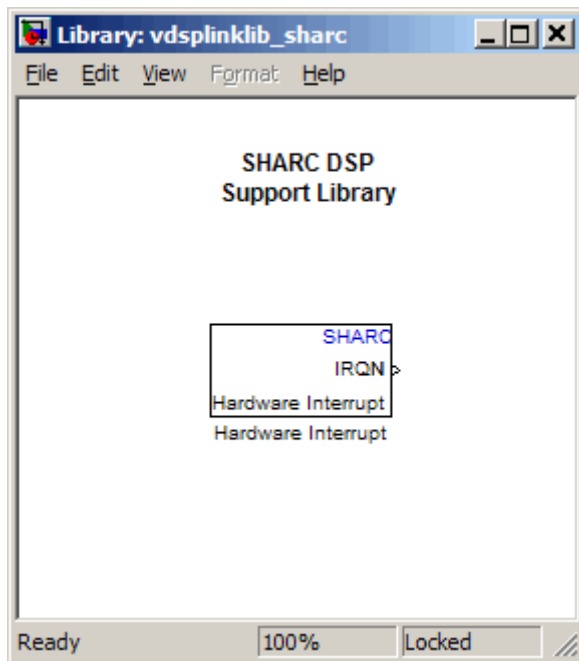
The next figure shows the Blackfin DSP Support library.



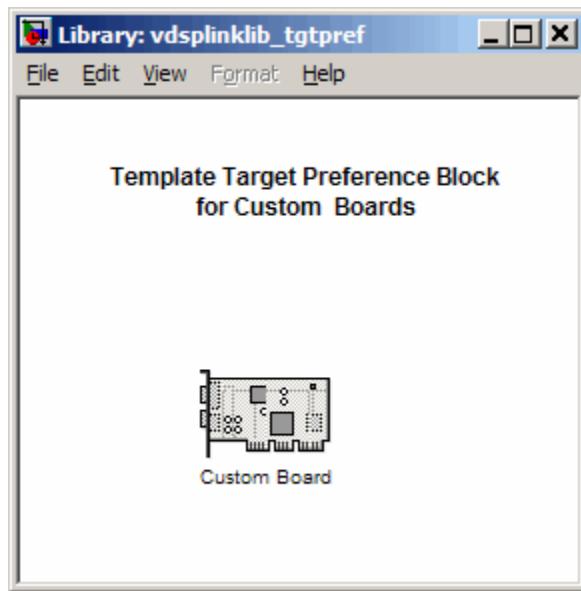
The Core Support library contains the blocks shown in the next figure.



The SHARC DSP Support library contains the block in the next figure.



The target preferences library for all Analog Devices processors appears in the next figure.



The TigerSHARC DSP Support library appear in the next figure.





## Schedulers and Timing

In this section...
“Timer-Based Versus Asynchronous Interrupt Processing” on page 3-10
“Synchronous Scheduling” on page 3-11
“Asynchronous Scheduling” on page 3-12
“Scheduling Blocks” on page 3-12
“Asynchronous Scheduler Examples” on page 3-12
“Uses for Asynchronous Scheduling” on page 3-15

The following sections describe how Embedded IDE Link VS software provides timing and scheduling for generated code running on your processor.

### Timer-Based Versus Asynchronous Interrupt Processing

Code generated for periodic tasks, both single- and multitasking, runs out of the context of a timer interrupt. The generated code that represents model blocks for periodic tasks runs periodically, clocked by the periodic interrupt whose period is equal to the base sample time of the model.

---

**Note** In timer-based models, the timer counts through one full base-sample-time before it creates an interrupt. When the model is finally executed, it is for time 0.

---

This execution scheduling scheme is not flexible enough for some systems, such as control and communication systems that must respond to asynchronous events in real time. Such systems may need to handle a variety of hardware interrupts in an asynchronous, or aperiodic, fashion.

When you plan your project or algorithm, select your scheduling technique based on your application needs.

If your application processes hardware interrupts asynchronously, add the appropriate asynchronous scheduling blocks from the Embedded IDE Link VS library to your model, shown in the following table.

<b>Processor Support Library</b>	<b>Block Purpose</b>	<b>Description</b>
Blackfin	Hardware Interrupt for asynchronous scheduling	Create interrupt service routine to handle hardware interrupt on Blackfin processors
Core DSP	Idle Task	Create task that runs as separate thread for any Analog Devices processor
SHARC	Hardware Interrupt for asynchronous scheduling	Create interrupt service routine to handle hardware interrupt on SHARC processors
Target Preferences	Target Preferences	Configure model for Analog Devices processor
TigerSHARC	Hardware Interrupt for asynchronous scheduling	Create interrupt service routine to handle hardware interrupt on TigerSHARC processors

If your application does not service asynchronous interrupts, your model should include only the algorithm and device driver blocks that specify the periodic sample times. Generating code from a model like this automatically enables and manages a timer interrupt. The periodic timer interrupt clocks the entire model.

## Synchronous Scheduling

For code that runs synchronously in the context of the timer interrupt, each iteration of the model runs after an interrupt has been posted and serviced by an interrupt service routine (ISR). The code generated for Embedded IDE Link VS software uses Timer 1. Timer 1 is configured so that the base rate sample time for the coded process corresponds to the interrupt rate. Embedded IDE Link VS software calculates and configures the timer period to ensure the desired sample rate.

The minimum achievable base rate sample time depends on the algorithm complexity and the CPU clock speed. The maximum value depends on the maximum timer period value and the CPU clock speed.

If all the blocks in the model inherit their sample time value, and no sample time is defined explicitly, Simulink software assigns a default sample time of 0.2 second.

## Asynchronous Scheduling

Embedded IDE Link VS software facilitates modeling and automatically generating code for asynchronous systems by providing interrupt and task scheduling blocks as shown in the following table:

Mode	Block
Hardware Interrupt	Blackfin, SHARC, TigerSHARC
Free-Running Task for Bare-Board Code Generation	Idle Task

## Scheduling Blocks

Embedded IDE Link VS Hardware Interrupt blocks enable selected hardware interrupts for the Analog Devices processors, generate corresponding ISRs, and connect them to the corresponding interrupt service vector table entries.

When you connect the output of the Hardware Interrupt block to the control input of a function-call subsystem, the generated subsystem code is called from the ISRs each time the interrupt is raised.

The Idle Task block specifies one or more functions to execute as background tasks in the code generated for the model. The functions are created from the function-call subsystems to which the Idle Task block is connected.

## Asynchronous Scheduler Examples

After you identify the blocks to use, you can use an asynchronous (real-time) scheduler for your application. With the asynchronous scheduler you can

define interrupts and tasks to occur when you want them to by using blocks from the following libraries:

- Blackfin DSP Support
- SHARC DSP Support
- TigerSHARC DSP Support

Also, you can schedule multiple tasks for asynchronous execution using the blocks.

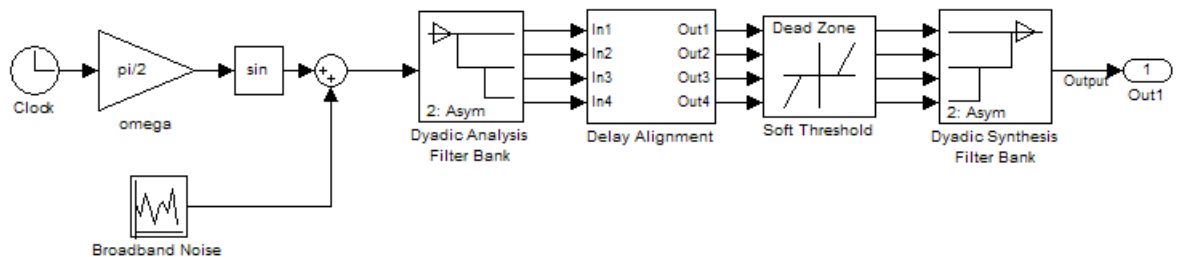
The following figures show a model updated to use the asynchronous scheduler rather than the synchronous scheduler.

---

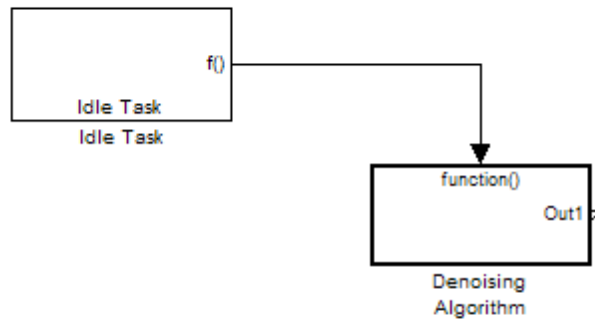
**Note** You cannot run the example models. They provide example configurations only. They will not run or build without additional blocks.

---

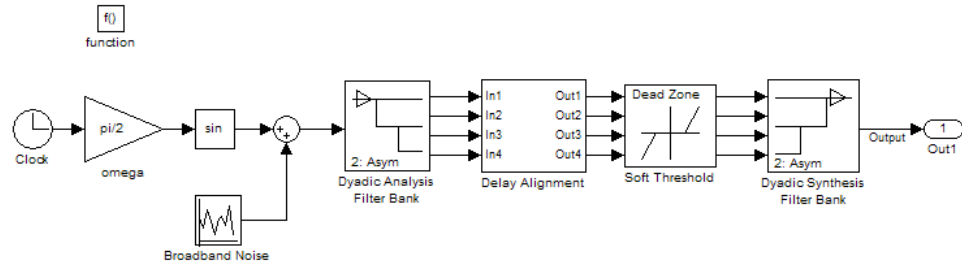
### Before



### After



## Model Inside the Function Call Subsystem Block

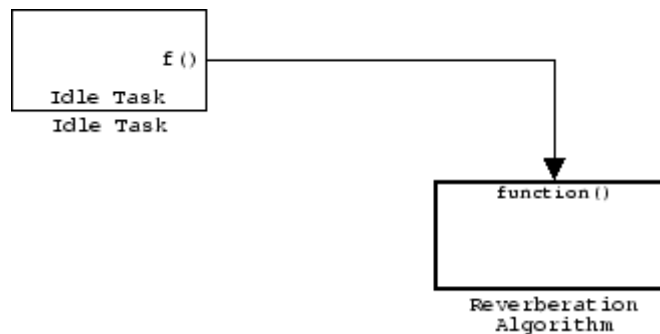


## Uses for Asynchronous Scheduling

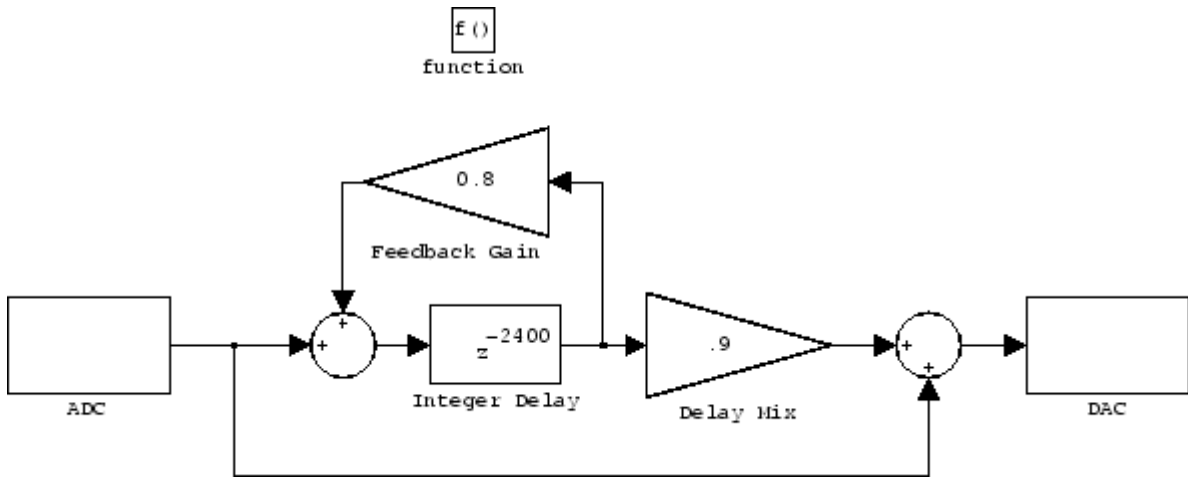
The following sections present common cases for the scheduling blocks described in the previous sections.

### Idle Task

The following model illustrates a case where the reverberation algorithm runs in the context of a background task in bare-board code generation mode.

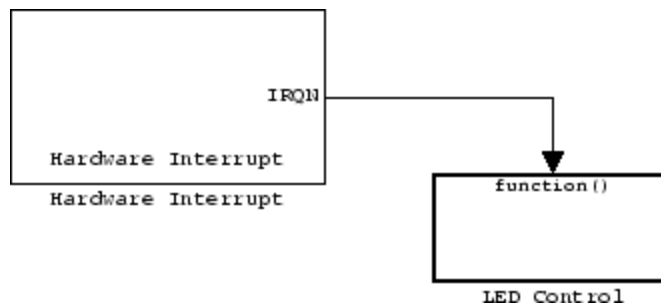


The function generated for this task normally runs in free-running mode—repetitively and indefinitely. However, the input and output blocks in this subsystem run in blocking mode. As a result, subsystem execution of the reverberation function is the same as the subsystem described for the Free-Running Task. Task execution is data driven via a background DMA interrupt-controlled ISR, shown in the following figure.



### Hardware Interrupt Triggered Task

In the next figure, you see a case where a function (control an LED) runs in the context of a hardware interrupt triggered task.



In this model, the Hardware Interrupt block installs a task that runs when it detects an external interrupt. This task then performs the specified operation.



# Project Generator Tutorial

**In this section...**

“Building the Model” on page 3-17

“Adding the Target Preferences Block to Your Model” on page 3-18

“Specifying Simulink Configuration Parameters for Your Model” on page 3-21

In this tutorial you build a model and generate a project from the model into VisualDSP++ IDE.

---

**Note** The model demonstrates project generation only. You cannot build and run the model on your processor without additional blocks.

---

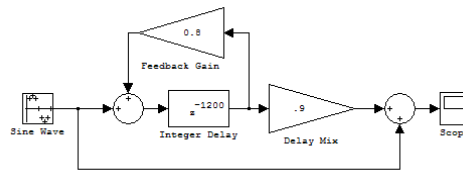
To generate a project from a model, complete the following tasks:

- 1** Use Simulink blocks, Signal Processing Blockset™ blocks, and blocks from other blocksets to create the model application.
- 2** Add the target preferences block from the Embedded IDE Link VS Target Preferences library to your model. Verify and set the block parameters for your hardware. In most cases, the default settings work fine.
- 3** Set the configuration parameters for your model, including the following parameters:
  - Solver parameters such as simulation start and solver options
  - Real-Time Workshop software options such as processor configuration and processor compiler selection
- 4** Generate your project.
- 5** Review your project in VisualDSP++ software.

## Building the Model

To build the model for audio reverberation, follow these steps:

- 1 Start Simulink software.
- 2 Create a new model by selecting **File > New > Model** from the **Simulink** menu bar.
- 3 Use Simulink blocks and Signal Processing Blockset blocks to create the following model.



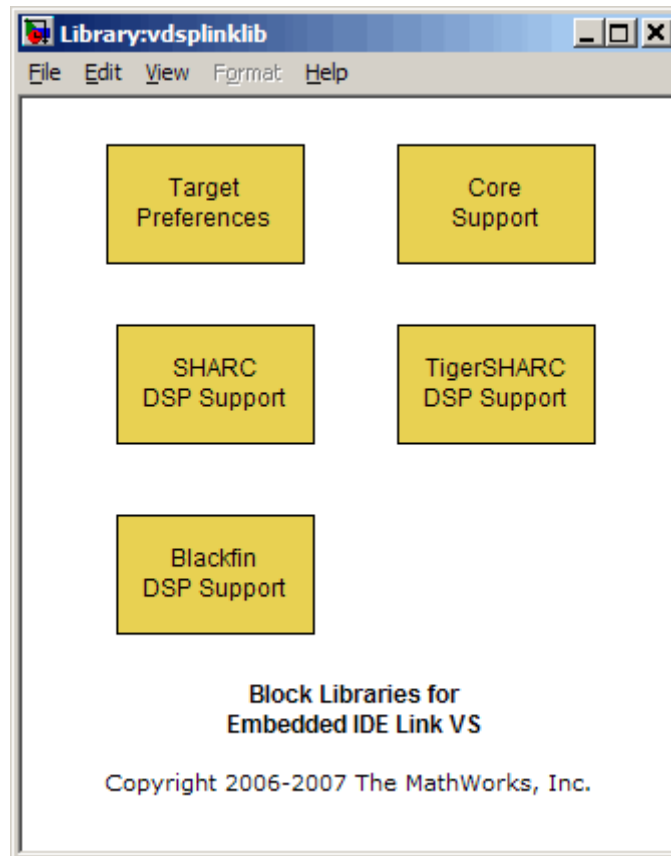
Look for the Integer Delay block in the Discrete library of Simulink and the Gain block in the Commonly Used Blocks library. Do not add the Custom Board block at this time.

- 4 Save your model with a suitable name before continuing.

## **Adding the Target Preferences Block to Your Model**

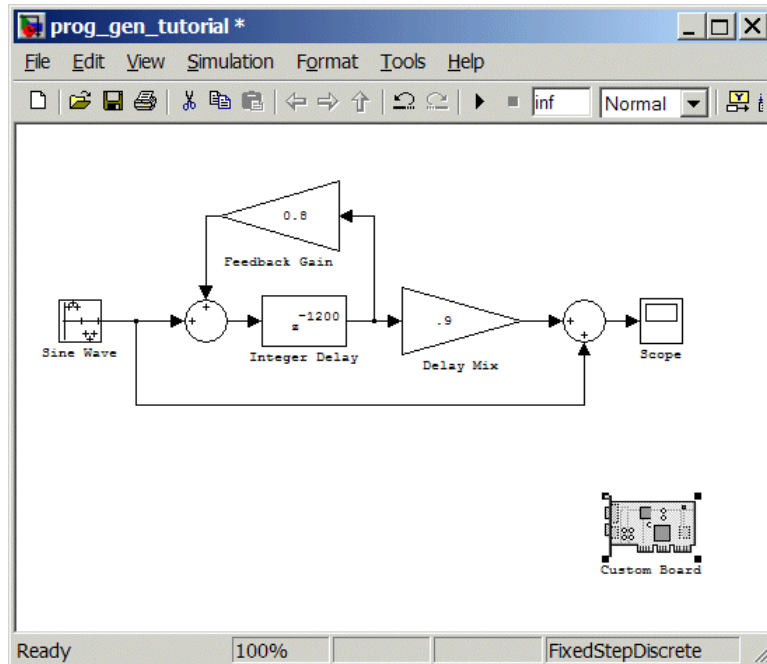
So that you can configure your model to work with Analog Devices processors, Embedded IDE Link VS software includes a block library containing a target preferences block for Analog Devices processor, Target Preferences.

Entering `vdspinklib_tgtpref` at the MATLAB prompt opens this window showing the library blocks. This block library is included in Embedded IDE Link VS `vdspinklib` blockset in the Simulink Library browser.



To add the Target Preferences block to your model, follow these steps:

- 1** Double-click Embedded IDE Link VS in the Simulink Library browser to open the vdsplinklib blockset.
- 2** Click the library Target Preferences to see the blocks available for your processor.
- 3** Drag and drop the Custom Board block to your model as shown in the following figure.



- 4 Double-click the Custom Board block to open the block dialog box.
- 5 In the Block dialog box, select your processor from the **Processor** list.
- 6 Verify the **CPU clock** value.
- 7 Select the session name from the **Session name** list. Verify that the session processor matches the one you selected from the **Processor** list.
- 8 Review the settings on the **Memory** and **Sections** tabs to verify that they are correct for the processor you selected.
- 9 Click **OK** to close the Target Preferences dialog box.

You have completed the model. Next, configure the model configuration parameters to generate a project in VisualDSP++ IDE from your model.

## Specifying Simulink Configuration Parameters for Your Model

The following sections describe how to configure the build and run parameters for your model. Generating a project, or building and running a model on the processor, starts with configuring model options in the Configuration Parameters dialog box in Simulink software.

### Setting Solver Options

After you have designed and implemented your digital signal processing model in Simulink software, complete the following steps to set the configuration parameters for the model:

- 1 Open the Configuration Parameters dialog box and set the appropriate options on the **Solver** category for your model and for Embedded IDE Link VS software.
  - Set **Start time** to 0.0 and **Stop time** to `inf` (model runs without stopping). If you set a stop time, your generated code does not honor the setting. Set this to `inf` for completeness.
  - Under **Solver options**, select the fixed-step and discrete settings from the lists.
  - Set the **Fixed step size** to Auto and the **Tasking Mode** to Single Tasking.

---

**Note** Generated code does not honor Simulink stop time from the simulation. Stop time is interpreted as `inf`. To implement a stop in generated code, you must put a Stop Simulation block in your model.

---

Ignore the Data Import/Export, Diagnostics, and Optimization categories in the Configuration Parameters dialog box. The default settings are correct for your new model.

### Setting Real-Time Workshop Software Options

To configure Real-Time Workshop software to use the correct processor files and to compile and run your model executable file, you set the options in

the Real-Time Workshop category of the **Select** tree in the Configuration Parameters dialog box. Follow these steps to set the Real-Time Workshop software options to generate code tailored for your DSP:

- 1 Select Real-Time Workshop on the **Select** tree.
- 2 In Target selection, click **Browse** to select the system target file for Analog Devices processors—`vdspink_grt.tlc`. It may already be the selected target file.

Clicking **Browse** opens the **System Target File Browser** to allow you to change the system target file.

- 3 On the **System Target File Browser**, select the system target file `vdspink_grt.tlc`, and click **OK** to close the browser.

### Setting Embedded IDE Link VS Options

After you set the Real-Time Workshop options for code generation, set the options that apply to your Analog Devices processor.

- 1 Change the category on the **Select** tree to Hardware Implementation.
- 2 Verify that the Device type is the correct value for your processor—ADI Blackfin, ADI SHARC, or ADI TigerSHARC.
- 3 From the **Select** tree, choose Embedded IDE Link VS to specify code generation options that apply to the processor.
- 4 Under **Code Generation**, select the **Inline run-time library functions** option. Clear all other options.
- 5 (optional) Under **Link Automation**, provide a name for the handle in **IDE handle name**.
- 6 Set the following options in the dialog box under **Project options**:
  - Set **Project options** to Custom.
  - Set **Compiler options string** and **Linker options string** to blank.
- 7 Set the following **Runtime** options:


- **Build action:** Create\_project.
- **Interrupt overrun notification method:** Print\_message.

You have configured the Real-Time Workshop options that let you generate a project for your processor. A few Real-Time Workshop categories on the **Select** tree, such as **Comments**, **Symbols**, and **Optimization** do not require configuration for use with Embedded IDE Link VS software. In some cases, you may decide to set options in the other categories.

For your new model, the default values for the options in these categories are correct. For other models you develop, you may want to set the options in these categories to provide information during the build and to run TLC debugging when you generate code. Refer to your Simulink and Real-Time Workshop documentation for more information about setting the configuration parameters.

## Creating Your Project

After you set the configuration parameters and configure Real-Time Workshop software to create the files you need, you direct the software to create your project:

- 1 Click **OK** to close the Configuration Parameters dialog box.
- 2 Click Incremental Build () on the model toolbar to generate your project into VisualDSP++ IDE.

When you click  with Create\_project selected for **Build action**, the automatic build process starts VisualDSP++ software and populates a new project in the development environment.

## Setting Real-Time Workshop Options for Analog Devices Processors

Before you generate code with the Real-Time Workshop software, set the fixed-step solver step size and specify an appropriate fixed-step solver if the model contains any continuous-time states. At this time, you should also select an appropriate sample rate for your system. Refer to the *Real-Time Workshop User's Guide* for additional information.

---

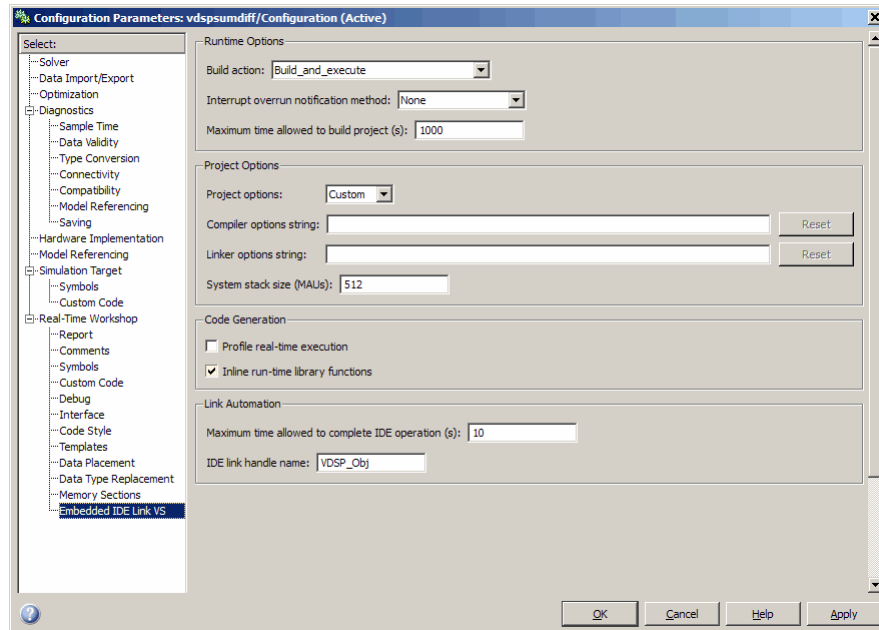
**Note** Embedded IDE Link VS software does not support continuous states in Simulink software models for code generation. In the **Solver options** in the Configuration Parameters dialog box, you must select **Discrete** (no continuous states) as the **Type**, along with **Fixed step**.

---

To open the Configuration Parameters dialog box for your model, select **Simulation > Configuration Parameters** from the menu bar.

The following figure shows the Real-Time Workshop **Select** tree categories when you are using Embedded IDE Link VS software.





In the **Select** tree, the categories provide access to the options you use to control how Real-Time Workshop software builds and runs your model. The first categories under **Real-Time Workshop** in the tree apply to all Real-Time Workshop targets including the processor and always appear on the list.

The last category under **Real-Time Workshop** is specific to Embedded IDE Link VS system target files `vdsplink_grt.tlc` and `vdsplink_ert.tlc` and appears when you select either target file.

When you select your target file in **Target Selection** on the **Real-Time Workshop** pane, the options change in the tree.

For Embedded IDE Link VS software, the target file to select is `vdsplink_grt.tlc`. Selecting either the `vdsplink_grt.tlc` or `vdsplink_ert.tlc` adds options specific to Embedded IDE Link VS software to the **Select** tree. The `vdsplink_grt.tlc` file is appropriate for all projects. Select `vdsplink_ert.tlc` when you are developing projects or code for embedded processors (requires Real-Time Workshop Embedded Coder software) or you plan to use Processor-in-the-Loop features.

The following sections present each Real-Time Workshop options category and the options available in each.

## Setting Real-Time Workshop Category Options

### In this section...

“Target File Selection” on page 3-28

“Build Process” on page 3-28

“Custom storage class” on page 3-28

“Report Options” on page 3-29

“Debug Pane Options” on page 3-30

“Optimization Pane Options” on page 3-31

“Embedded IDE Link VS Pane Options” on page 3-33

“Overrun Indicator and Software-Based Timer” on page 3-37

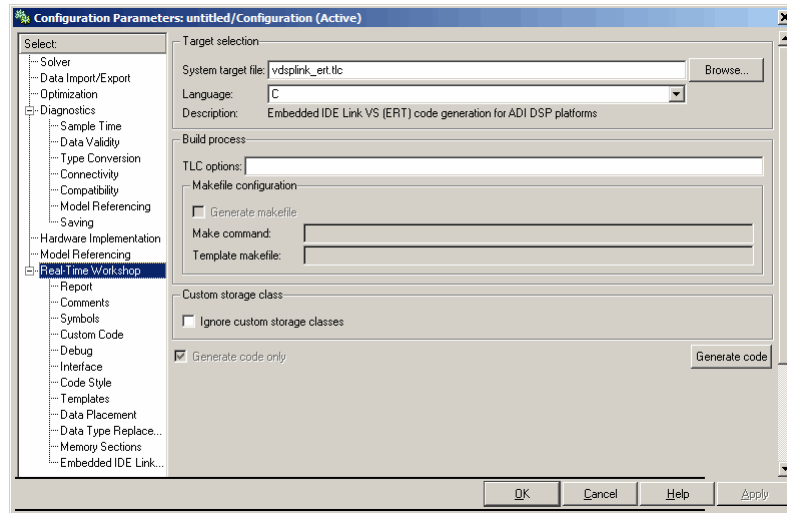
“Embedded IDE Link VS Default Project Options — Custom” on page 3-39

“Target Function Library and Embedded IDE Link VS Software” on page 3-40

Use the options in the **Select** tree under **Real-Time Workshop** to perform the following configuration tasks.

- Determine your processor, either Analog Devices or some other processor if you are not using Embedded IDE Link VS software.
- Configure your build process.
- Specify whether to use custom storage classes.

When you select one of the Embedded IDE Link VS system target files, the Embedded IDE Link VS category appears in the **Select** tree as shown in the following figure.



## Target File Selection

### System target file

Clicking **Browse** opens the Target File Browser where you select `vdsplink_grt.tlc` as your Real-Time Workshop **System target file**.

If you are using Real-Time Workshop Embedded Coder software, select the `vdsplink_ert.tlc` target file in **System target file**.

### Build Process

Embedded IDE Link VS software does not use makefiles or the build process to generate code. Code generation is project based so the options here do not apply.

### Custom storage class

When you generate code from a model employing custom storage classes (CSC), clear **Ignore custom storage classes**. This setting is the default value for Embedded IDE Link VS software and for Real-Time Workshop Embedded Coder software.

When you select **Ignore custom storage classes**, storage class attributes and signals are affected in the following ways:

- Objects with CSCs are treated as if you set their storage class attribute to Auto.
- The storage class of signals that have CSCs does not appear on the signal line, even when you select **Storage class** from **Format > Port/Signals Display** in your Simulink menus.

**Ignore custom storage classes** lets you switch to a processor that does not support CSCs, such as the generic real-time target (GRT), without reconfiguring your parameter and signal objects.

### **Generate code only**

The **Generate code only** option does not apply to targeting with Embedded IDE Link VS software. To generate source code without building and executing the code on your processor, select Embedded IDE Link VS from the **Select** tree. Then, under **Runtime**, select **Create\_project** for **Build action**.

### **Report Options**

Two options control HTML report generation during code generation.

- “Create Code Generation report” on page 3-29
- “Launch report automatically” on page 3-30

### **Create Code Generation report**

After you generate code, this option tells the software whether to generate an HTML report that documents the C code generated from your model. When you select this option, Real-Time Workshop writes the code generation report files in the `html` subdirectory of the build directory. The top-level HTML report file is named `modelname_codegen_rpt.html` or `subsystemname_codegen_rpt.html`. For more information about the report, refer to the online help for Real-Time Workshop. You can also use the following command at the MATLAB prompt to get more information.

```
docsearch 'Create code generation report'
```

In the Navigation options, when you select **Model-to-code** and **Code-to-model**, your HTML report includes hyperlinks to various features in your Simulink model.

### Launch report automatically

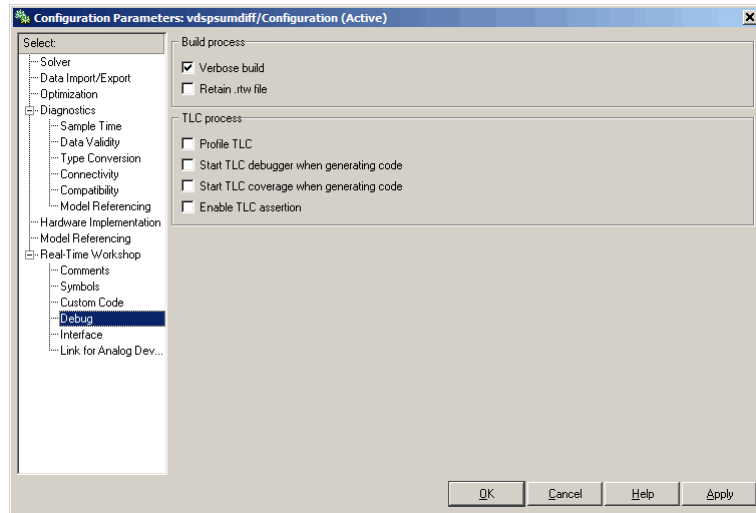
This option directs Real-Time Workshop to open a MATLAB Web browser window and display the code generation report. If you clear this option, you can open the code generation report (*modelName\_codegen\_rpt.html* or *subsystemname\_codegen\_rpt.html*) manually in a MATLAB Web browser window or in another Web browser.

### Debug Pane Options

Real-Time Workshop software uses the Target Language Compiler (TLC) to generate C code from the *model.rtw* file. The TLC debugger helps you identify programming errors in your TLC code. Using the debugger, you can perform the following actions:

- View the TLC call stack.
- Execute TLC code line-by-line.
- Analyze or change variables in a specified block scope.

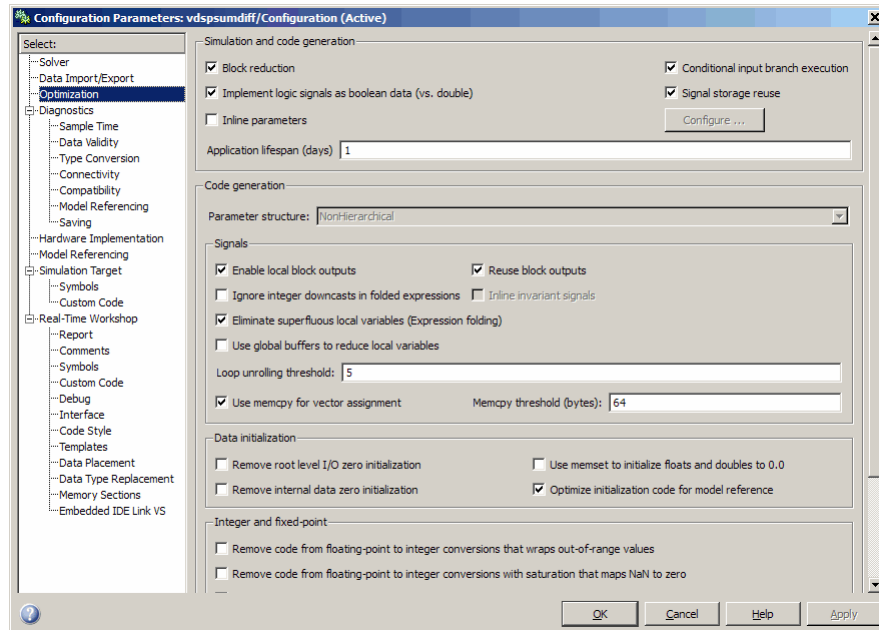
When you select **Debug** from the **Select** tree, you see the **Debug** options as shown in the next figure. In this pane, you set options that are specific to the Real-Time Workshop software process and TLC debugging.



For details about using the options in **Debug**, refer to “About the TLC Debugger” in your Real-Time Workshop Target Language Compiler documentation.

## Optimization Pane Options

On the **Optimization** pane in the Configuration Parameters dialog box, you set options for the code that Real-Time Workshop software generates during the build process. Use these options to tailor the generated code to your needs. Select **Optimization** from the **Select** tree on the Configuration Parameters dialog box. The figure shows the **Optimization** pane when you select the system target file `vdsplink_grt.tlc` under **Real-Time Workshop system target file**.



The following options are typically selected for Real-Time Workshop software to provide optimized code generation for common code operations:

- **Conditional input branch execution**
- **Signal storage reuse**
- **Enable local block outputs**
- **Reuse block outputs**
- **Eliminate superfluous temporary variables (Expression folding)**
- **Loop unrolling threshold**
- **Optimize initialization code for model reference**

For more information about using these and the other Optimization options, refer to the Real-Time Workshop documentation.



## Embedded IDE Link VS Pane Options

On the select tree, the Embedded IDE Link VS category provides options in these areas:

- **Link Automation** — Export a handle to your MATLAB workspace.
- **Code Generation** — Configure your code generation requirements, such as enabling real-time task execution profiling.
- **Project Options** — Set build options for your project code generation, including compiler and linker settings.
- **Runtime** — Set options for run-time operations, like the build action.
- **Processor-in-the-loop (PIL) verification** — Enable processor in the loop capability for your project.

### Link Automation

When you use Real-Time Workshop software to build a model to an Analog Devices processor, Embedded IDE Link VS software makes a connection between MATLAB software and the VisualDSP++ IDE. MATLAB software represents that connection as an `adivdsp` object. The properties of the `adivdsp` object contain information about the IDE instance it refers to, such as the session and processor it accesses. In this pane, the **IDE link handle name** option instructs Embedded IDE Link VS software to export the `adivdsp` object created during code generation to your MATLAB workspace with the name you enter. Replace the default name `VDSP_obj` with your own name for the object to export.

### Code Generation

From this category, you select options that define the way your code is generated:

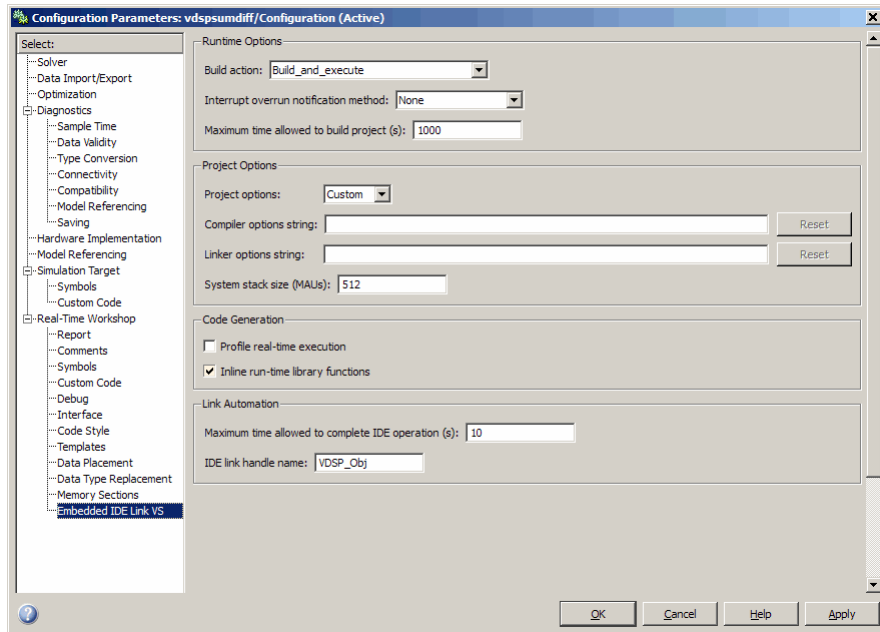
- **Profile real-time task execution**
- **Inline run-time library functions**

To enable the real-time execution profile capability, select **Profile real-time task execution**. When you select this option, the build process instruments your code to provide performance profiling at the task level. When you run

your code, the executed code reports the profiling information in both a graphical presentation and an HTML report form.

To allow you to specify whether the functions generated from blocks in your model are used inline or by pointers, **Inline run-time library functions** tells the compiler to inline each Signal Processing Blockset and Video and Image Processing Blockset™ function. Using inline functions optimizes your code to run more efficiently. However, such optimization requires more memory.

As shown in the following figure, the default setting uses inlining to optimize your generated code.



When you designate a block function as inline, the compiler replaces each call to a block function with the equivalent function code from the static run-time library. If your model use the same block four times, your generated code contains four copies of the function.

While this redundancy uses more memory, inline functions run more quickly than calls to the functions outside the generated code.

## Project Options

Before you run your model as an executable on any processor, configure the Project options for the model. By default, the setting for the project options is **Custom**, which applies MathWorks software specified compiler and linker settings for your generated code.

## Compiler options string

To let you determine the degree of optimization provided by the Analog Devices optimizing compiler, you enter the optimization level to apply to files in your project. For details about the compiler options, refer to your VisualDSP++ documentation. When you create new projects, Embedded IDE Link VS software sets the optimization to **Function (-o2)**.

## Linker options string

To let you specify the options provided by the Analog Devices linker during link time, you enter the linker options as a string. For details about the linker options, refer to your VisualDSP++ documentation. When you create new projects, Embedded IDE Link VS software sets no linker options.

## System stack size (MAUs)

Enter the amount of memory to use for the stack. For more information on memory requirements, refer to **Enable local block outputs** on the **Optimization** pane of the Configuration Parameters dialog box. Block output buffers are placed on the stack until the stack memory is fully allocated. When the stack memory is full, the output buffers go in global memory. Refer to the online Help system for more information about Real-Time Workshop software options for configuring and building models and generating code.

## Runtime

Before you run your model as an executable on any Analog Devices processor, you must configure the run-time options for the model.

By selecting values for the options available, you configure the operation of your model build process and overrun handling.

### **Build action**

To specify to Real-Time Workshop software what to do when you click **Build**, select one of the following options.:

- **Create\_project** — Directs Real-Time Workshop software to start VisualDSP++ IDE and populate a new project with the files from the build process. This option offers a convenient way to build projects in VisualDSP++ software.
- **Archive\_library** — Directs Real-Time Workshop software to archive the project for this model. Use this option when you plan to use the model in a model reference application. Model reference requires that you archive your VisualDSP++ software projects for models that you use in model referencing.
- **Build** — Builds the executable file, but does not download the file to your processor.
- **Build\_and\_execute** — Directs Real-Time Workshop software to build, download, and run your generated code as an executable on your processor.
- **Create\_processor\_in\_the\_loop\_project** — Directs the Real-Time Workshop code generation process to create PIL algorithm object code as part of the project build.

Your selection for **Build action** determines what happens when you click **Build** or press **Ctrl+B**. Your selection tells Real-Time Workshop software at which stage to stop the code generation and build process.

To run your model on the processor, select the default build action, **Build\_and\_execute**. Real-Time Workshop software automatically downloads and runs the model on your processor.

---

**Note** When you build and execute a model on your processor, the Real-Time Workshop software build process resets the processor automatically. You do not need to reset the board before building models.

---

## Interrupt overrun notification method

To enable the overrun indicator, choose one of three ways for the processor to respond to an overrun condition in your model:

- **None** — Ignore overruns encountered while running the model.
- **Print\_message** — When the processor encounters an overrun condition, it prints a message to the standard output device, `stdout`.
- **Call\_custom\_function** — Respond to overrun conditions by calling the custom function you identify in **Interrupt overrun notification function**.

## Interrupt overrun notification function

When you select `Call_custom_function` from the **Interrupt overrun notification method** list, you enable this option. Enter the name of the function the processor should use to notify you that an overrun condition occurred. The function must exist in your code on the processor.

## Overrun Indicator and Software-Based Timer

Embedded IDE Link VS software includes code that generates interrupts in models that use multiple clock rates. In the following cases, the overrun indicator does not work:

- In multirate systems where the rate in the model is not the same as the base clock rate for your model. In such cases, the timer in Embedded IDE Link VS software provides the interrupts for setting the model rate.
- In models that do not include ADC or DAC blocks. In such cases, the timer provides the software interrupts that drive model processing.

## PIL block action

If you have Real-Time Workshop Embedded Coder software installed and you select the `vdspink_ert.tlc` system target file, you can choose to use the processor-in-the-loop (PIL) feature provided by Embedded IDE Link VS software. Selecting `Create_processor_in_the_loop_project` for the **Build action** enables the **PIL block action** option. **PIL block action** specifies whether Real-Time Workshop software builds the PIL block and downloads the block to the processor.

Choose one of the following three actions for creating a PIL block:

- **None** — Configures model to generate a VisualDSP++ project that contains the PIL algorithm code. Does not build the PIL object code or block. The new project will not compile in VisualDSP++ software.
- **Create PIL block** — Creates a PIL block, places the block in a new model, and then stops without building or downloading the block. The resulting project will not compile in VisualDSP++ IDE.
- **Create PIL block\_build\_and\_download** — Builds and downloads the PIL application to the processor after creating the PIL block. Adds PIL interface code that exchanges data with Simulink software. Use this selection to update the algorithmic code in an existing PIL block in a model.

Your selections affect how you use the resulting PIL block. The following list describes the build process and actions you take based on the **PIL block action** setting:

- When you click **Build** on the PIL dialog box, the build process adds the PIL interface code to the project and compiles the project in VisualDSP++ IDE.
- If you select **Create PIL block**, you can build manually from the right-click context menu on the PIL block.
- After you select **Create PIL Block**, copy the PIL block into your model to replace the original subsystem. Save the original subsystem in a different model so you can restore in the future. Click **Build** to build your model with the PIL block in place.
- Add the PIL block to your model to use cosimulation to compare PIL results with the original subsystem results. Refer to the demo *Getting Started with Application Development* in the product demos *Embedded IDE Link VS*
- To use the PIL block in a project after you selected **None** or **Create PIL block** for **Block action** when you built the project, click **Build** followed by **Download** in the PIL block dialog box.

## Embedded IDE Link VS Default Project Options – Custom

Although VisualDSP++ software offers standard project configurations, Release and Debug, models you build with Embedded IDE Link VS software use Custom for a custom configuration that provides a third combination of build and optimization.

Project configurations define sets of project build options. When you specify the build options at the project level, the options apply to all files in your project. For more information about the build options, refer to your Analog Devices VisualDSP++ documentation.

The default settings for Custom are the same as the Release project configuration in VisualDSP++ software, except for the compiler options discussed in the next section “Default Project Options in Custom” on page 3-39. Custom uses different compiler optimization levels to preserve important features of the generated code.

### Default Project Options in Custom

When you create a new project or build a model to your Analog Devices processor, your project and model inherit the build configuration settings from the configuration Custom. The settings in Custom differ from the settings in the default Debug and Release configurations in VisualDSP++ software in the compiler settings.

For the compiler options, Custom uses the Function(-o2) compiler setting. The VisualDSP++ software default Release configuration uses File(-o3), a slightly more aggressive optimization model.

For memory configuration, where Release uses the default memory model that specifies near functions and data, Custom specifies near functions and data—the -m11 memory model—because some custom hardware might not support far data or aggregate data. Your VisualDSP++ documentation provides complete details on the compiler build options.

You can change the individual settings or the build configuration within VisualDSP++ IDE. Build configuration options that do not appear on these panes default to match the settings for the Release build configuration in VisualDSP++ software.

## Target Function Library and Embedded IDE Link VS Software

If you are using `vdspLink_ert.tlc` as your system target file, Embedded IDE Link VS software supports generating code that is optimized for the processor by using compiler intrinsics and assembly code to replace certain mathematical operator functions. Embedded IDE Link VS software accomplishes this optimization through the Target Function Library (TFL) replacement mechanism that Real-Time Workshop Embedded Coder software provides. TFL replacement requires Real-Time Workshop Embedded Coder software and the embedded real-time target—`vdspLink_ert.tlc`.

Some code generation stages launch TFL queries. Based on the processor you select, TFL replaces the default Real-Time Workshop software sum and multiply functions and other arithmetic and mathematical operators with processor-specific compiler intrinsics and assembly code functions. For more general information about TFL, look for TFL in the Interface options in “Configuring Real-Time Workshop Code Generation Parameters”.

### TFL Replacement Functions

When you enable TFL replacement, Real-Time Workshop Embedded Coder software uses compiler intrinsics and assembly code functions provided by Embedded IDE Link VS software to replace the sums and multiplies in your generated code. The replacement functions provide optimized operations that enable your generated code to run more efficiently and quickly.

### TFL Viewer

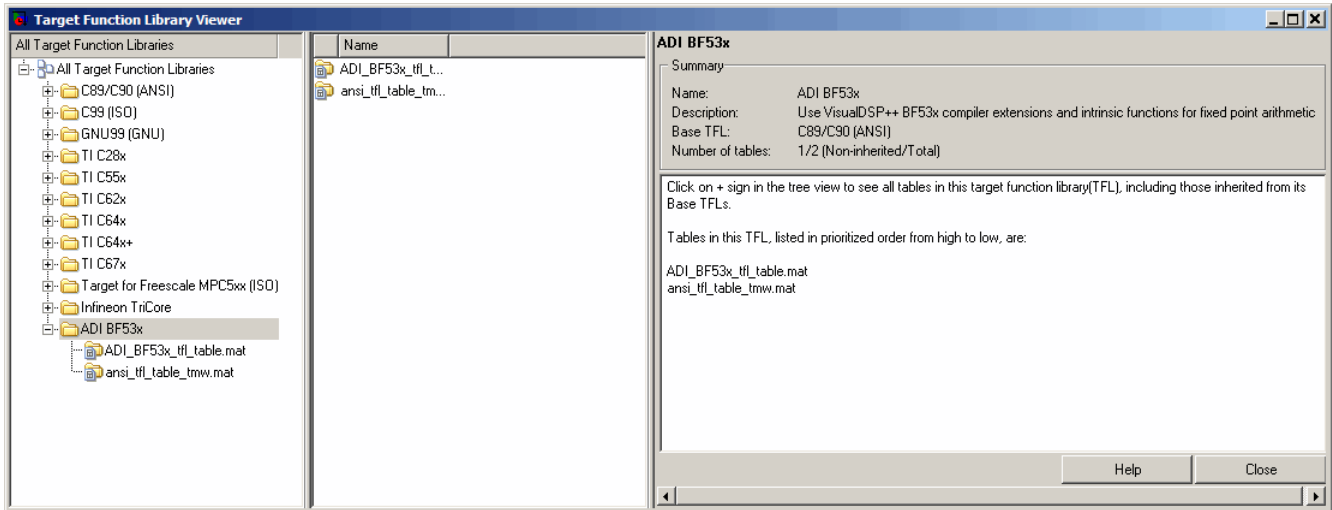
TFL replacement does not provide direct feedback when you generate code. To help you review the TFL replacement operators and code, Real-Time Workshop Embedded Coder software provides the TFL Viewer. To start the viewer with all of the available math libraries listed, enter the following command at the MATLAB prompt:

```
RTW.viewTFL
```

The viewer enables you to see the content of target function library tables that were created using Real-Time Workshop Embedded Coder software. The following figure shows the TFL viewer displaying the libraries for the



Blackfin 53x processor family. Follow the instructions in the viewer to see the operators and the TFL code associated with each operator.



## Enabling TFL for Code Generation

You use an option in the Configuration Parameters for your model to enable TFL replacement during code generation. Perform the following steps to enable the TFL replacement process when you generate code from a model.

To use the TFL replacement capability when you generate code, you must install Real-Time Workshop Embedded Coder software and select the system target file `vdspink_ert.tlc`.

- 1 Open the Configuration Parameters for your model by selecting **Simulation > Configuration Parameters** from the model menu bar.
- 2 On the **Select** tree in the Configuration Parameters dialog box, choose Real-Time Workshop.
- 3 Set the **System target file** to `vdspink_ert.tlc`. Use **Browse** to select the file.
- 4 On the **Select** tree, choose Interface.

**5** From the **Target function library** list, select the Analog Devices processor family that matches your processor.

**6** Click **OK** to save your changes and close the dialog box.

With TFL enabled, your generated code uses the TFL replacement libraries provided for your processor.

## Model Reference and Embedded IDE Link VS Software

### In this section...

“How Model Reference Works” on page 3-43

“Using Model Reference with Embedded IDE Link VS Software” on page 3-44

“Configuring Targets to Use Model Reference” on page 3-46

Model reference lets your model include other models as modular components. This technique is useful because it provides the following capabilities:

- Simplifies working with large models by letting you build large models from smaller ones, or even large ones.
- Lets you generate code once for all the modules in the entire model and then only regenerate code for modules that change.
- Lets you develop the modules independently.
- Lets you reuse modules and models by reference, rather than including the model or module multiple times in your model. Also, multiple models can refer to the same model or module.

Your Real-Time Workshop documentation provides much more information about model reference.

### How Model Reference Works

Model reference behaves differently in simulation and in code generation. For this discussion, you need to know the following terms:

- The *Top model* is the root model block or model. It refers to other blocks or models. In the model hierarchy, this is the topmost model.
- *Referenced models* are blocks or models that other models reference, such as models the top model refers to. All models or blocks below the top model in the hierarchy are reference models.

The following sections describe briefly how model reference works. More details are available in your Real-Time Workshop documentation in the online Help system.

### **Model Reference in Simulation**

When you simulate the top model, Real-Time Workshop software detects that your model contains referenced models. Simulink software generates code for the referenced models and uses the generated code to build shared library files for updating the model diagram and simulation. It also creates an executable (.mex file) for each reference model that is used to simulate the top model.

When you rebuild reference models for simulations or when you run or update a simulation, Simulink software rebuilds the model reference files. Whether reference files or models are rebuilt depends on whether and how you change the models and on the **Rebuild options** settings. You can access these setting through the **Model Reference** pane of the Configuration Parameters dialog box.

### **Model Reference in Code Generation**

Real-Time Workshop software requires executables to generate code from models. If you have not simulated your model at least once, Real-Time Workshop software creates a .mex file for simulation.

Next, for each referenced model, the code generation process calls `make_rtw` and builds each referenced model. This build process creates a library file for each of the referenced models in your model.

After building all the referenced models, the software calls `make_rtw` on the top model, linking to all the library files it created for the associated referenced models.

### **Using Model Reference with Embedded IDE Link VS Software**

With few limitations or restrictions, Embedded IDE Link VS software provides full support for generating code from models that use model reference.

## Build Action Setting

The most important requirement for using model reference with the Analog Devices targets is that you must set the **Build action** (select **Configuration Parameters > Embedded IDE Link VS**) for all models referred to in the simulation to `Archive_library`.

To set the build action, perform the following steps:

- 1 Open your model.
- 2 Select **Simulation > Configuration Parameters** from the model menus.

The Configuration Parameters dialog box opens.

- 3 From the **Select** tree, choose **Embedded IDE Link VS**.
- 4 In the right pane, under **Runtime**, select set `Archive_library` from the **Build action** list.

If your top model uses a reference model that does not have the build action set to `Archive_library`, the build process automatically changes the build action to `Archive_library` and issues a warning about the change.

Selecting the `Archive_library` setting removes the following options from the dialog box:

- **Interrupt overrun notification method**
- **Compiler options string**
- **Linker options string**
- **System stack size (MAUs)**
- **Profile real-time task execution**

## Target Preferences Blocks in Reference Models

Each referenced model and the top model must include a Target Preferences block for the correct processor. You must configure all the Target Preferences blocks for the same processor.

The referenced models need target preferences blocks to provide information about which compiler and which archiver to use. Without these blocks, the compile and archive processes do not work.

By design, model reference does not allow information to pass from the top model to the referenced models. Referenced models must contain all the necessary information, which the Target Preferences block in the model provides.

### **Other Block Limitations**

Model reference with Embedded IDE Link VS software does not allow you to use the following blocks or S-functions in reference models:

- No noninlined S-functions
- No blocks from the Embedded IDE Link VS library (vdsplinklib) (because these are noninlined S-functions)

### **Configuring Targets to Use Model Reference**

When you create models to use in Model Referencing, keep in mind the following considerations:

- Your model must use a system target file derived from the ERT or GRT targets files.
- When you generate code from a model that references other models, you must configure the top-level model and the referenced models for the same system target file.
- Real-Time Workshop software builds and Embedded IDE Link VS software do not support external mode in model reference. If you select the external mode option, it is ignored during code generation.
- Your TMF must support use of the shared utilities directory, as described in Supporting Shared Utility Directories in the Build Process in the Real-Time Workshop documentation.

To use an existing processor, or a new processor, with Model Reference, set the `ModelReferenceCompliant` flag for the processor. For information about setting this option, refer to `ModelReferenceCompliant` in the online Help system.

If you start with a model that was created prior to MATLAB release R14SP3, use the following command to set the `ModelReferenceCompliant` flag to `On` to make your model compatible with model reference:

```
set_param(bdroot, 'ModelReferenceCompliant', 'on')
```

Code that you generate from Simulink software models by using Embedded IDE Link VS software automatically include the model reference capability. You do not need to set the flag.





# Verification

---

- “What is Verification?” on page 4-2
- “Using Processor-in-the-Loop” on page 4-3
- “Real-Time Execution Profiling” on page 4-11
- “System Stack Profiling” on page 4-18

## What is Verification?

Verification consists broadly of running generated code on a processor and verifying that the code does what you intend. The components of Embedded IDE Link VS software combine to provide tools that help you verify your code during development by letting you run portions of simulations on your hardware and profiling the executing code.

Using the Automation Interface and Project Generator components, Embedded IDE Link VS software offers the following verification functions:

- Processor-in-the-Loop — A technique to help you evaluate how your process runs on your processor
- Real-Time Task Execution Profiling — A tool that lets you see how the tasks in your process run in real-time on your processor hardware
- Stack usage profiling — A tool that lets you see how your application uses the CPU stack

## Using Processor-in-the-Loop

In this section...
“Processor-in-the-Loop Overview” on page 4-3
“PIL Block” on page 4-6
“PIL Issues” on page 4-6
“Creating and Using PIL Blocks” on page 4-8

Processor-in-the-loop provides one verification capability in your development process.

### Processor-in-the-Loop Overview

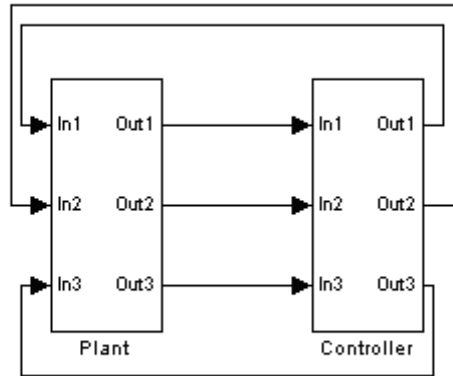
Processor-in-the-loop (PIL) cosimulation is a technique designed to help you evaluate how well a candidate algorithm, such as a control system, operates on the actual processor selected for the application.

The term *cosimulation* reflects a division of labor in which Simulink software models the plant, while code generated from the controller subsystem runs on the processor hardware.

During the Real-Time Workshop Embedded Coder code generation process, you can create a PIL block from one of several Simulink software components including a model, a subsystem in a model, or subsystem in a library. You then place the generated PIL block inside a Simulink software model that serves as the test harness and run tests to evaluate the processor-specific code execution behavior.

### Why Use Cosimulation?

PIL cosimulation is particularly useful for simulating, testing, and validating a controller algorithm in a system comprising a plant and a controller. In a classic closed-loop simulation, Simulink software and Stateflow<sup>®</sup> software model such a system as two subsystems with the signals transmitted between them, as shown in the following block diagram:



Your starting point in developing a plant/controller system is to model the system as two subsystems in closed-loop simulation. As your design progresses, you can use Simulink external mode with standard Real-Time Workshop software targets (such as GRT or ERT) to help you model the control system separately from the plant.

However, these simulation techniques do not help you account for restrictions and requirements imposed by the hardware, such as limited memory resources, or behavior of processor-specific optimized code. When you finally reach the stage of deploying controller code on the processor hardware, you may need to make extensive adjustments to the controller system. After you make these adjustments, your deployed system may diverge significantly from the original model. Such discrepancies can create difficulties if you need to return to the original model and change it.

PIL cosimulation addresses these issues by providing an intermediate stage between simulation and deployment. In a PIL cosimulation, the processor participates fully in the simulation loop—hence the term *processor-in-the-loop*.

### *Definitions*

### **PIL Algorithm**

The algorithmic code, such as the control algorithm, to be tested during the PIL cosimulation. The PIL algorithm resides in compiled object form to allow verification at the object level.

### **PIL Application**

The executable application to run on the processor. The PIL application is created by linking the PIL algorithm object code with some wrapper code (or test harness) that provides an execution framework that interfaces to the PIL algorithm.

The wrapper code includes the `string.h` header file so that the `memcpy` function is available to the PIL application. The PIL application uses `memcpy` to facilitate data exchange between Simulink software and the cosimulation processor.

---

**Note** Whether the PIL algorithm code under test uses `string.h` is independent of the use of `string.h` by the wrapper code, and depends on the implementation of the algorithm in the generated code.

---

### **How Cosimulation Works**

In a PIL cosimulation, Real-Time Workshop software generates an executable application for the PIL algorithm. This code runs (in simulated time) on a processor platform. The plant model remains in Simulink software without the use of code generation.

During PIL cosimulation, Simulink software simulates the plant model for one sample interval and exports the output signals (`outn` of the plant) to the processor platform via VisualDSP++ IDE. When the processor platform receives signals from the plant model, it executes the PIL algorithm for one sample step. The PIL algorithm returns its output signals (`ontn` of the algorithm) computed during this step to Simulink software in `inn`, via the VisualDSP++ interface. At this point, one sample cycle of the simulation is complete and the plant model proceeds to the next sample interval. The process repeats and the simulation progresses.

PIL tests do not run in real time. After each sample period, the simulation halts to ensure that all data has been exchanged between the Simulink software test harness and object code. You can then check functional differences between the model and generated code.

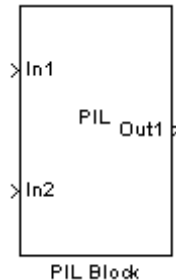
## PIL Block

The PIL cosimulation block is the Simulink software block interface to PIL and the interface between the Simulink software model and the executable application running on the processor. The Simulink software inputs and outputs of the PIL cosimulation block are configured to match the input and output specification of the PIL algorithm.

The block is a basic building block that enables you to perform these operations:

- Select a PIL algorithm
- Build and download a PIL application
- Run a PIL cosimulation

The PIL block inherits the shape and signal names from the parent subsystem, like those in the following example. This inheritance feature is convenient for copying the PIL block into the model to replace the original subsystem for cosimulation.



## PIL Issues

- “Data Types Must Be The Same Size on the Host and Processor” on page 4-7

- “Buses and MUX Signals Not Supported at PIL Component Boundary” on page 4-8
- “Signals with Custom Storage Classes Not Supported at PIL Component Boundary” on page 4-8
- “Continuous Sample Times Not Supported” on page 4-8
- “Real-Time Workshop Software grt.tlc-Based Targets Not Supported” on page 4-8

Consider the following issues when you work with PIL blocks.

### **Data Types Must Be The Same Size on the Host and Processor**

Only data types with the same size on the host and processor are supported at the PIL I/O boundary.

The data types used at the PIL I/O boundary are restricted based on the following rule: PIL supports the data type only if the data type size in MATLAB is the same as the data type size on the processor.

- For `boolean`, `uint8`, and `int8`, the size is 8 bits on the processor and in MATLAB.
- For `uint16` and `int16`, the size is 16 bits on the processor and in MATLAB.
- For `uint32` and `int32`, the size is 32 bits on the processor and in MATLAB.
- For `single`, the size is 32 bits on the processor and in MATLAB.
- For `double`, the size is 64 bits on the processor and in MATLAB.

Examples of MATLAB data types that are not supported on some processors:

- On SHARC — `boolean`, `uint8`, `int8`, `uint16`, and `int16` and are not supported because the processor is limited to 32-bit word addressing.
- On TigerSHARC — `boolean`, `uint8`, `int8`, `uint16`, and `int16` and are not supported because the processor is limited to 32-bit word addressing.

To avoid data type problems, do not use the example data types in your model because the data type on the processor does not match the built-in MATLAB data type.

### **Buses and MUX Signals Not Supported at PIL Component Boundary**

Buses and MUX Signals are not supported at the PIL component boundary.

There is no resolution for this issue.

### **Signals with Custom Storage Classes Not Supported at PIL Component Boundary**

Signals with Custom Storage Classes are not supported at the PIL component boundary.

There is no resolution for this issue.

PIL does support the standard storage classes, such as ExportedGlobal.

### **Continuous Sample Times Not Supported**

Continuous sample times are not supported by PIL. If you encounter this you see the following error:

```
??? Processor-in-the-Loop (PIL) does not support continuous  
time. Please uncheck "continuous time" in the RTW Interface  
configuration set options or disable PIL.
```

You must use discrete sample times in your model configuration parameters when you use PIL.

### **Real-Time Workshop Software grt.tlc-Based Targets Not Supported**

Real-Time Workshop grt.tlc-based targets are not supported for PIL.

To use PIL, select the vdsplink\_ert.tlc target provided by Real-Time Workshop Embedded Coder software.

### **Creating and Using PIL Blocks**

Using PIL and PIL blocks to verify your processes begins with a Simulink software model of your process. To see an example of one such model used to implement PIL, refer to the demo Comparing Simulation and Processor



---

Implementation with Processor-in-the Loop (PIL) (`pilsumdiffdemo.mdl`) in the demos for Embedded IDE Link VS.

---

**Note** Your models can have multiple PIL blocks for different subsystems. You cannot have more than one PIL block for the same subsystem. Including multiple PIL blocks for the same subsystem causes errors and incorrect results.

---

To create and use a PIL block, perform the following tasks:

**1** Develop the model of the process to simulate.

Use Simulink software to build a model of the process to simulate. The blocks in the library `vdspinklib` can help you set up the timing and scheduling for your model.

For information about building Simulink software models, refer to *Getting Started with Simulink* in the online Help system.

**2** Convert your process to a masked subsystem in your model.

For information about how to convert your process to a subsystem, refer to *Creating Subsystems* in *Using Simulink* or in the online Help system.

**3** Open the new masked subsystem and add a target preferences block to the subsystem.

The block library `vdspinklib` contains the Target Preferences block to add to your system. Configure the Target Preferences block for your processor. For details about the options on the Target Preferences block, refer to the Target Preferences block reference in the online Help system.

**4** Configure your model to enable it to generate PIL algorithm code and a PIL block from your subsystem.

- From the model menu bar, go to **Simulation > Configuration Parameters** in your model to open the Configuration Parameters dialog box.

- b** Choose **Real-Time Workshop** from the **Select** tree. Set the configuration parameters for your model as required by Embedded IDE Link VS software. Get more information about setting the Real-Time Workshop software parameters in “Setting Real-Time Workshop Options for Analog Devices Processors” on page 3-24 in the online Help system.
  - c** Under **Target selection**, set the **System target file** to `vdsplink_ert.tlc` (PIL requires Real-Time Workshop Embedded Coder software).
- 5** Configure the model to perform PIL building and PIL block creation.
- a** Select **Embedded IDE Link VS** on the **Select** tree.
  - b** Under **Build action**, select **Create\_processor\_in\_the\_loop\_project** from the list to enable PIL block and PIL project generation.
  - c** Click **OK** to close the Configuration Parameters dialog box.
- 6** To create the PIL block, right-click the masked subsystem in your model and select **Real-Time Workshop > Build Subsystem** from the context menu.

This step builds the PIL algorithm object code and a PIL block that corresponds to the subsystem, with the same inputs and outputs. Follow the progress of the build process in the MATLAB command window.

A new model window opens and the new PIL block appears in it.

- 7** Copy the new PIL block from the new model to your model, either in parallel to your masked subsystem to cosimulate the processes, or replace your subsystem with the PIL block.

To see the PIL block used in parallel to a masked subsystem, refer to the demo Comparing Simulation and Processor Implementation with Processor-in-the Loop (PIL) (`pilsumdiffdemo.mdl`) in the demos for Embedded IDE Link VS.

- 8** Click **Simulation > Start** to run the PIL simulation and view the results.

## Real-Time Execution Profiling

In this section...
“Overview” on page 4-11
“Profiling Execution by Tasks” on page 4-12
“Profiling Execution By Subsystems” on page 4-15

### Overview

Real-time execution profiling in Embedded IDE Link VS software uses a set of utilities to support profiling for synchronous and asynchronous tasks, or atomic subsystems, in your generated code. These utilities record, upload, and analyze the execution profile data.

Execution profiler supports profiling your code two ways:

- Tasks—Profile your project according to the tasks in the code.
- Atomic subsystems—Profile your project according to the atomic subsystems in your model.

---

**Note** To perform execution profiling, you must generate your project from a model in Simulink modeling environment and you must select the system target file `vdsplink_ert.tlc` in the model configuration parameters.

---

When you enable profiling, you select whether to profile by task or subsystem.

To profile by subsystems, you must configure your model with at least one atomic subsystem. To learn more about creating atomic subsystems, refer to “Creating Subsystems” in the online help for Simulink software.

The profiler generates output in the following formats:

- Graphical display that shows task or subsystem activation, preemption, resumption, and completion. All data appears in a MATLAB graphic with the data notated by model rates or subsystems and execution time.

- An HTML report that provides statistical data about the execution of each task or atomic subsystem in the running process.

These reports are identical to the reports you see if you use `profile(advdsp_obj, 'execution', 'report')` to view the execution results. For more information about report formats, refer to `profile`. In combination, the reports provide a detailed analysis of how your code runs on the processor.

Use this general process for profiling your project:

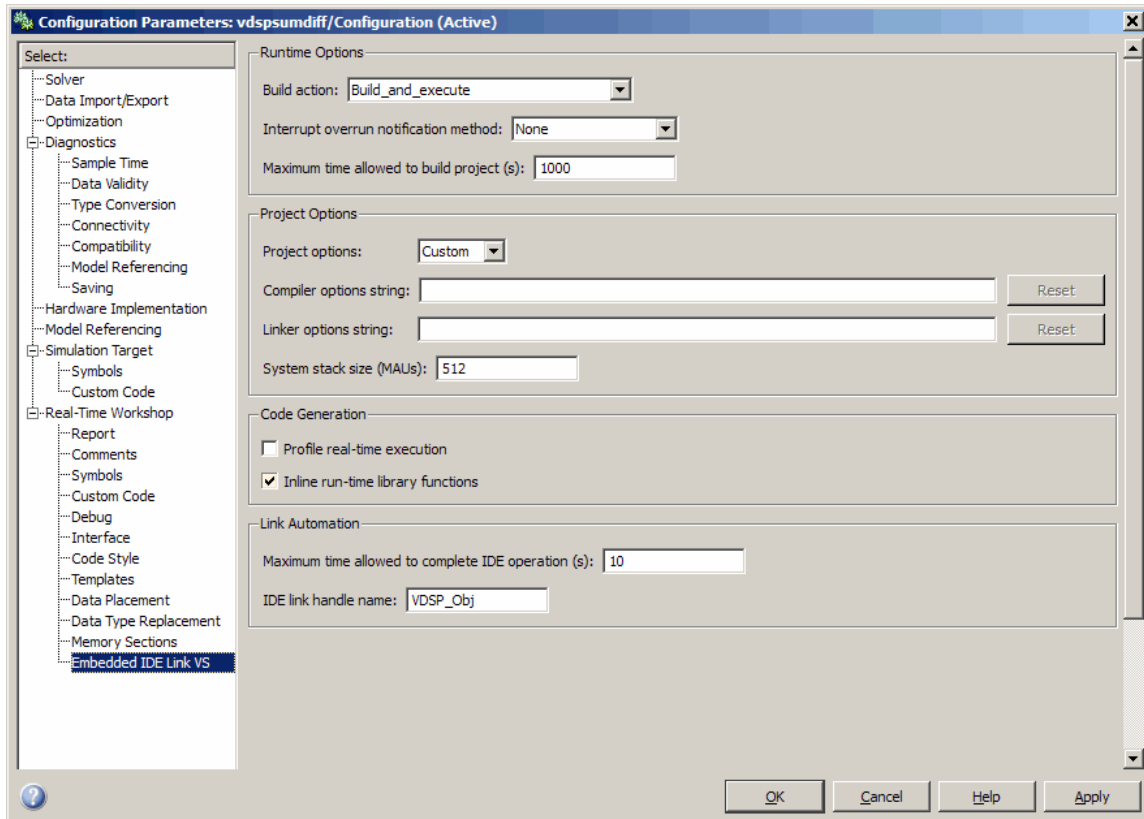
- 1** Create your model in Simulink modeling environment.
- 2** Enable execution profiling in the configuration parameters for your model.
- 3** Run your application.
- 4** Stop your application.
- 5** Get the profiling results with the `profile` function.

The following sections describe profiling your projects in more detail.

## **Profiling Execution by Tasks**


To configure a model to use task execution profiling, perform the following steps:

- 1** Open the Configuration Parameters dialog box for your model.
- 2** Select Embedded IDE Link VS from the **Select** tree. The pane appears as shown in the following figure.



- 3** Select **Profile real-time execution**. The **Profile by** list appears.
- 4** On the **Profile by** list, select **Task** to enable real-time task profiling.
- 5** Assign a name for the object handle in **IDE link handle name**. Embedded IDE Link VS software exports this object to your MATLAB workspace with the name you enter.
- 6** Click **OK** to close the Configuration Parameters dialog box.

To view the execution profile for your model:

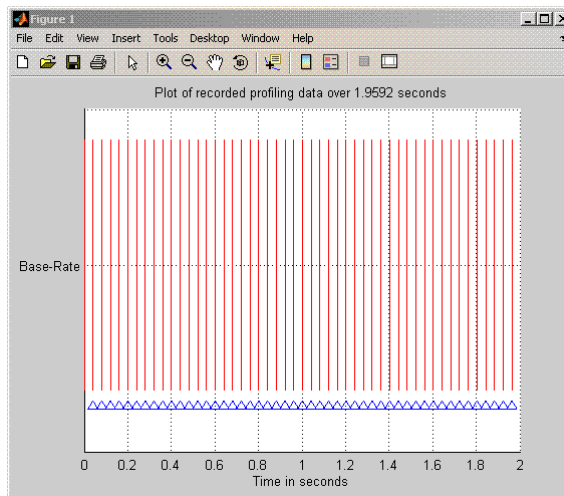
- 1 Click **Incremental build** () on the model toolbar to generate, build, load, and run your code on the processor.
- 2 To stop the running program, select **Debug > Halt** in VisualDSP++ IDE or use `halt(objectname)` from the MATLAB command prompt. Gathering profiling data from a running program may yield incorrect results.
- 3 At the MATLAB command prompt, enter

```
profile(handlename, execution , report )
```

to view the MATLAB software graphic of the execution report and the HTML execution report.

Refer to `profile` for information about other reporting options.

The following figure shows the profiling plot from running an application that has three rates—the base rate and two slower rates. The gaps in the Sub-Rate2 task bars indicate preempted operations.



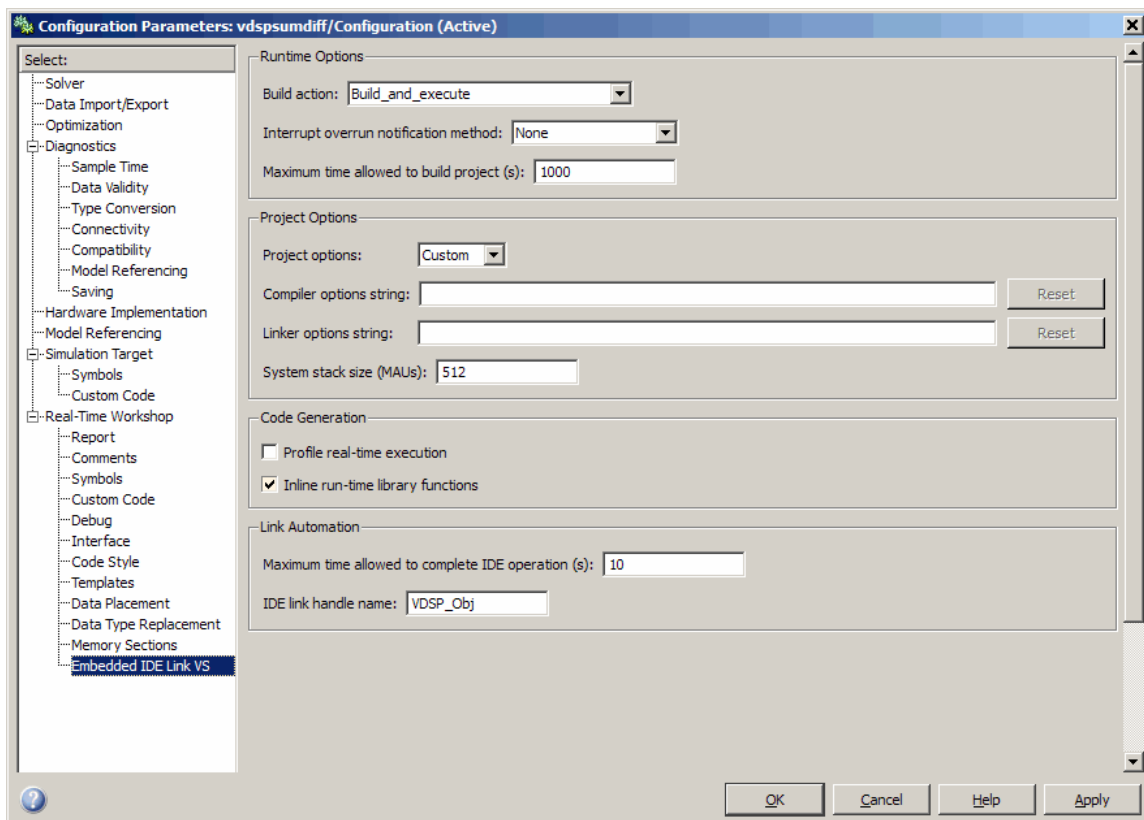
Refer to .

## Profiling Execution By Subsystems

When your models use atomic subsystems, you have the option of profiling your code based on the subsystems along with the tasks.

To configure a model to use subsystem execution profiling, perform the following steps:


- 1 Open the Configuration Parameters dialog box for your model.
- 2 Select Embedded IDE Link VS from the **Select** tree. The pane appears as shown in the following figure.



- 3 Select **Profile real-time execution**.

- 4** On the **Profile by** list, select `Atomic` subsystem to enable real-time subsystem execution profiling.
- 5** Assign a name for the object handle in **IDE link handle name**. Embedded IDE Link VS software exports this object to your MATLAB workspace with the name you enter.
- 6** Click **OK** to close the Configuration Parameters dialog box.

To view the execution profile for your model:

- 1** Click **Incremental build** () on the model toolbar to generate, build, load, and run your code on the processor.
- 2** To stop the running program, select **Debug > Halt** in VisualDSP IDE, or use `halt(objectname)` from the MATLAB command prompt. Gathering profile data from a running program may yield incorrect results.
- 3** At the MATLAB command prompt, enter:

```
profile(handlename, execution , report )
```

to view the MATLAB software graphic of the execution report and the HTML execution report.

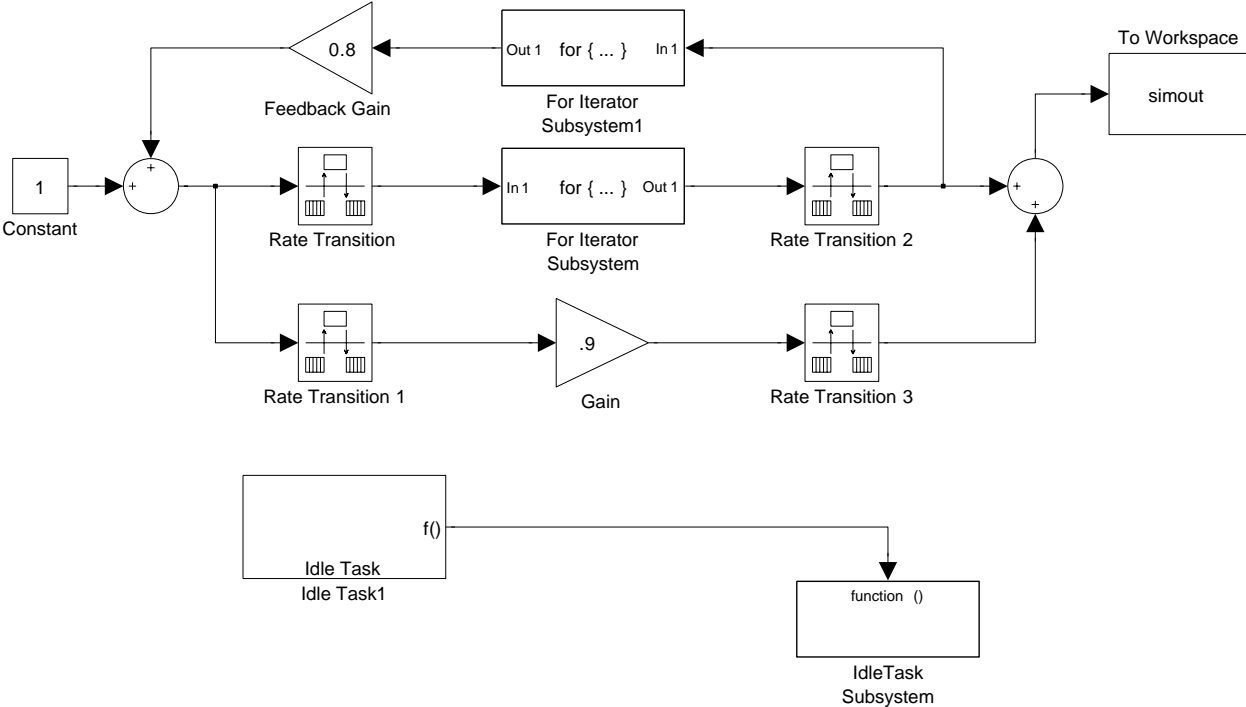
Refer to `profile` for more information.

The following figure shows the profiling plot from running an application that has three subsystems—For Iterator Subsystem, For Iterator Subsystem1, and Idle Task Subsystem.

The following figure presents the model that contains the subsystems reported in the profiling plot.



# Atomic Subsystem Profiling



Atomic Subsystem Profiling Report.

## System Stack Profiling

### In this section...

“Overview” on page 4-18

“Profiling System Stack Use” on page 4-19

### Overview

Along with real-time task execution profiling, the software enables you to determine how your application uses the processor system stack. Using the `profile` method, you can initialize and test the size and usage of the stack. This capability helps you optimize both the size of the stack and how your code uses the stack.

To provide stack profiling, `profile` writes a known pattern to the addresses in the stack. After you run your application for a while, and then stop your application, `profile` examines the contents of the stack addresses. `profile` counts each address that no longer contains the known pattern as used. The total number of address that have been used, compared to the total number of addresses you allocated, becomes the stack usage profile. This profile process does not tell you how often any address was changed by your application.

When you use `profile` to initialize and test the stack operation, the software returns a report that contains information about stack size, usage, addresses, and direction. With this information, you can modify your code to use the stack efficiently. The following program listing shows the stack usage results from running an application on a simulator.

```
profile(cc, 'stack', 'report')
```

```
Maximum stack usage:
```

```
System Stack: 532/1024 (51.95%) MAUs used.
```

```
      name: System Stack  
startAddress: [512    0]  
endAddress: [1535   0]
```

```

stackSize: 1024 MAUs
growthDirection: ascending

```

The following table describes the entries in the report:

Report Entry	Units	Description
System Stack	Minimum Addressable Unit (MAU)	Maximum number of MAUs used and the total MAUs allocated for the stack.
name	String for the stack name	Lists the name assigned to the stack.
startAddress	Decimal address and page	Lists the address of the stack start and the memory page.
endAddress	Decimal address and page	Lists the address of the end of the stack and the memory page.
stackSize	Addresses	Reports number of address locations, in MAUs, allocated for the stack.
growthDirection	Not applicable	Reports whether the stack grows from the lower address to the higher address (ascending) or from higher to lower (descending).

## Profiling System Stack Use

To profile the system stack operation, perform these tasks in order:

- 1 Load an application.
- 2 Set up the stack to enable profiling.

- 3** Run your application.
- 4** Request the stack profile information.

---

**Note** If your application initializes the stack with known values when you run it, stack usage is reported as 100%. The value does not correctly reflect the stack usage.

---

Follow these steps to profile the stack as your application interacts with it. In this example, `cc` is an existing `adivdsp` object.

- 1** Load the application to profile.
- 2** Use the `profile` method with the **setup** input keyword to initialize the stack to a known state.

```
profile(cc, 'stack', 'setup')
```

With the **setup** input argument, `profile` writes a known pattern into the addresses that compose the stack. For all processors, the pattern is `A5`. As long as your application does not write the same pattern to the system stack, `profile` can report the stack usage correctly.

- 3** Run your application.
- 4** Stop your running application. Stack use results gathered from an application that is running may be incorrect.
- 5** Use the `profile` method to capture and view the results of profiling the stack.

```
profile(cc, 'stack', 'report')
```

The following example demonstrates setting up and profiling the stack. The `adivdsp` object `vd` must exist in your MATLAB workspace and your application must be loaded on your processor. This example comes from a SHARC ADSP-2136x simulator.

```
profile(vd, 'stack', 'setup') % Set up processor stack--write A5 to the stack addresses.
```

Maximum stack usage:

System Stack: 0/512 (0%) MAUs used.

```
        name: System Stack
startAddress: [785920      1]
endAddress: [786431      1]
      stackSize: 512 MAUs
growthDirection: ascending
```

```
run(vd)
halt(vd)
profile(vd, 'stack', 'report')
```

Maximum stack usage:

System Stack: 91/512 (17.77%) MAUs used.

```
        name: System Stack
startAddress: [785920      1]
endAddress: [786431      1]
      stackSize: 512 MAUs
growthDirection: ascending
```



# Function Reference

---

Constructor (p. 5-2)	adivdsp object constructor
IDE Operations (p. 5-3)	Work with VisualDSP++ IDE
Processor Operations (p. 5-4)	Control processor
Debug Operations (p. 5-5)	Perform project and code debugging
Read/Write Operations (p. 5-6)	Access memory on the processor
Get Information Operations (p. 5-7)	Project and memory operations
Object Information (p. 5-8)	Object property information
Status Operations (p. 5-9)	Determine processor operation status
Session Operations (p. 5-10)	Manage VisualDSP++ sessions
Verification (p. 5-11)	Functions that help verify code performance

## **Constructor**

adivdsp

Create object to session in  
VisualDSP++ IDE



## IDE Operations

<code>activate</code>	Make specified project, file, or configuration active
<code>add</code>	Add file or data type to active project
<code>build</code>	Build or rebuild current project
<code>cd</code>	Set IDE working directory
<code>close</code>	Close file in IDE window
<code>dir</code>	Files and directories in current IDE window
<code>new</code>	New text, project, or configuration file
<code>open</code>	Open specified file
<code>remove</code>	Remove file from active project in IDE window
<code>save</code>	Save file
<code>visible</code>	Visibility of IDE window

## **Processor Operations**

halt	Halt program execution by processor
load	Load file into processor
profile	Code execution profile and stack usage information
reset	Stop program execution and reset processor
run	Execute program loaded on processor

## Debug Operations

delete

Remove breakpoint

insert

Insert breakpoint in file

## **Read/Write Operations**

read

Read data from processor memory

write

Write data to processor memory  
block

## Get Information Operations

address

Return address and memory type of specified symbol

info

Property names and values for active session

## **Object Information**

display

Properties of adivdsp object

## Status Operations

`isrunning`

Determine whether processor is executing process

`isvisible`

Determine if IDE is running on desktop and window is open

## Session Operations

`listsessions`

List existing sessions



## Verification

profile

Code execution profile and stack  
usage information



# Functions — Alphabetical List

---

# activate

---

**Purpose** Make specified project, file, or configuration active

**Syntax**

```
activate(vd, 'my_project.dpj', 'project')
activate(vd, 'my_file', 'text')
activate(vd, 'my_config', 'buildcfg')
```

**Description** `activate(vd, 'my_project.dpj', 'project')` uses handle `vd` to activate the project named `my_project.dpj` in the IDE. If `my_project.dpj` does not exist in the IDE, MATLAB software issues an error that explains that the specified project does not exist.

VisualDSP++ IDE allows you to have two or more projects with the same name open at the same time, such as `c:\try11\try11.dpj` and `c:\try12\try11.dpj`. If you use the following function to activate the project `try11.dpj` at the command prompt, where you do not provide the full path to the project:

```
activate(vd, 'try11.dpj')
```

Embedded IDE Link VS software cannot tell which project named `try11.dpj` to activate and may not activate the correct one. The following steps describe how the software decides which project to activate.

- 1** Search the current VisualDSP++ IDE directory to find the first project with the specified name. If the search finds the project, the software activates the project and returns.
- 2** If the specified project is not found in the IDE, search the MATLAB path to find a project with this name. If the search finds the project, the software activates the project and returns.
- 3** If Embedded IDE Link VS software search cannot find a project with the specified name in the VisualDSP++ IDE or on the MATLAB path, the software returns an error saying it could not find the specified project.

`activate(vd, 'my_file', 'text')` If the document window is open, this command makes the file `my_file` active in the document window. If the document window is closed, MATLAB returns an error explaining that the document window is closed, and does not activate any file. If the specified file does not exist in the project, MATLAB returns an error. `activate` supports the text file extensions on the following list:

- `.txt`
- `.c`
- `.html`
- `.xml`

`activate(vd, 'my_config', 'buildcfg')` If the IDE application is open, and it contains an active project, `activate` makes build configuration `my_config` the active configuration in the IDE. Otherwise, MATLAB returns an error message stating that there is no active project and it could not activate the specified build configuration.

**See Also**`new``remove`

# add

---

**Purpose** Add file or data type to active project

**Syntax** `add(vd, 'my_file')`

**Description** `add(vd, 'my_file')` adds the file `my_file` to the active project from the current MATLAB working directory. If you do not have an active project in the IDE, MATLAB returns an error message and does not add the file. You can specify the file by name, if the file is in your MATLAB or Embedded IDE Link VS software working directory, or provide the fully qualified path to the file when the file is not in your working directories. To add a file `add.txt` that is in your MATLAB working directory to the IDE, use the following command:

```
add(vd, 'add.txt');
```

where `vd` is the handle for your `vdspLink` object. If the file `add.txt` is not in either working directory, the command changes to include the full path to the file:

```
add(vd, 'fullpathToFile\add.txt');
```

You can add files of all types that the IDE supports. The following table shows the supported file types.

Supported File Type	File Extension
ANSI C/C++ source files	*.cpp, *.c, *.cxx, *.h, *.hpp, *.hxx
Assembly source files	*.asm, *.dsp
Object and Library files	*.obj, *.lib
Linker Command files	*.ldf
VisualDSP++ support file	*.vdk

**See Also** `activate`

`cd`

open

remove

# address

---

**Purpose** Return address and memory type of specified symbol

**Syntax** `a = address(vd, 'symbolstring')`

**Description** `a = address(vd, 'symbolstring')` returns the address and memory type values for the symbol identified by `symbolstring`. For `address` to work, `symbolstring` must be a symbol in the symbol table for your active project. There must be a linker command file (`lcf`) in your project.

**See Also** `read`  
`write`



**Purpose**

Create object to session in VisualDSP++ IDE

**Syntax**

```
vd = adivdsp
vd = adivdsp('propname1',propvalue1,'propname2',propvalue2, ,
    'timeout',value)
vd = adivdsp('my_session')
```

**Description**

vd = adivdsp opens the VisualDSP++ software for the most recent active session, if the IDE is not running. After that, it creates an object vd that references the newly-opened session. If the IDE is running, adivdsp returns object vd that connects to the active session in the IDE.

adivdsp creates an interface between MATLAB software and Analog Devices VisualDSP++ software. If this is the first time you have used adivdsp, you must supply a session name as an input argument (refer to the next syntax).

---

**Note** The output (left-hand argument) object name you provide for adivdsp cannot begin with an underscore, such as `_vd`.

---

vd = adivdsp('sessionname','name','procnum','number',...) returns an object handle vd that you use to interact with a processor in the IDE from MATLAB.

You use the debug methods (refer to “Debug Operations” on page 5-5 for the methods available) with this object to access memory and control the execution of the processor. adivdsp also enables you to create an array of objects for a multiprocessor board, where each object refers to one processor on the board. When vd is an array of objects, any method called with vd as an input argument is sent sequentially to all processors connected to the adivdsp object. VisualDSP++ software provides the communication between the IDE and the processor.

Parameters that you pass as input arguments to adivdsp are interpreted as object property definitions. Each property definition consists of a property name followed by the desired property value

(often called a *PV*, or *property name/property value*, pair). Although you can define any `adivdsp` object property when you create the object, there are several important properties that you must provide during object construction. These properties must be properly delineated when you create the object. The required input arguments are

- `sessionname`—Specifies the session to connect to. This session must exist in the session list. `adivdsp` does not create new sessions. The resulting object refers to a processor in `sessionname`. To see the list of sessions, use `listsessions` at the MATLAB command prompt.
- `procnum`—Specifies the processor to connect to in `sessionname`. The default value for `procnum` is 0 for the first processor on the board. If you omit the `procnum` argument, `adivdsp` connects to the first processor. `procnum` can also be an array of processor indexes on a multiprocessor board. Using an array results in the `adivdsp` object `vd` being an array of handles that correspond to the specified processors.

After you build the `adivdsp` object `vd`, you can review the object property values with `get`, but you cannot modify the `sessionname` and `procnum` property values.

To connect to the active session in IDE, omit the `sessionname` property in the syntax. If you do not pass `sessionname` as an input argument, the object defaults to the active session in the IDE.

Use `listsessions` to determine the number for the desired DSP processor(s). If your IDE session is single processor or to connect to processor zero, you can omit the `procnum` property definition. If `procnum` is not passed as an input argument, the object defaults to `procnum = 0` (zero-based).

```
vd =  
adivdsp('propname1',propvalue1,'propname2',propvalue2, , 'timeout',value)
```

sets the global time-out value to `value` in `vd`. MATLAB waits for the specified time-out value to get a response from the IDE application. If the IDE does not respond within the allotted time-out period, MATLAB exits from the evaluation of this function.

`vd = adivdsp('my_session')` connects to `my_session` if the session exists in the session list and the IDE is not already running. In this case, MATLAB starts VisualDSP++ IDE for the session named `my_session`.

The following list shows some other possible cases and results of using `adivdsp` to construct an object that refers to `my_session`.

- If `my_session` does not exist in the session list and the IDE is not already running, MATLAB returns an error stating that `my_session` does not exist in the session list.
- When `my_session` is the current active session and the IDE is already running, MATLAB connects to the IDE for this session.
- If `my_session` is not the current active session, but exists in the session list, and the IDE is already running, MATLAB displays a dialog box asking if you want to switch to `my_session`. If you choose to switch to `my_session`, all existing handles you have to other sessions in the IDE become invalid. To connect to the other sessions you need to use `adivdsp` to recreate the objects for those sessions.
- If `my_session` does not exist in the session list and the IDE is already running, MATLAB returns an error, explaining that the session `my_session` does not exist in the session list.

## Examples

These examples demonstrate some of the operation of `adivdsp`.

```
vd = adivdsp('sessionname','my_session','procnum',0);
```

returns a handle to the first DSP processor for session `my_session`.

```
vd =  
adivdsp('sessionname','my_multiproc_session','procnum',[0  
1]);
```

returns a 1-by-2 array of handles to the first and second DSP processor for the multiprocessor session `my_multiproc_session`. `vd(1)` is the handle for first processor (0) `vd(2)` is the handle for second processor (1).

# adivdsp

---

`vd = adivdsp` without input arguments constructs the object `vd` with the default property values, returning a handle to the first DSP processor for the active session in the IDE.

`vd = adivdsp('sessionname', 'my_session');` returns a handle to the first DSP processor for the session `my_session`.

## See Also

`listsessions`

**Purpose** Build or rebuild current project

**Syntax**

```
build(vd)
build(vd,timeout)
build(vd,'all')
build(vd,'all',timeout)
```

**Description** `build(vd)` incrementally builds the active project. Incremental builds recompile only source files in your project that you changed or added after the most recent build. `build` uses the file time stamp to determine whether to recompile a file. After recompiling the source files, `build` links the files to make a new program file.

`build(vd,timeout)` incrementally builds the active project with a time limit for how long MATLAB waits for the build process to complete. `timeout` defines the upper limit in seconds for the period the `build` routine waits for confirmation that the build process is finished. If the build process exceeds the time-out period, control returns to MATLAB immediately with a time-out error. Usually, `build` causes the processor to initiate a restart, even if it reaches the time-out limit. The time-out error in MATLAB indicates that confirmation was not received before the time-out period expired. The build action continues. Generally, the build and link process finishes successfully in spite of the time-out error.

`build(vd,'all')` rebuilds all the files in the active project.

`build(vd,'all',timeout)` rebuilds all the files in the active project applying the time-out limit on how long MATLAB waits for the build process to complete.

**See Also**

- `isrunning`
- `open`

# cd

---

**Purpose** Set IDE working directory

**Syntax**  
`wd = cd(vd)`  
`cd (vd, 'directory')`

**Description** `wd = cd(vd)` returns the current IDE working directory, where `vd` is an `adivdsp` object that refers to the VisualDSP++ window, or a vector of objects.

`cd (vd, 'directory')` sets the IDE working directory to `'directory'`. `'directory'` can be a path string relative to your current working directory, or an absolute path. The intended directory must exist. `cd` does not create a new directory. Setting the IDE directory does not affect your MATLAB working directory.

`cd` alters the default directory for `open` and `load`. Loading a new workspace file also changes the working directory for the IDE.

**See Also**  
`dir`  
`load`  
`open`

**Purpose**

Close file in IDE window

---

**Note** `close( , text )` produces a warning and `text` will not be accepted in a future version.

---

**Syntax**

```
close(vd,'filename','filetype')
```

**Description**

`close(vd,'filename','filetype')` closes the file named `'filename'` in the active project in the `vd` IDE window. If `filename` is not an open file in the IDE, MATLAB returns a warning message. When you enter null value `[]` for `filename`, `close` closes the current active file in the IDE. `filename` must match exactly the name of the file to close. If you enter `all` for the filename, `close` closes all files in the project that are of the type specified by `filetype`.

---

**Note** `CLOSE` does not save the file before closing it and it does not prompt you to save the file. You lose changes you made after the most-recent `save` operation. Use `save` to ensure that your changes are preserved before you close the file.

---

Parameter `'filetype'` is optional, with the default value of `text`. Allowed `'filetype'` strings are `project`, `projectgroup`, `text`, and `workspace`. Here are some examples of `close` operation commands. In these examples, `vd` is an `adivdsp` object handle to the IDE.

```
close(vd,'all','project') — Closes all open project files
```

```
close(vd,'my.dpj','project') — Closes the open project my.dpj
```

```
close(vd,[],'project') — Closes the active open project
```

```
close(vd,'all','projectgroup') — Close all open project groups
```

# close

---

`close(vd, 'myg.dpg', 'projectgroup')` — Closes the project group `myg.dpg`

`close(vd, [], 'projectgroup')` — Closes the active project group

`close(vd, 'all', 'text')` — Close all text files

`close(vd, 'text.c', 'text')` — Closes the text file `text.c`

`close(vd, [], 'text')` — Closes the active text file

## See Also

`add`

`open`

`save`



**Purpose** Remove breakpoint

**Syntax**  
`delete(vd,addr)`  
`delete(vd,'filename','linenumber')`  
`delete(vd,'all')`

**Description** `delete(vd,addr)` removes a breakpoint located at the memory address `addr` of the processor. Provide the address input value in hexadecimal format, such as `0x244fc`, or `0x0014`.

`delete(vd,'filename','linenumber')` removes the breakpoint located at the line number `'linenumber'` in the file `'filename'` for the processor.

`delete(vd,'all')` removes all breakpoints in the current project source files.

**See Also** `insert`

# dir

---

**Purpose** Files and directories in current IDE window

**Syntax** `dir(vd)`  
`d = dir(vd)`

**Description** `dir(vd)` lists the files and directories in the IDE working directory, where `vd` is the handle to the IDE. `vd` can be either a single handle, or a vector of handles. When `vd` is a vector, `dir` returns the files and directories for each handle.

`d = dir(vd)` returns the list of files and directories as an M-by-1 structure in `d` with the following fields for each file and directory, as shown in the following table.

Field Name	Description
<code>name</code>	Name of the file or directory.
<code>date</code>	Date of most recent file or directory modification.
<code>bytes</code>	Size of the file in bytes. Directories return 0 for the number of bytes.
<code>isdirectory</code>	0 if this is a file, 1 if this is a directory.

To view the entries in `d`, use an index in the command at the MATLAB prompt, as shown by the following examples.

- `d(3)` returns the third element in the structure.
- `d(10)` returns the tenth element in the structure `d`.
- `d(4).date` returns the `date` field value for the fourth structure element.

**See Also** `cd`  
`open`

**Purpose** Properties of adivdsp object

**Syntax** `display(vd)`

**Description** `display(vd)` displays the properties and property values of the adivdsp object `vd`.

For example, when you create `vd` associated with the session `Testsession` and the processor is the ADSP-BF533, `display(vd)` returns the following information in the MATLAB command window:

```
display(vd)
```

```
ADIVDSP Object:
```

```
Session name      : Testsession
Processor name    : ADSP-BF533
Processor type    : ADSP-BF533
Processor number  : 0
Default timeout   : 10.00 secs
```

**See Also** `get` in the MATLAB Function Reference

# halt

---

**Purpose** Halt program execution by processor

**Syntax** `halt(vd)`  
`halt(vd,timeout)`

**Description** `halt(vd)` stops the program running on the processor. After you issue this command, MATLAB waits for a response from the processor that the processor has stopped. By default, the wait time is 10 seconds. If 10 seconds elapses before the response arrives, MATLAB returns an error. In this syntax, the time-out period defaults to the global time-out period specified in `vd`. Use `get(vd, 'timeout')` to determine the global time-out period. However, the processor usually stops in spite of the error message.

To resume processing after you halt the processor, use `run`. Also, the `read(vd, 'pc')` function can determine the memory address where the processor stopped after you use `halt`.

`halt(vd,timeout)` immediately stops program execution by the processor. After the processor stops, `halt` returns to the host. `timeout` defines, in seconds, how long the host waits for the processor to stop running.

`timeout` defines the maximum time the routine waits for the processor to stop. If the processor does not stop within the specified time-out period, the routine returns with a time-out error.

## Examples

Use one of the provided demonstration programs to show how `halt` works. From the VisualDSP++ demonstration programs, load and run one of the demonstration projects.

At the MATLAB prompt, create an object that refers to a VisualDSP++ IDE session.

```
vd = adivdsp
```

Check whether the program is running on the processor.

```
isrunning(vd)

ans =

    1

vd.isrunning % Alternate syntax for checking the run status.

ans =

    1
halt(vd) % Stop the running application on the processor.
isrunning(vd)

ans =

    0
```

Issuing the halt stops the process on the processor. Checking in VisualDSP++ IDE confirms that the process has stopped.

## See Also

```
isrunning
reset
run
```

# info

---

**Purpose** Property names and values for active session

**Syntax** `objinfo = info(vd)`

**Description** `objinfo = info(vd)` returns the property names and values associated with the active session and the processors for that session. The following table shows the properties `info` returns for `vd` and provides brief descriptions of the properties.

Property Name	Data Type	Description
<code>procname</code>	String	Provides the name of the processor.
<code>proctype</code>	String	Provide the platform name the session uses.
<code>revision</code>	String	Reports the silicon revision of the processor. Does not apply to simulators.

## Examples

When you have an `adivdsp` object `vd`, `info` provides information about the object.

```
vd = adivdsp('sessionname', 'Testsession')
```

```
ADIVDSP Object:
```

```
Session name      : Testsession
Processor name    : ADSP-BF533
Processor type    : ADSP-BF533
Processor number  : 0
Default timeout   : 10.00 secs
```

```
objinfo = info(vd)
```

```
objinfo =
```

```
procname: 'ADSP-BF533'
proctype: 'ADSP-BF533'
```

```
revision: ''
```

```
objinfo.procname
```

```
ans =
```

```
ADSP-BF533
```

**See Also**

```
display
```

```
adivdsp
```

# insert

---

**Purpose** Insert breakpoint in file

**Syntax** `insert(vd,addr)`  
`insert(vd,'filename','linenumber')`

**Description** `insert(vd,addr)` inserts a breakpoint at the memory address specified by the `addr` parameter. `vd` identifies the session that adds the breakpoint.

`insert(vd,'filename','linenumber')` inserts a breakpoint at the line '`linenumber`' in the file '`filename`'.

**See Also** `address`  
`delete`  
`run`



**Purpose** Determine whether processor is executing process

**Syntax** `isrunning(vd)`

**Description** `isrunning(vd)` returns 1 when the processor is executing a program. When the processor is halted, `isrunning` returns 0.

**Examples** `isrunning` lets you determine whether the processor is running. After you load a program to the processor, use `isrunning` to verify that the program is running.

```
vd = adivdsp
```

```
ADIVDSP Object:
```

```
Session name      : Testsession
```

```
Processor name    : ADSP-BF533
```

```
Processor type    : ADSP-BF533
```

```
Processor number  : 0
```

```
Default timeout   : 10.00 secs
```

```
visible(vd,1)
```

```
load(vd, 'adi.dxe', 'program')
```

```
run(vd)
```

```
isrunning(vd)
```

```
ans =
```

```
1
```

```
halt(vd)
```

```
isrunning(vd)
```

```
ans =
```

```
0
```

# isrunning

---

## See Also

halt

load

run

**Purpose** Determine if IDE is running on desktop and window is open

**Syntax** `isvisible(vd)`

**Description** `isvisible(vd)` determines whether the VisualDSP++ IDE is running on the desktop and the window is open. `isvisible` returns either 1 indicating that the IDE is running and the window is open, or 0 indicating that either the IDE is running in the background or is not running.

**See Also** `visible`

# listsessions

---

## **Purpose**

List existing sessions

## **Syntax**

```
list = listsessions  
list = listsessions('verbose')
```

## **Description**

`list = listsessions` returns `list` that contains a listing of all of the sessions by name currently in the development environment.

`list = listsessions('verbose')` adds the optional input argument `verbose`. When you include the `verbose` argument, `listsessions` returns a cell array that contains one row for each existing session. Each row has three columns — processor type, platform name, and processor name.

## **See Also**

`adivdsp`

**Purpose** Load file into processor

**Syntax** `load(vd, 'filename', timeout)`  
`load( , timeout)`

**Description** `load(vd, 'filename', timeout)` transfers file 'my\_file.dxe' to the processor. `filename` can include a full path to the file, or the name of a file that is in the current working directory of VisualDSP++ IDE. Use the function `cd` to check or modify the VisualDSP++ working directory. Use this function only with program files that you created by a VisualDSP++ build process. When you issue the `load` command, the command waits for the period defined by `timeout` in `vd` for the process to complete—ten seconds.

`load( , timeout)` adds the optional parameter `timeout` that defines how long, in seconds, MATLAB waits for the specified load process to complete. If the time-out period expires before the load process returns a completion message, MATLAB generates an error and returns. Usually the program load process works correctly in spite of the error message.

**See Also** `cd`  
`dir`  
`open`

# new

---

## Purpose

New text, project, or configuration file

---

**Note** `new( , 'text')` produces a warning and 'text' will not be accepted in a future version.

---

## Syntax

`new(vd, 'name', 'type')`

## Description

`new(vd, 'name', 'type')` creates a new file, project, or build configuration in the active project. Input argument name specifies the name assigned to identify the new file, project, or configuration.

When you are creating a new file or project, `name` is a filename that can include the full path to the new file. If you omit the path, `new` creates the new file or project in your current VisualDSP++ working directory.

To define the kind of entity to create, `type` accepts the strings shown in the following table.

Type String	Description
<b>text</b>	Create an empty text file in the current session.
<b>project</b>	Create a new executable project in the current session. Sometimes this is called a <i>DSP executable file</i> .
<b>projlib</b>	Create a new library project in the current session.
<b>buildcfg</b>	Create a build configuration in the active project.

## Examples

`new(vd, 'my_project.dpj', 'project', project_type)` creates a new project 'my\_project.dpj' of type `project_type`. The `project_type` argument is optional; the default project type is DSP executable file.

`new(vd, 'my_config', 'buildcfg')` creates a new build configuration, named `my_config`, in the active project.

**See Also**

`activate`

`close`

`save`

# open

**Purpose** Open specified file

---

**Note** `open( , 'text')` produces a warning and 'text' will not be accepted in a future version.

---

**Syntax**

```
open(vd, 'filename')  
open( , 'filetype')
```

**Description** `open(vd, 'filename')` opens file `filename` in the IDE. If you specify the file extension in `filename`, `open` opens the file of that type. If you omit the file extension from the name, `open` assumes the file to open is a text file. The following table presents the possible file types and extensions.

File Type	Extension	Description
<b>text</b>	txt, c, asm, cpp, h, and all file extensions not listed elsewhere in this table	Text file
<b>project</b>	dpj	VisualDSP++ IDE project
<b>projectgroup</b>	dpg	Project group in VisualDSP++ IDE project
<b>workspace</b>	None	Workspace in VisualDSP++ IDE project

If the file to open does not exist in the current project or directory path, MATLAB returns a warning and returns control to MATLAB.

`open( , 'filetype')` identifies the type of file to open. This can be useful when your project includes files of different types that have the same name or when you want to open a project, project group, or workspace. Using the input argument `filetype` overrides the file type defined by the file extension in the file name. The preceding table defines the valid file type extensions.



`open( ,timeout)` adds the optional parameter `timeout` that defines how long, in seconds, MATLAB waits for the specified load process to complete. If the time-out period expires before the load process returns a completion message, MATLAB returns an error. Usually the program load process works correctly in spite of the error message.

**See Also**

`cd`  
`dir`  
`load`  
`new`

# profile

---

**Purpose** Code execution profile and stack usage information

**Syntax**  
`profile(vd, execution , 'report')`  
`profile(vd, 'stack', action)`

**Description** `profile(vd, execution , 'report')` returns execution profile measurements from the generated code. The **report** input argument is required. When you select the **Profile real-time execution** option in the configuration parameters for your model, and then build and run your model on a processor, this function accesses the report of the process execution.

---

**Note** Real-time task execution profiling works with hardware only. Simulators do not support the profiling feature.

---

To use `profile` to assess how your program executes in real-time, complete the following tasks with a Simulink model:

- 1** Enable real-time execution profiling in the configuration parameters and build your model.
- 2** Select whether to profile by task or subsystem.
- 3** Build your model.
- 4** Download your program to the processor.
- 5** Run the program on the processor.
- 6** Stop the running program.
- 7** Use `profile` at the MATLAB command prompt to access the profiling reports.

The HTML report contains the sections described in the following table.

Section Heading	Description
Worst case task turnaround times	Maximum task turnaround time for each task since model execution started.
Maximum number of concurrent overruns for each task	Maximum number of concurrent task overruns since model execution started.
Analysis of profiling data recorded over <i>nnn</i> seconds.	Profiling data was recorded over <i>nnn</i> seconds. The recorded data for task turnaround times and task execution times is presented in the table below this heading.

*Task turnaround time* is the elapsed time between starting and finishing the task. If the task is not preempted, task turnaround time equals the task execution time.

*Task execution time* is the time between task start and finish when the task is actually running. It does not include time during which the task may have been preempted by another task.

---

**Note** Task execution time cannot be measured directly. Task profiling infers the execution time from the task start and finish times, and the intervening periods during which the task was preempted by another task.

---

The execution time calculations do not account for processor time consumed by the scheduler while switching tasks. In cases where preemption occurs, the reported task execution times overestimate the true task execution time.

*Task overruns* occur when a timer task does not complete before the same task is scheduled to run again. Depending on how you configure the real-time scheduler, a task overrun may be handled as a real-time failure. Alternatively, you might allow a small number of task overruns to accommodate cases where a task occasionally takes longer than

normal to complete. If a task overrun occurs, and the same task is scheduled to run again before the first overrun has been cleared, concurrent task overruns are said to have occurred.

Here is a sample of the HTML profiling report—task execution profile report.

`profile(vd, 'stack', action)` returns the CPU stack usage from your application. `action` defines the stack profiling operation and accepts one of the strings in the following table:

<b>action String</b>	<b>Description</b>
<b>setup</b>	Initializes the CPU stack with a known pattern—0xA5 on all processors.
<b>report</b>	Returns the report of the stack usage from running your application.

You cannot assign the stack profile report to an output variable. The MATLAB structure output from profiling the system stack has the elements described in the following table.

<b>Report Entry</b>	<b>Units</b>	<b>Description</b>
System Stack	Minimum Addressable Unit (MAU)	Maximum number of MAUs used and the total MAUs allocated for the stack.
name	String for the stack name	Lists the name assigned to the stack.
startAddress	Decimal address and page	Lists the address of the stack start and the memory page.

Report Entry	Units	Description
endAddress	Decimal address and page	Lists the address of the end of the stack and the memory page.
stackSize	Addresses	Reports number of address locations, in MAUs, allocated for the stack.
growthDirection	Not applicable	Reports whether the stack grows from the lower address to the higher address (ascending) or from higher to lower (descending).

To use `profile` to assess how your program uses the stack, complete the following tasks with a Simulink model or manually written code:

- 1** Build your model with real-time execution profiling enabled in the configuration parameters. Skip this step for custom code.
- 2** Download your program to the processor.
- 3** Run the program on the processor.
- 4** Stop the running program.
- 5** Use `profile` at the MATLAB command prompt to access the profiling reports.

You cannot assign the stack profile report to an output variable. For more information about using stack profiling, refer to “System Stack Profiling” on page 4-18.

# profile

---

## See Also

load

run

**Purpose**

Read data from processor memory

**Syntax**

```
mem = read(vd, address)
mem = read(..., datatype)
mem = read(..., count)
mem = read(..., memorytype)
mem = read(..., timeout)
```

**Description**

`mem = read(vd, address)` returns a block of data values from the memory space of the DSP processor referenced by `vd`. The block to read begins from the DSP memory location given by the input parameter `address`. The data is read starting from `address` without regard to type-alignment boundaries in the DSP. Conversely, the byte ordering defined by the data type is automatically applied.

`address` is a decimal or hexadecimal representation of a memory address in the DSP. In all cases, the full memory address consist of two parts:

- The start address
- The memory type

You can use a numeric vector representation of the address (see below) to define the memory type value explicitly .

Alternatively, the `vd` object has a default memory type value that is applied when the memory type value is not explicitly incorporated in the passed address parameter. In DSP processors with only a single memory type, it is possible to specify all addresses using the abbreviated (implied memory type) format by setting the `vd` object memory type value to zero.

---

**Note** You cannot read data from processor memory while the processor is running.

---

Provide the address parameter either as a numerical value that is a decimal representation of the DSP memory address, or as a string that `read` converts to the decimal representation of the start address. (Refer to function `hex2dec` in the MATLAB Function Reference. `read` uses `hex2dec` to convert the hexadecimal string to a decimal value).

The examples in the following table demonstrate how `read` uses the address parameter:

address Parameter Value	Description
131082	Decimal address specification. The memory start address is 131082 and memory type is 0. This is the same as specifying [131082 0].
[131082 1]	Decimal address specification. The memory start address is 131082 and memory type is 1.
'2000A'	Hexadecimal address specification provided as a string entry. The memory start address is 131082 (converted to the decimal equivalent) and memory type is 0.

It is possible to specify `address` as a cell array. You can use a combination of numbers and strings for the start address and memory type values. For example, the following are valid addresses from cell array `myaddress`:

```
myaddress1 myaddress1{1} = 131072; myaddress1{2} =  
'Program(PM) Memory';  
myaddress2 myaddress2{1} = '20000'; myaddress2{2} =  
'Program(PM) Memory';  
myaddress3 myaddress3{1} = 131072; myaddress3{2} = 0;
```

`mem = read(...,datatype)` where the input argument `datatype` defines the interpretation of the raw values read from DSP memory. Parameter `datatype` specifies the data format of the raw memory image. The data is read starting from `address` without regard to data type alignment



boundaries in the DSP. The byte ordering defined by the data type is automatically applied. This syntax supports the following MATLAB data types:

<b>MATLAB Data Type</b>	<b>Description</b>
double	IEEE® double-precision floating point value
single	IEEE single-precision floating point value
uint8	8-bit unsigned binary integer value
uint16	16-bit unsigned binary integer value
uint32	32-bit unsigned binary integer value
int8	8-bit signed two's complement integer value
int16	16-bit signed two's complement integer value
int32	32-bit signed two's complement integer value

`read` does not coerce data type alignment. Some combinations of address and datatype will be difficult for the processor to use.

`mem = read(...,count)` adds the `count` input parameter that defines the dimensions of the returned data block `mem`. To read a block of multiple data values, specify `count` to determine how many values to read from `address`. `count` can be a scalar value that causes `read` to return a column vector that has `count` values. You can perform multidimensional reads by passing a vector for `count`. The elements in the input vector of `count` define the dimensions of the returned data matrix. The memory is read in column-major order. `count` defines the

dimensions of the returned data array `mem` as shown in the following table.

- `n` — Read `n` values into a column vector.
- `[m,n]` — Read `m`-by-`n` values into `m` by `n` matrix in column-major order.
- `[m,n,...]` — Read a multidimensional matrix `m`-by-`n`-by...of values into an `m`-by-`n`-by...array.

To read a block of multiple data values, specify the input argument `count` that determines how many values to read from address.

`mem = read(...,memorytype)` adds an optional input argument `memorytype`. Object `vd` has a default memory type value 0 that `read` applies if the memory type value is not explicitly incorporated into the passed address parameter.

In processors with only a single memory type, it is possible to specify all addresses using the implied memory type format by setting the `vd` `memorytype` property value to zero. Blackfin and SHARC processors use different memory types. Blackfin processors have one memory type. SHARC processors provide five types. The following table shows the memory types for both processor families.

String Entry for <code>memorytype</code>	Numerical Entry for <code>memorytype</code>	Processor Support
'program(pm) memory'	0	Blackfin and SHARC
'data(dm) memory'	1	SHARC
'data(dm) short word memory'	2	SHARC
'external data(dm) byte memory'	3	SHARC
'boot(prom) memory'	4	SHARC

---

`mem = read(...,timeout)` adds the optional parameter `timeout` that defines how long, in seconds, MATLAB waits for the specified read process to complete. If the time-out period expires before the read process returns a completion message, MATLAB returns an error and returns control to the MATLAB command prompt. Usually the read process works correctly in spite of the error message.

## Examples

This example reads one 16-bit integer from memory on the processor.

```
mlvar = read(vd,131072,'int16')
```

131072 is the decimal address of the data to read.

You can read more than one value at a time. This `read` command returns 100 32-bit integers from the address 0x20000 and plots the result in MATLAB.

```
data = read(vd,'20000','int32',100)
plot(double(data))
```

## See Also

`write`

## remove

---

**Purpose** Remove file from active project in IDE window

**Syntax** `remove(vd, 'filename', 'filetype')`

**Description** `remove(vd, 'filename', 'filetype')` removes the file named `filename` from the active project in the `vd` window of the IDE. If the file does not exist, MATLAB returns a warning and does not remove any files. The `filetype` argument is optional, with the default value of `text`. Possible values for `filetype` are: `project` and `text`.

**See Also**

- `add`
- `cd`
- `open`

**Purpose** Stop program execution and reset processor

**Syntax** `reset(vd,timeout)`

**Description** `reset(vd,timeout)` stops the program executing on the processor and asynchronously performs a processor reset, returning all processor register contents to their power-up settings. `reset` returns immediately after the processor halt.

The `timeout` is an optional parameter, with the default value set to the global default value. The `timeout` determines how long, in seconds, MATLAB waits for the processor to halt.

**See Also** `halt`  
`load`  
`run`

# run

---

**Purpose** Execute program loaded on processor

**Syntax**  
`run(vd)`  
`run(vd, 'runopt')`  
`run(..., timeout)`

**Description** `run(vd)` runs the program file loaded on the referenced processor, returning immediately after the processor starts running. Program execution starts from the location of program counter (PC). Usually, the PC is positioned at the top of the executable file. However, if you stopped a running program with `halt`, the PC may be anywhere in the program. `run` starts the program from the PC current location.

If `vd` references more than one processor, each processor calls `run` in sequence.

`run(vd, 'runopt')` includes the parameter `runopt` that defines the action of the `run` method. The options for `runopt` are listed in the following table.

<b>runopt String</b>	<b>Description</b>
<code>run</code>	Executes the run and waits to confirm that the processor is running, and then returns to MATLAB.
<code>runtohalt</code>	Executes the run but then waits until the processor halts before returning. The halt can be the result of the PC reaching a breakpoint, or by direct interaction with VisualDSP++ IDE, or by the normal program exit process.

`run(..., timeout)` adds input argument `timeout`, to allow you to set the time-out to a value different from the global time-out value. The `timeout` value specifies how long, in seconds, MATLAB waits for the processor to start executing the loaded program before returning.

Most often, the `run` and `runtohalt` options cause the processor to initiate execution, even when a time-out is reached. The time-out

indicates that the confirmation was not received before the time-out period elapsed.

**See Also**

halt

load

reset

# save

---

## Purpose

Save file

---

**Note** `save( , 'text')` produces a warning and 'text' will not be accepted in a future version.

---

## Syntax

```
save(vd, 'filename')  
save(vd, 'filename', 'filetype')
```

## Description

`save(vd, 'filename')` saves the file named `filename` in VisualDSP++ IDE. `filename` must match the name of the file to save and you must include the file extension. You can save only open files. If you specify the `filename` parameter as `all`, every open file of the defined type is saved (refer to the `filetype` parameter in the next syntax). A null input, `[]`, for `filename` or no file name saves the current active file (the file that has focus).

`save(vd, 'filename', 'filetype')` saves the specified file in VisualDSP++ IDE.

`filetype` defines the type of file to save. In the following table you see examples of `save` that use the allowed file type definitions—`project`, `projectgroup`, and `text`.

<b>save Command</b>	<b>Description of save Operation</b>
<code>save(vd, 'all', 'project')</code>	Saves all project files
<code>save(vd, 'my.dpj', 'project')</code>	Saves the project <code>my.dpj</code>
<code>save(vd, [], 'project')</code>	Saves the active project
<code>save(vd, 'all', 'projectgroup')</code>	Saves all project files in the project groups
<code>save(vd, 'myg.dpg', 'projectgroup')</code>	Saves the project group <code>myg.dpg</code>



<b>save Command</b>	<b>Description of save Operation</b>
<code>save(vd,[],'projectgroup')</code>	Saves the projects in the active project group
<code>save(vd,'all','text')</code>	Save all text files
<code>save(vd,'text.c','text')</code>	Saves the text file <code>text.c</code>
<code>save(vd,[],'text')</code>	Save the active text file

**See Also**

adivdsp

close

load

# visible

---

**Purpose** Visibility of IDE window

**Syntax** `visible(vd,state)`

**Description** `visible(vd,state)` sets the visibility state of the IDE window defined by `vd`. Possible values of `state` are 0 for not visible, and 1 for visible.

Setting the state to 1 forces the IDE to be visible on the desktop so you can interact directly with it. Setting to 0 hides the IDE—the IDE runs in the background. In the not visible state, you interact with the IDE from the MATLAB command line. When you create an `adivdsp` object, the IDE visibility is set to 0 and the IDE is not visible.

**See Also** `info`  
`isvisible`

**Purpose** Write data to processor memory block

**Syntax**

```
mem = write(vd,address,data)
mem = write(...,datatype)
mem = write(...,memorytype)
mem = write(...,timeout)
```

**Description** `mem = write(vd,address,data)` writes `data`, a collection of values, to the memory space of the DSP processor referenced by `vd`. Input argument `data` is a scalar, vector or array of values to write to the memory of the processor. The block to write begins from the DSP memory location given by the input parameter `address`.

The data is written starting from `address` without regard to type-alignment boundaries in the DSP. Conversely, the byte ordering of the data type is automatically applied.

---

**Note** You cannot write data to processor memory while the processor is running.

---

`address` is a decimal or hexadecimal representation of a memory address in the processor. In all cases, the full memory address consist of two parts: the start address and the memory type. The memory type value can be explicitly defined using a numeric vector representation of the address (see below).

Alternatively, the `vd` object has a default memory type value which is applied if the memory type value is not explicitly incorporated into the passed address parameter. In DSP processors with only a single memory type, by setting the `vd` object memory type value to zero it is possible to specify all addresses using the abbreviated (implied memory type) format.

You provide the address parameter either as a numerical value that is a decimal representation of the DSP memory address, or as a string that `write` converts to the decimal representation of the start address.

# write

(Refer to function `hex2dec` in the MATLAB Function Reference that read uses to convert the hexadecimal string to a decimal value).

To demonstrate how `write` uses `address`, here are some examples of the `address` parameter:

<b>address Parameter Value</b>	<b>Description</b>
131082	Decimal address specification. The memory start address is 131082 and memory type is 0. This is the same as specifying [131082 0].
[ 131082 1 ]	Decimal address specification. The memory start address is 131082 and memory type is 1.
'2000A'	Hexadecimal address specification provided as a string entry. The memory start address is 131082 (converted to the decimal equivalent) and memory type is 0.

It is possible to specify `address` as a cell array, in which case you can use a combination of numbers and strings for the start address and memory type values. For example, the following are valid addresses from cell array `myaddress`:

```
myaddress1 myaddress1{1} = 131072; myaddress1{2} =  
'Program(PM) Memory';  
myaddress2 myaddress2{1} = '20000'; myaddress2{2} =  
'Program(PM) Memory';  
myaddress3 myaddress3{1} = 131072; myaddress3{2} = 0;
```

`mem = write(...,datatype)` where the input argument `datatype` defines the interpretation of the raw values written to DSP memory. Parameter `datatype` specifies the data format of the raw memory image. The data is written starting from `address` without regard to data type alignment boundaries in the DSP. The byte ordering of the data type is automatically applied. The following MATLAB data types are supported:

<b>MATLAB Data Type</b>	<b>Description</b>
double	IEEE double-precision floating point value
single	IEEE single-precision floating point value
uint8	8-bit unsigned binary integer value
uint16	16-bit unsigned binary integer value
uint32	32-bit unsigned binary integer value
int8	8-bit signed two's complement integer value
int16	16-bit signed two's complement integer value
int32	32-bit signed two's complement integer value

`write` does not coerce data type alignment. Some combinations of `address` and `datatype` will be difficult for the processor to use.

`mem = write(...,memorytype)` adds an optional input argument `memorytype`. Object `vd` has a default memory type value 0 that `write` applies if the memory type value is not explicitly incorporated into the passed address parameter. In processors with only a single memory type, it is possible to specify all addresses using the implied memory type format by setting the `vd` `memorytype` property value to zero.

Blackfin and SHARC use different memory types. Blackfin processors have one memory type. SHARC processors provide five types. The following table shows the memory types for both processor families.

# write

String Entry for memorytype	Numerical Entry for memorytype	Processor Support
'program(pm) memory'	0	Blackfin and SHARC
'data(dm) memory'	1	SHARC
'data(dm) short word memory'	2	SHARC
'external data(dm) byte memory'	3	SHARC
'boot(prom) memory'	4	SHARC

`mem = write(...,timeout)` adds the optional parameter `timeout` that defines how long, in seconds, MATLAB waits for the specified write process to complete. If the `timeout` period expires before the write process returns a completion message, MATLAB displays an error and returns control to the command prompt. Usually the process works correctly in spite of the error message.

## Examples

These three syntax examples demonstrate how to use `write` in some common ways. In the first example, write an array of 16-bit integers to location [131072 1].

```
write(vd,[131072 1],int16([1:100]));
```

Now write a single-precision IEEE floating point value (32-bits) at address 2000A(Hex).

```
write(vd,'2000A',single(23.5));
```

For the third example, write a 2-D array of integers in row-major format (standard ANSI C code programming format) at address 131072 (decimal).

```
mlarr = int32([1:10;101:110]);  
write(vd,131072,mlarr);
```

**See Also**

hex2dec in the MATLAB Function Reference  
read

**write**

---



# Block Reference

---

Blackfin DSP Support (p. 7-2)

Work with Blackfin processors

Core Support (p. 7-3)

Work with Analog Devices processors

SHARC DSP Support (p. 7-4)

Work with SHARC processors

TigerSHARC DSP Support (p. 7-5)

Work with TigerSHARC processors

## **Blackfin DSP Support**

Blackfin Hardware Interrupt

Target Preferences

Generate Interrupt Service Routine

Configure model for Analog Devices  
processor

## Core Support

Idle Task

Memory Allocate

Memory Copy

Create free-running task

Allocate memory section on Blackfin,  
SHARC, TigerSHARC processors

Copy to and from memory section

## **SHARC DSP Support**

SHARC Hardware Interrupt

Target Preferences

Generate Interrupt Service Routine

Configure model for Analog Devices  
processor

## **TigerSHARC DSP Support**

Target Preferences

Configure model for Analog Devices  
processor

TigerSHARC Hardware Interrupt

Generate Interrupt Service Routine



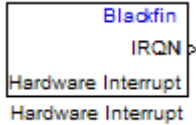
# Blocks — Alphabetical List

---

# Blackfin Hardware Interrupt

**Purpose** Generate Interrupt Service Routine

**Library** Blackfin DSP Support in Embedded IDE Link VS software



**Description** Create interrupt service routines (ISR) in the software generated by the build process. When you incorporate this block in your model, code generation results in ISRs on the processor that run the processes that are downstream from the this block or an Idle Task block connected to this block. Core interrupts trigger the ISRs. System interrupts trigger the core interrupts. In the following figure, you see the mapping possibilities between system interrupts and core interrupts.

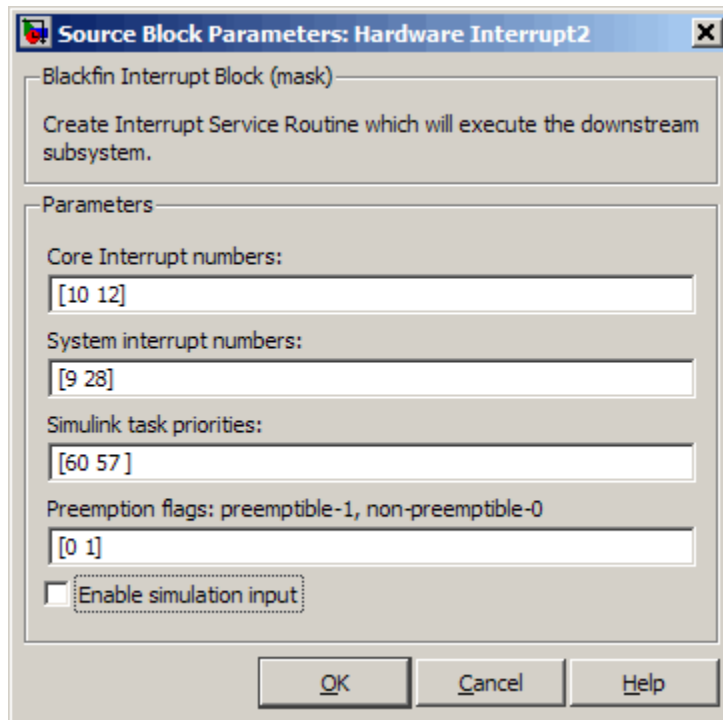
## Interrupts

Blackfin processors support the interrupt numbers shown in the following table. Some Blackfin processors do not support all of the system interrupts.

Interrupt Description	Valid Range in Embedded IDE Link VS Software
Core interrupt numbers	7 to 14
System interrupt numbers	0 to 31 (The upper end value depends on the processor. May be less than 31.)



## Dialog Box



### Core interrupt numbers

Specify a vector of one or more interrupt numbers for the interrupt service routines (ISR) to install. The valid range is 7 to 14, where 7 through 13 are hardware driven, and 14 is software driven. Core interrupts numbered 0 to 6 are reserved and cannot be entered in this field.

The width of the block output signal corresponds to the number of interrupt values you specify in this field. Triggering of each ISR depends on the core interrupt value, the system interrupt value, and the preemption flag you enter for each interrupt. These three values define how the code and processor respond to interrupts during asynchronous scheduler operations.

# Blackfin Hardware Interrupt

---

## System interrupt numbers

System interrupt numbers identify system interrupts to map to core interrupts. Enter one or more values as a vector. The valid range is 0 through 31, although the valid range depends on your processor. Some processors do not support the full range of 32 system interrupts. Embedded IDE Link VS software does not test for valid system interrupt values. You must verify that your values are valid for your processor. You must specify at least one system interrupt number to use asynchronous scheduling.

The block maps the first interrupt value in this field to the first core interrupt value you enter in **Core interrupt numbers**, it maps the second system interrupt value to the second core interrupt value, and so on until it has mapped all of the system interrupt values to core interrupt values. You can map more than one system interrupt to the same core interrupt. For example, when you enter [7 8 8 9] in **Core interrupt numbers** and [9 11 14 28] in this parameter, the software maps system interrupts 11 and 14 to the core interrupt 8. You must enter the same number of system interrupts as core interrupts.

When you trigger one of the system interrupts in this field, the block triggers the ISR associated with the core interrupt that is mapped to the system interrupt.

## Simulink task priorities

Each output of the Hardware Interrupt block drives a downstream block (for example, a function call subsystem). Simulink model task priority specifies the priority of the downstream blocks. Specify an array of priorities corresponding to the interrupt numbers entered in **Interrupt numbers**.

Proper code generation requires rate transition code (see Rate Transitions and Asynchronous Blocks). The task priority values ensure absolute time integrity when the asynchronous task must obtain real time from its base rate or its caller. Typically, assign

priorities for these asynchronous tasks that are higher than the priorities assigned to periodic tasks.

## **Preemption flags preemptible – 1, non-preemptible – 0**

Higher priority interrupts can preempt interrupts that have lower priority. To control this preemption, use the preemption flags to specify whether an interrupt can be preempted.

- Entering 1 indicates the corresponding core interrupt can be preempted.
- Entering 0 indicates the corresponding interrupt cannot be preempted.

When **Core interrupt numbers** contains more than one interrupt priority, you can assign different preemption flags to each interrupt by entering a vector of preemption flag values that correspond to the order of the interrupts in **Core interrupt numbers**. If **Core interrupt numbers** contains more than one interrupt, and you enter only one flag value in this field, that status applies to all interrupts.

For example, the default settings [0 1] indicate that the interrupt with value 10 in **Core interrupt numbers** is not preemptible and the value 12 interrupt can be preempted.

## **Enable simulation input**

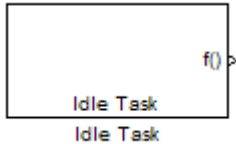
When you select this option, Simulink software adds an input port to the Hardware Interrupt block. This port receives input only during simulation. Connect one or more simulated interrupt sources to the simulation input.

# Idle Task

---

**Purpose** Create free-running task

**Library** DSP Core Support in Embedded IDE Link VS



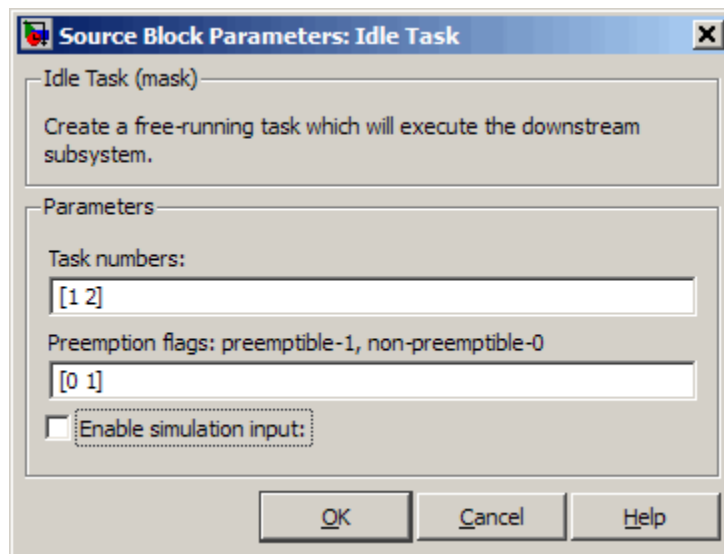
**Description** The Idle Task block, and the subsystem connected to it, specify one or more functions to execute as background tasks. All tasks executed through the Idle Task block are of the lowest priority, lower than that of the base-rate task.

## Vectorized Output

The block output comprises a set of vectors—the task numbers vector and the preemption flag or flags vector. Any preemption flag vector must be the same length as the number of tasks vector unless the preemption flag vector has only one element. The value of the preemption flag determines whether a given interrupt (and corresponding task) is preemptible. Preemption overrides prioritization. A lower-priority, nonpreemptible task can preempt a higher-priority, preemptible task.

When the preemption flag vector has only one element, that element value applies to all functions in the downstream subsystem as defined by the task numbers in the task number vector. If the preemption flag vector has the same number of elements as the task number vector, each task defined in the task number vector has a preemption status defined by the value of the corresponding element in the preemption flag vector.

## Dialog Box



### Task numbers

Identifies the created tasks by number. Enter as many tasks as you need by entering a vector of integers. The default values are [ 1, 2 ], to indicate that the downstream subsystem has two functions.

The values you enter determine the execution order of the functions in the downstream subsystem, while the number of values you enter corresponds to the number of functions in the downstream subsystem.

Enter a vector containing the same number of elements as the number of functions in the downstream subsystem. This vector can contain no more than 16 elements, and the values must be from 0 to 15 inclusive.

The value of the first element in the vector determines the order in which the first function in the subsystem is executed. Similarly,

the value of the second element determines the order in which the second function in the subsystem is executed, and so on.

For example, entering the vector [2,3,1] in this field indicates that there are three functions to be executed, and that the third function is executed first, the first function is executed second, and the second function is executed third. After all functions are executed, the Idle Task block cycles back and repeats the execution of the functions in the same order.

### Preemption flags

Higher-priority interrupts can preempt interrupts that have lower priority. To allow you to control preemption, use the preemption flags to specify whether an interrupt can be preempted.

- Entering 1 indicates that the interrupt can be preempted.
- Entering 0 indicates the interrupt cannot be preempted.

When **Task numbers** contains more than one task, you can assign different preemption flags to each task by entering a vector of flag values, corresponding to the order of the tasks in **Task numbers**. If **Task numbers** contains more than one task, and you enter only one flag value in this field, that preemption setting applies to all tasks.

For example, the default settings [0 1] indicate the task with priority 1 in **Task numbers** is not preemptible, and the priority 2 task can be preempted.

### Enable simulation input

When you select this option, Simulink software adds an input port to the Idle Task block. This port receives input only during simulation. Connect one or more simulated interrupt sources to the simulation input.

---

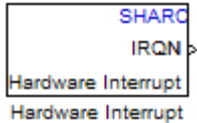
**Note** Select this check box to test asynchronous interrupt processing behavior in Simulink software models.

---

# SHARC Hardware Interrupt

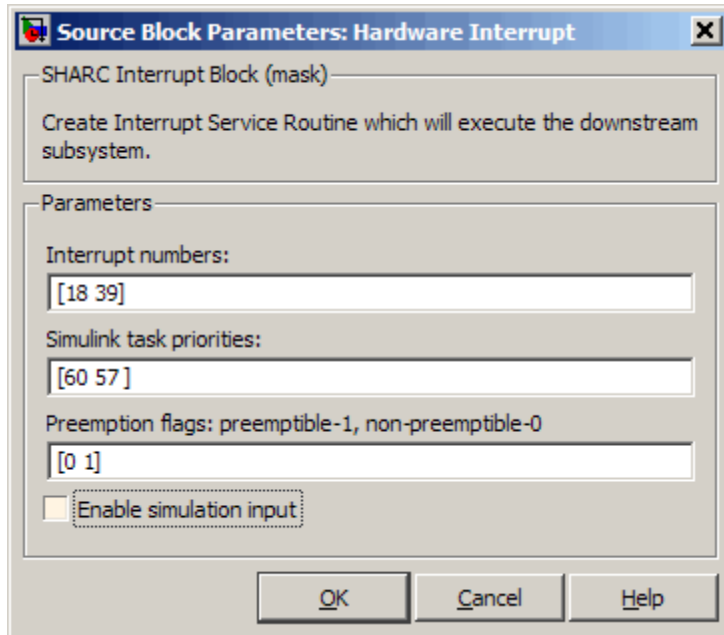
**Purpose** Generate Interrupt Service Routine

**Library** SHARC DSP Support in Embedded IDE Link VS



**Description** Create interrupt service routines (ISR) in the software generated by the build process. When you incorporate this block in your model, code generation results in ISRs on the processor that either run the processes that are downstream from this block or trigger an Idle Task block connected to this block.

## Dialog Box





## Interrupt numbers

Specify an array of interrupt numbers for the interrupts to install. The valid ranges are 8-36 and 38-40.

The width of the block output signal corresponds to the number of interrupt numbers specified in this field. The values in this field and the preemption flag entries in **Preemption flags: preemptible-1, non-preemptible-0** define how the code and processor handle interrupts during asynchronous scheduler operations.

## Simulink task priorities

Each output of the Hardware Interrupt block drives a downstream block (for example, a function call subsystem). Simulink model task priority specifies the priority of the downstream blocks. Specify an array of priorities corresponding to the interrupt numbers entered in **Interrupt numbers**.

Proper code generation requires rate transition code (refer to Rate Transitions and Asynchronous Blocks in the Real-Time Workshop documentation). The task priority values ensure absolute time integrity when the asynchronous task must obtain real time from its base rate or its caller. Typically, assign priorities for these asynchronous tasks that are higher than the priorities assigned to periodic tasks.

## Preemption flags preemptible – 1, non-preemptible – 0

Higher-priority interrupts can preempt interrupts that have lower priority. To allow you to control preemption, use the preemption flags to specify whether an interrupt can be preempted.

- Entering 1 indicates that the interrupt can be preempted.
- Entering 0 indicates the interrupt cannot be preempted.

When **Interrupt numbers** contains more than one interrupt value, you can assign different preemption flags to each interrupt by entering a vector of flag values to correspond to the order of the interrupts in **Interrupt numbers**. If **Interrupt numbers**

# SHARC Hardware Interrupt

---

contains more than one interrupt, and you enter only one flag value in this field, that status applies to all interrupts.

In the default settings [0 1], the interrupt with priority 18 in **Interrupt numbers** is not preemptible and the priority 39 interrupt can be preempted.

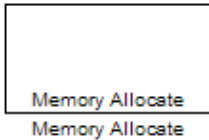
## **Enable simulation input**

When you select this option, Simulink software adds an input port to the Hardware Interrupt block. This port is used in simulation only. Connect one or more simulated interrupt sources to the simulation input.

**Purpose** Allocate memory section on Blackfin, SHARC, TigerSHARC processors

**Library** Core Support in Embedded IDE Link VS

## Description



On your ADI processor, this block directs the VisualDSP++ compiler to allocate memory for a new variable you specify. Parameters in the block dialog box let you specify the variable name, the alignment of the variable in memory, the data type of the variable, and other features that fully define the memory required.

The block does not verify whether the entries for your variable are valid, such as checking the variable name, data type, or section. You must ensure that all variable names are valid, that they use valid data types, and that all section names you specify are valid as well.

The block does not have input or output ports. It only allocates a memory location. You do not connect it to other blocks in your model.

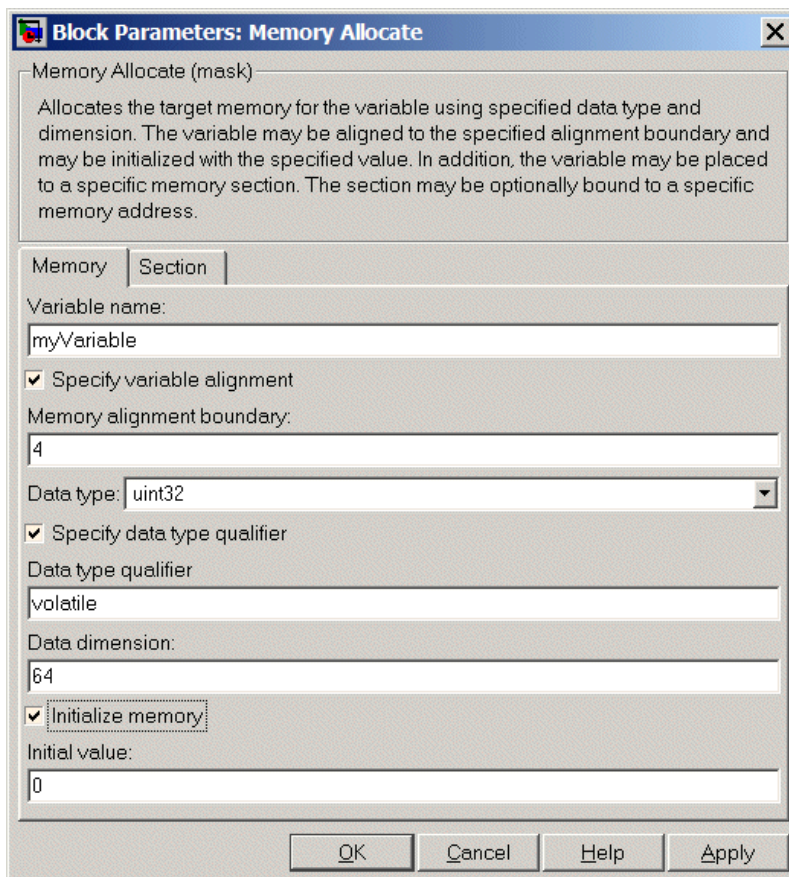
## Dialog Box

The block dialog box comprises multiple tabs:

- **Memory** — Allocate the memory for storing variables. Specify the data type and size.
- **Section** — Specify the memory section in which to allocate the variable.

The dialog box images show all of the available parameters enabled. Some of the parameters shown do not appear until you select one or more other parameters.

# Memory Allocate



The following sections describe the contents of each pane in the dialog box.

## Memory Parameters

**Block Parameters: Memory Allocate**

Memory Allocate (mask)

Allocates the target memory for the variable using specified data type and dimension. The variable may be aligned to the specified alignment boundary and may be initialized with the specified value. In addition, the variable may be placed to a specific memory section. The section may be optionally bound to a specific memory address.

Memory | Section

Variable name:  
myVariable

Specify variable alignment

Memory alignment boundary:  
4

Data type: uint32

Specify data type qualifier

Data type qualifier  
volatile

Data dimension:  
64

Initialize memory

Initial value:  
0

OK Cancel Help Apply

You find the following memory parameters on this tab.

### Variable name

Specify the name of the variable to allocate. The variable is allocated in the generated code.

# Memory Allocate

---

## **Specify variable alignment**

Select this option to direct the compiler to align the variable in **Variable name** to an alignment boundary. When you select this option, the **Memory alignment boundary** parameter appears so you can specify the alignment. Use this parameter and **Memory alignment boundary** when your processor requires this feature.

## **Memory alignment boundary**

After you select **Specify variable alignment**, this option enables you to specify the alignment boundary in bytes. If your variable contains more than one value, such as a vector or an array, the elements are aligned according to rules applied by the compiler.

## **Data type**

Defines the data type for the variable. Select from the list of types available.

## **Specify data type qualifier**

Selecting this enables **Data type qualifier** so you can specify the qualifier to apply to your variable.

## **Data type qualifier**

After you select **Specify data type qualifier**, you enter the desired qualifier here. `Volatile` is the default qualifier. Enter the qualifier you need as text. Common qualifiers are `static` and `register`. The block does not check for valid qualifiers.

## **Data dimension**

Specifies the number of elements of the type you specify in **Data type**. Enter an integer here for the number of elements.

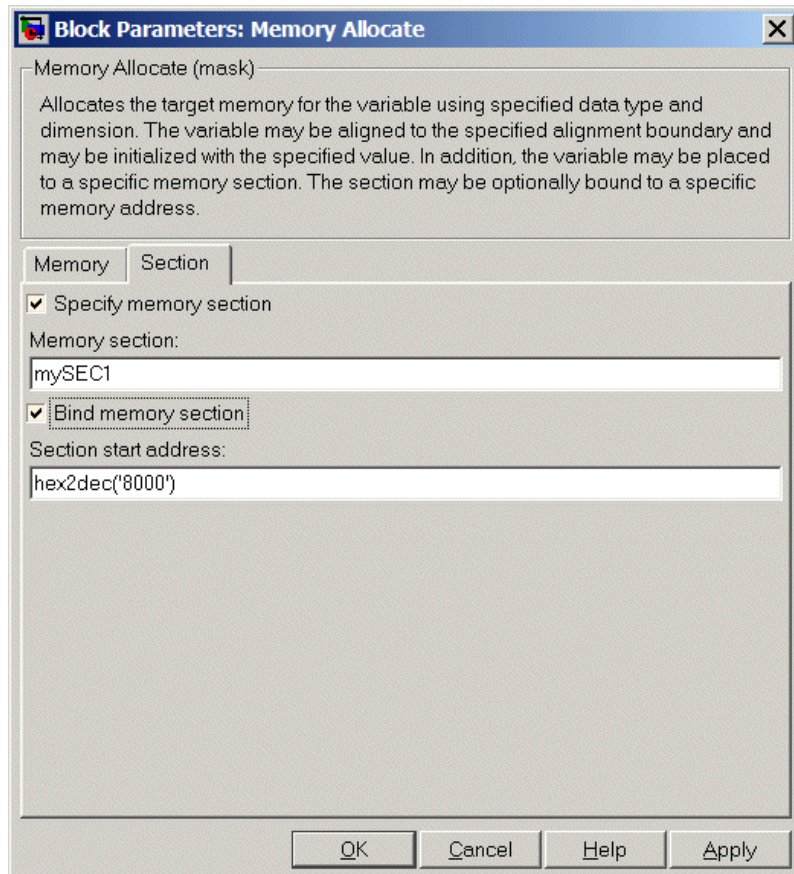
## **Initialize memory**

Directs the block to initialize the memory location to a fixed value before processing.

## **Initial value**

Specifies the initialization value for the variable. At run time, the block sets the memory location to this value.

## Section Parameters



Parameters on this pane specify the section in memory to store the variable.

### Specify memory section

Selecting this parameter enables you to specify the memory section to allocate space for the variable. Enter either one of the

# Memory Allocate

---

standard memory sections or a custom section that you declare elsewhere in your code.

## **Memory section**

Identify a specific memory section to allocate the variable in **Variable name**. Verify that the section has sufficient space to store your variable. After you specify a memory section by selecting **Specify memory section** and entering the section name in **Memory section**, use **Bind memory section** to bind the memory section to a location.

## **See Also**

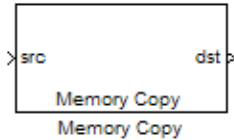
Memory Copy



**Purpose** Copy to and from memory section

**Library** Core Support in Embedded IDE Link VS

**Description** In generated code, this block copies variables or data from and to target memory as configured by the block parameters. Your model can contain as many of these blocks as you require to manipulate memory on your target.



Each block works with one variable, address, or set of addresses provided to the block. Parameters for the block let you specify both the source and destination for the memory copy, as well as options for initializing the memory locations.

Using parameters provided by the block, you can change options like the memory stride and offset at run time. In addition, by selecting various parameters in the block, you can write to memory at program initialization, at program termination, and at every sample time. The initialization process occurs once, rather than occurring for every read and write operation.

With the custom source code options, the block enables you to add custom ANSI C source code before and after each memory read and write (copy) operation. You can use the custom code capability to lock and unlock registers before and after accessing them. For example, some processors have registers that you may need to unlock and lock with EALLOW and EDIS macros before and after your program accesses them.

## Block Operations

This block performs operations at three periods during program execution—initialization, real-time operations, and termination. With the options for setting memory initialization and termination, you control when and how the block initializes memory, copies to and from memory, and terminates memory operations. The parameters enable you to turn on and off memory operations in all three periods independently.

# Memory Copy

---

Used in combination with the Memory Allocate block, this block supports building custom device drivers, such as PCI bus drivers or codec-style drivers, by letting you manipulate and allocate memory. This block does not require the Memory Allocate block to be in the model.

In a simulation, this block does not perform any operation. The block output is not defined.

## Copy Memory

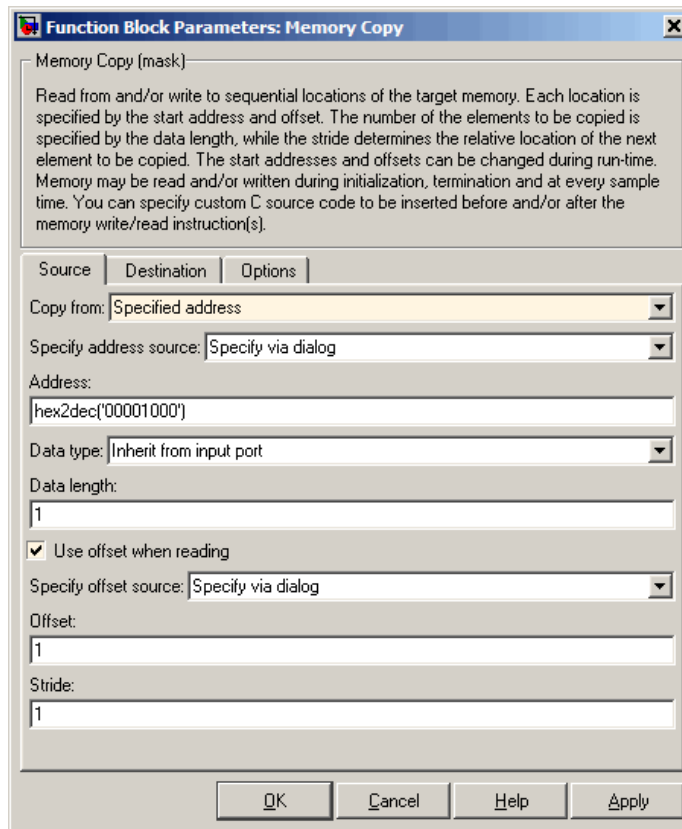
When you employ this block to copy an individual data element from the source to the destination, the block copies the element from the source in the source data type, and then casts the data element to the destination data type as provided in the block parameters.

### Dialog Box

The block dialog box contains multiple tabs:

- **Source** — Identifies the sequential memory location to copy from. Specify the data type, size, and other attributes of the source variable.
- **Destination** — Specify the memory location to copy the source to. Here you also specify the attributes of the destination.
- **Options** — Select various parameters to control the copy process.

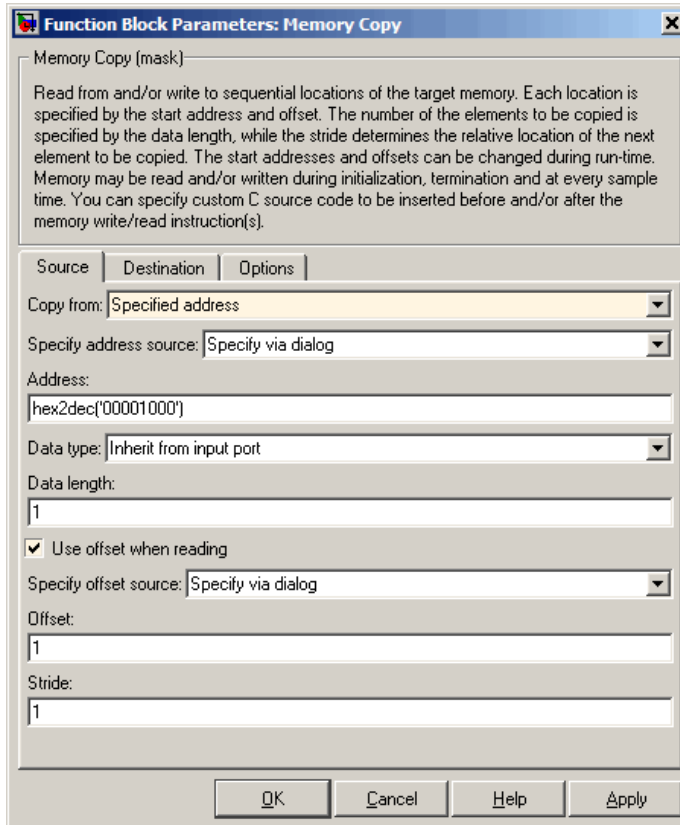
The dialog box images show many of the available parameters enabled. Some parameters shown do not appear until you select one or more other parameters. Some parameters are not shown in the figures, but the text describes them and how to make them available.



Sections that follow describe the parameters on each tab in the dialog box.

# Memory Copy

## Source Parameters



### Copy from

Select the source of the data to copy. Choose one of the entries on the list:

- **Input port** — This source reads the data from the block input port.
- **Specified address** — This source reads the data at the specified location in **Specify address source** and **Address**.

- Specified source code symbol — This source tells the block to read the symbol (variable) you enter in **Source code symbol**. When you select this copy from option, you enable the **Source code symbol** parameter.

---

**Note** If you do not select the **Input port** option for **Copy from**, you must change the **Data type** parameter setting from the default **Inherit from input port** to one of the data types on the **Data type** list. If you do not make the change, you receive an error message that the data type cannot be inherited because the input port does not exist.

---

Depending on the choice you make for **Copy from**, you see other parameters that let you configure the source of the data to copy.

### Specify address source

This parameter directs the block to get the address for the variable either from an entry in **Address** or from the input port to the block. Select either **Specify via dialog** or **Input port** from the list. Selecting **Specify via dialog** activates the **Address** parameter for you to enter the address for the variable.

When you select **Input port**, the port label on the block changes to **&src**, indicating that the block expects the address to come from the input port. Being able to change the address dynamically lets you use the block to copy different variables by providing the variable address from an upstream block in your model.

### Source code symbol

Specify the symbol (variable) in the source code symbol table to copy. The symbol table for your program must include this symbol. The block does not verify that the symbol exists and uses valid syntax. Enter a string to specify the symbol exactly as you use it in your code.

# Memory Copy

---

## Address

When you select **Specify via dialog** for the address source, you enter the variable address here. Addresses should be in decimal form. Enter either the decimal address or the address as a hexadecimal string with single quotations marks and use `hex2dec` to convert the address to the proper format. The following example converts `0x1000` to decimal form.

```
4096 = hex2dec('1000');
```

For this example, you could enter either `4096` or `hex2dec('1000')` as the address.

## Data type

Use this parameter to specify the type of data that your source uses. The list includes the supported data types, such as `int8`, `uint32`, and `Boolean`, and the option `Inherit` from input port for inheriting the data type for the variable from the block input port.

## Data length

Specifies the number of elements to copy from the source location. Each element has the data type specified in **Data type**.

## Use offset when reading

When you are reading the input, use this parameter to specify an offset for the input read. The offset value is in elements with the assigned data type. The **Specify offset source** parameter becomes available when you check this option.

## Specify offset source

The block provides two sources for the offset — `Input port` and `Specify via dialog`. Selecting `Input port` configures the block input to read the offset value by adding an input port labeled `src ofs`. This port enables your program to change the offset dynamically during execution by providing the offset value as an input to the block. If you select `Specify via dialog`, you enable the **Offset** parameter in this dialog box so you can enter the offset to use when reading the input data.

## Offset

**Offset** tells the block whether to copy the first element of the data at the input address or value, or skip one or more values before starting to copy the input to the destination. **Offset** defines how many values to skip before copying the first value to the destination. Offset equal to one is the default value and **Offset** accepts only positive integers of one or greater.

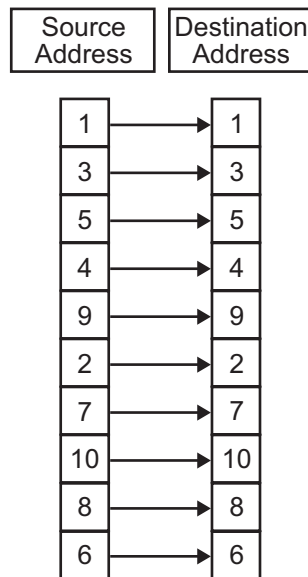
## Stride

Stride lets you specify the spacing for reading the input. By default, the stride value is one, meaning the generated code reads the input data sequentially. When you add a stride value that is not equal to one, the block reads the input data elements not sequentially, but by skipping spaces in the source address equal to the stride. **Stride** must be a positive integer.

The next two figures help explain the stride concept. In the first figure you see data copied without any stride. Following that figure, the second figure shows a stride value of two applied to reading the input when the block is copying the input to an output location. You can specify a stride value for the output with parameter **Stride** on the **Destination** pane. Compare stride with offset to see the differences.

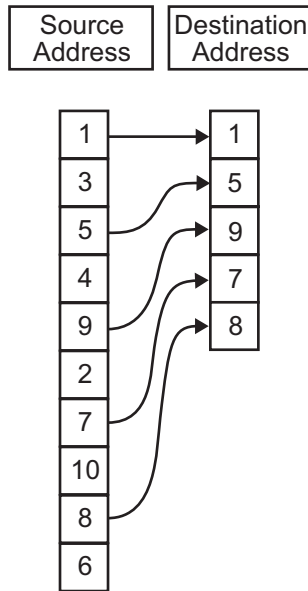
# Memory Copy

---



Input Stride = 1  
Output Stride = 1  
Number of Elements Copied = 10

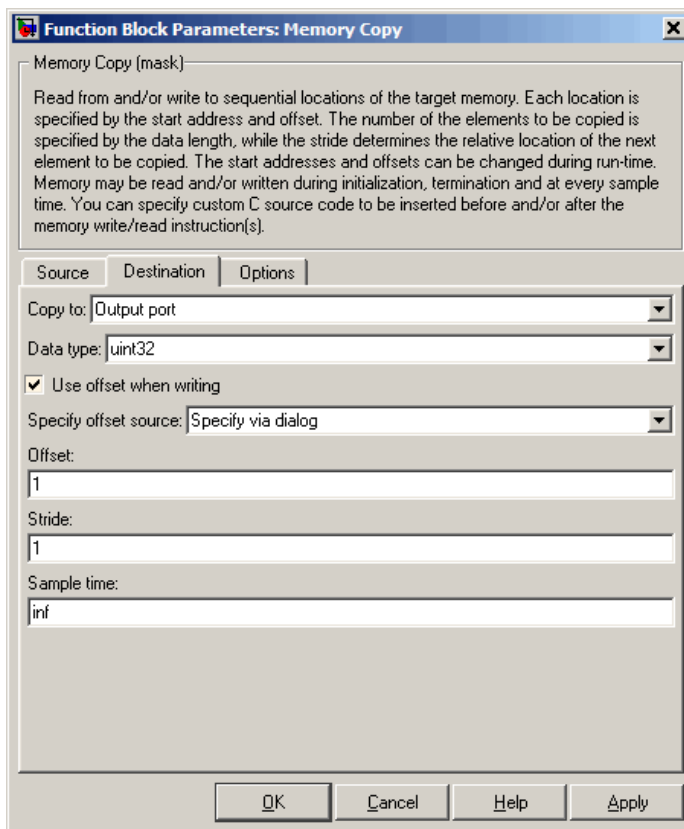




Input Stride = 2  
Output Stride = 1  
Number of Elements Copied = 5

# Memory Copy

## Destination Parameters



### Copy to

Select the destination for the data. Choose one of the entries on the list:

- **Output port** — Copies the data to the block output port. From the output port the block passes data to downstream blocks in the code.

- **Specified address** — Copies the data to the specified location in **Specify address source** and **Address**.
- **Specified source code symbol** — Tells the block to copy the variable or symbol (variable) to the symbol you enter in **Source code symbol**. When you select this copy to option, you enable the **Source code symbol** parameter.

Depending on the choice you make for **Copy from**, you see other parameters that let you configure the source of the data to copy.

### **Specify address source**

This parameter directs the block to get the address for the variable either from an entry in **Address** or from the input port to the block. Select either **Specify via dialog** or **Input port** from the list. Selecting **Specify via dialog** activates the **Address** parameter for you to enter the address for the variable.

When you select **Input port**, the port label on the block changes to **&dst**, indicating that the block expects the destination address to come from the input port. Being able to change the address dynamically lets you use the block to copy different variables by providing the variable address from an upstream block in your model.

### **Source code symbol**

Specify the symbol (variable) in the source code symbol table to copy. The symbol table for your program must include this symbol. The block does not verify that the symbol exists and uses valid syntax.

### **Address**

When you select **Specify via dialog** for the address source, you enter the variable address here. Addresses should be in decimal form. Enter either the decimal address or the address as a hexadecimal string with single quotations marks and use **hex2dec** to convert the address to the proper format. This example converts **0x2000** to decimal form.

# Memory Copy

---

```
8192 = hex2dec('2000');
```

For this example, you could enter either 8192 or `hex2dec('2000')` as the address.

## Data type

Use this parameter to specify the type of data that your variable uses. The list includes the supported data types, such as `int8`, `uint32`, and `Boolean`, and the option `Inherit` from source for inheriting the data type for the variable from the block input port.

## Specify offset source

The block provides two sources for the offset—`Input port` and `Specify via dialog`. Selecting `Input port` configures the block input to read the offset value by adding an input port labeled `src ofs`. This port enables your program to change the offset dynamically during execution by providing the offset value as an input to the block. If you select `Specify via dialog`, you enable the **Offset** parameter in this dialog box so you can enter the offset to use when writing the output data.

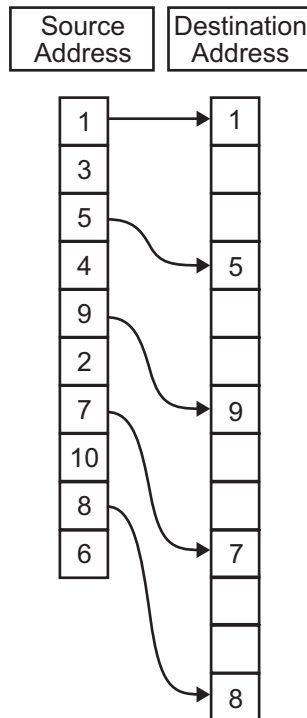
## Offset

**Offset** tells the block whether to write the first element of the data to be copied to the first destination address location, or skip one or more locations at the destination before writing the output. **Offset** defines how many values to skip in the destination before writing the first value to the destination. One is the default offset value and **Offset** accepts only positive integers of one or greater.

## Stride

Stride lets you specify the spacing for copying the input to the destination. By default, the stride value is one, meaning the generated code writes the input data sequentially to the destination in consecutive locations. When you add a stride value not equal to one, the output data is stored not sequentially, but by skipping addresses equal to the stride. **Stride** must be a positive integer.

This figure shows a stride value of three applied to writing the input to an output location. You can specify a stride value for the input with parameter **Stride** on the **Source** pane. As shown in the figure, you can use both an input stride and output stride at the same time to enable you to manipulate your memory more fully.



Input Stride = 2  
Output Stride = 3  
Number of Elements Copied = 5

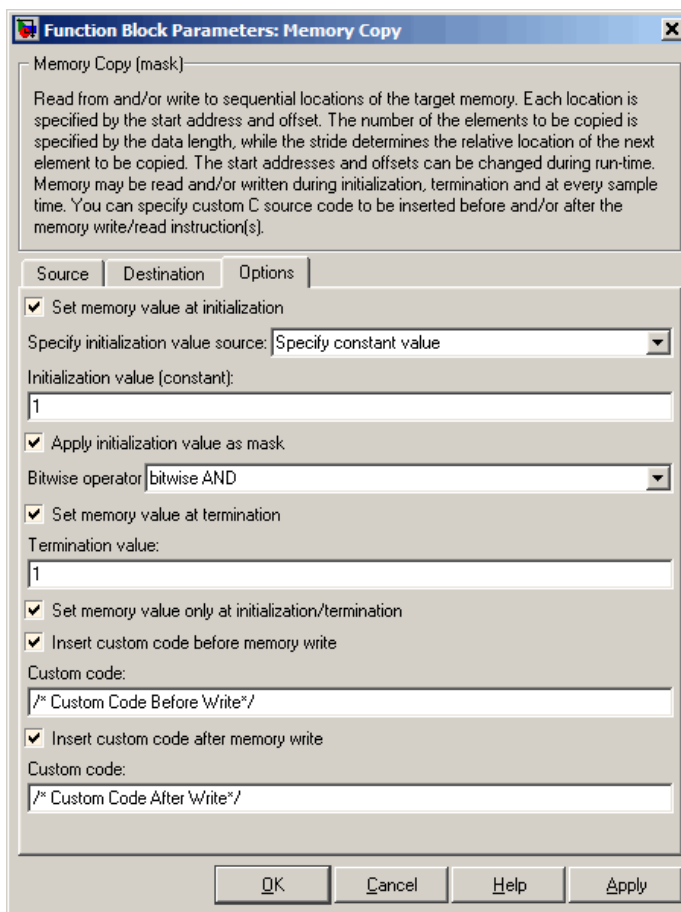
### Sample time

**Sample time** sets the rate at which the memory copy operation occurs, in seconds. The default value Inf tells the block to use a

# Memory Copy

constant sample time. You can set **Sample time** to -1 to direct the block to inherit the sample time from the input, if there is one, or the Simulink software model (when there are no input ports on the block). Enter the sample time in seconds as you need.

## Options Parameters



The dialog box is titled "Function Block Parameters: Memory Copy" and contains the following sections:

- Memory Copy (mask):** A text area containing the description: "Read from and/or write to sequential locations of the target memory. Each location is specified by the start address and offset. The number of the elements to be copied is specified by the data length, while the stride determines the relative location of the next element to be copied. The start addresses and offsets can be changed during run-time. Memory may be read and/or written during initialization, termination and at every sample time. You can specify custom C source code to be inserted before and/or after the memory write/read instruction(s)."
- Source | Destination | Options:** Three tabs, with "Options" selected.
- Set memory value at initialization:** A checked checkbox. Below it, a dropdown menu is set to "Specify constant value".
- Initialization value (constant):** A text input field containing the value "1".
- Apply initialization value as mask:** A checked checkbox.
- Bitwise operator:** A dropdown menu set to "bitwise AND".
- Set memory value at termination:** A checked checkbox.
- Termination value:** A text input field containing the value "1".
- Set memory value only at initialization/termination:** A checked checkbox.
- Insert custom code before memory write:** A checked checkbox.
- Custom code:** A text input field containing the code `/* Custom Code Before Write*/`.
- Insert custom code after memory write:** A checked checkbox.
- Custom code:** A text input field containing the code `/* Custom Code After Write*/`.

At the bottom of the dialog are four buttons: **OK**, **Cancel**, **Help**, and **Apply**.

## **Set memory value at initialization**

When you check this option, you direct the block to initialize the memory location to a specific value when you initialize your program at run time. After you select this option, use the **Set memory value at termination** and **Specify initialization value source** parameters to set your desired value. Alternately, you can tell the block to get the initial value from the block input.

## **Specify initialization value source**

After you check Set memory value at initialization, use this parameter to select the source of the initial value. Choose either

- **Specify constant value** — Sets a single value to use when your program initializes memory. Enter any value that meets your needs.
- **Specify source code symbol** — Specifies a variable (a symbol) to use for the initial value. Enter the symbol as a string.

## **Initialization value (constant)**

If you check **Set memory value at initialization** and choose **Specify constant value** for **Specify initialization value source**, enter the constant value to use in this field. Any real value that meets your needs is acceptable.

## **Initialization value (source code symbol)**

If you check **Set memory value at initialization** and choose **Specify source code symbol** for **Specify initialization value source**, enter the symbol to use in this field. Any symbol that meets your needs and is in the symbol table for the program is acceptable. When you enter the symbol, the block does not verify whether the symbol is a valid one. If it is not valid you get an error when you try to compile, link, and run your generated code.

## **Apply initialization value as mask**

You can use the initialization value as a mask to manipulate register contents at the bit level. Your initialization value is treated as a string of bits for the mask.

# Memory Copy

---

Checking this parameter enables the **Bitwise operator** parameter for you to define how to apply the mask value.

To use your initialization value as a mask, the output from the copy has to be a specific address. It cannot be an output port, but it can be a symbol.

## Bitwise operator

To use the initialization value as a mask, select one of the entries on the following table from the **Bitwise operator** list to describe how to apply the value as a mask to the memory value.

<b>Bitwise Operator List Entry</b>	<b>Description</b>
bitwise AND	Apply the mask value as a bitwise AND to the value in the register.
bitwise OR	Apply the mask value as a bitwise OR to the value in the register.
bitwise exclusive OR	Apply the mask value as a bitwise exclusive OR to the value in the register.
left shift	Shift the bits in the register left by the number of bits represented by the initialization value. For example, if your initialization value is 3, the block shifts the register value to the left 3 bits. In this case, the value must be a positive integer.
right shift	Shift the bits in the register to the right by the number of bits represented by the initialization value. For example, if your initialization value is 6, the block shifts the register value to the right 6 bits. In this case, the value must be a positive integer.



Applying a mask to the copy process lets you select individual bits in the result, for example, to read the value of the fifth bit by applying the mask.

### **Set memory value at termination**

Along with initializing memory when the program starts to access this memory location, this parameter directs the program to set memory to a specific value when the program terminates.

### **Set memory value only at initialization/termination**

This block performs operations at three periods during program execution—initialization, real-time operations, and termination. When you check this option, the block only does the memory initialization and termination processes. It does not perform any copies during real-time operations.

### **Insert custom code before memory write**

Select this parameter to add custom ANSI C code before the program writes to the specified memory location. When you select this option, you enable the **Custom code** parameter where you enter your ANSI C code.

### **Custom code**

Enter the custom ANSI C code to insert into the generated code just before the memory write operation. Code you enter in this field appears in the generated code exactly as you enter it.

### **Insert custom code after memory write**

Select this parameter to add custom ANSI C code immediately after the program writes to the specified memory location. When you select this option, you enable the **Custom code** parameter where you enter your ANSI C code.

### **Custom code**

Enter the custom ANSI C code to insert into the generated code just after the memory write operation. Code you enter in this field appears in the generated code exactly as you enter it.

## **See Also**

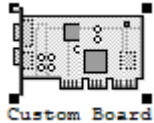
Memory Allocate

# Target Preferences

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**Purpose** Configure model for Analog Devices processor

**Library** Target Preferences in Embedded IDE Link VS



**Description** Options on the block mask let you set features of code generation for your custom Blackfin, SHARC, or TigerSHARC processor. Adding this block to your Simulink software model provides access to the processor hardware settings you need to configure when you generate code from Real-Time Workshop software to run on the processor.

Any model that you target to custom hardware must include this block. Real-Time Workshop software returns an error message if a target preferences block is not present in your model.

---

**Note** This block must be in your model at the top level and not in a subsystem. It does not connect to other blocks, but stands alone to set the target preferences for the model. Simulink software returns an error when your model either does not include a target preferences block or has more than one.

---

You can specify the following processor and target options on this block:

- Board and processor information
- Memory mapping and layout
- Allocation of the various code sections, such as compiler, and custom sections

Setting the options included in this dialog box results in identifying your target to Real-Time Workshop, VisualDSP++, and Simulink

software, and configuring the memory map for your target. Both steps are essential for developing code for any processor that is custom or explicitly supported.

Unlike most other blocks, you cannot open the block dialog box for this block until you add the block to a model. When you try to open the block dialog, the block attempts to connect to a VisualDSP++ IDE session. It cannot make the connection when the block is in the library. If you try to open the block dialog before you add it to a model, the open process fails and returns an error message.

---

**Note** If you do not have VisualDSP++ software installed on your PC, you cannot open this block dialog.

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## Generating Code from Model Subsystems

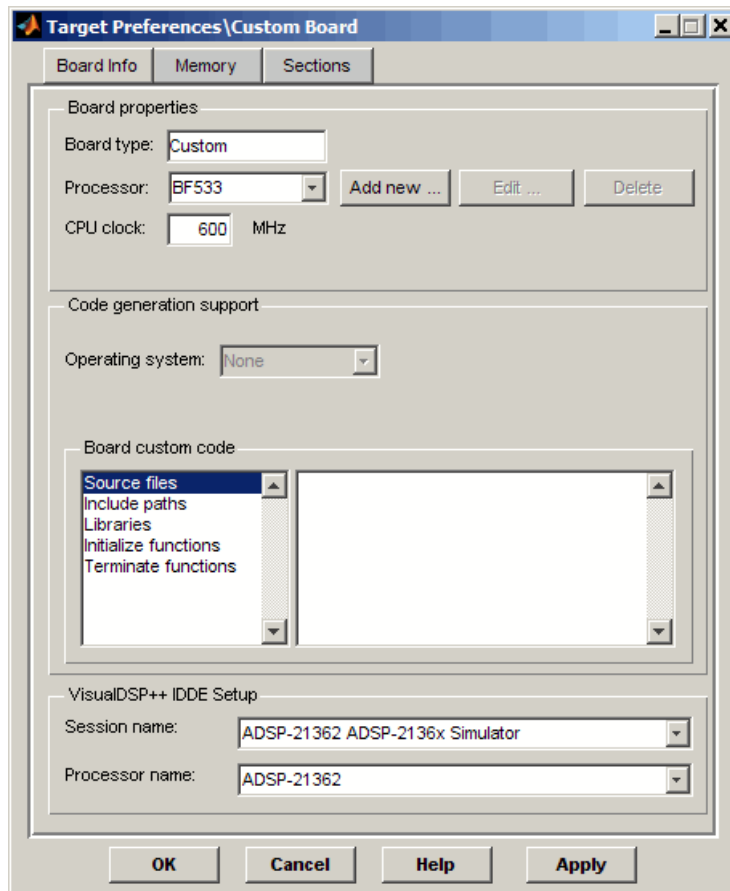
Real-Time Workshop software provides the capability to generate code from a selected subsystem in a model. To generate code for an Analog Devices processor from a subsystem, the subsystem model must include this target preferences block.

### Dialog Box

This section contains the following subsections:

- “Board Info Pane” on page 8-39
- “Memory Pane” on page 8-42
- “Sections Pane” on page 8-48
- “New Processor Dialog Box” on page 8-53

# Target Preferences



All target preferences block dialog boxes provide tabbed access to the following panes. You set the options for the processor from these panes:

- **Board info** — Select the board type and processor, set the clock speed, and identify the session.
- **Memory** — Set the memory allocation and layout on the processor (memory mapping).

- **Sections** — Determine the arrangement and location of the sections on the processor, such as where to put the compiler information.

## Board Info Pane

The following options appear on the **Board Info** pane for the **Target Preferences** dialog box.

### Board Type

Enter the type of board you are targeting with the model. You can enter **Custom** to support any board, based on one of the supported processors, or enter the name of one of the supported boards.

### Processor

Select the processor on the board you select in **Board type**. The processor type you enter determines the contents and setting for options on the **Memory** and **Sections** panes in this dialog box.

### CPU clock

Shows the clock speed of the processor. When you enter a value, you are not changing the CPU clock rate. Instead, you are reporting the actual rate. If the value you enter does not match the rate on the processor, your model's real-time code profiling results may be incorrect.

Enter the actual clock rate the board uses. The rate you enter in this field does not change the rate on the board. Setting **CPU clock** to the actual board rate allows the code you generate to run correctly according to the actual clock rate of the hardware.

When you generate code for targets from Simulink software models, you may encounter the software timer. The timer is invoked automatically to handle and create interrupts to drive your model if the processing rates in your model change (the model is multirate).

Correctly generating interrupts for your model depends on the clock rate of the CPU on your processor.

# Target Preferences

---

For the timer software to calculate the interrupts correctly, VisualDSP++ software needs to know the actual clock rate of your processor as you configured it. CPU clock speed lets you tell the timer the rate at which your processor CPU runs, which is the rate to use to match the CPU rate.

The timer uses the CPU clock rate you specify in **CPU clock** to calculate the time for each interrupt. For example, if your model includes a sine wave generator block running at 1 kHz feeding a signal into an FIR filter block, the timer needs to create interrupts to generate the sine wave samples at the proper rate. The timer uses the clock rate you enter, for example, 100 MHz, to calculate the sine generator interrupt period as follows for the sine block:

- Sine block rate = 1 kHz, or 0.001 s/sample
- CPU clock rate = 100 MHz, or 0.000000001 s/sample

To create sine block interrupts at 0.001 s/sample requires:

$$100,000,000/1000 = 1 \text{ Sine block interrupt per } 100,000 \text{ clock ticks}$$

Thus, you must report the correct clock rate, or the interrupts come at the wrong times and the results are incorrect.

## Board Custom Code

Entries in this group let you specify the locations of custom source files or libraries or other functions. The following options provide access to text areas where you enter files and file paths. The block does not check whether the functions you enter are correct or the file paths you provide exist and are correct. Entering incorrect functions or paths may cause errors during code generation.

- **Source files** — Enter the full paths to source code files to use with this processor. By default, there are no entries in this parameter.

- **Include paths** — If you require additional files on your path, add them by typing the path into the text area. The default setting does not include additional paths.
- **Libraries** — These entries identify specific libraries that the processor requires. They appear on the list by default if required. Add more as you require by entering the full path to the library with the library file in the text area. No additional libraries appear in this field in the default configuration.
- **Initialize functions** — If your project requires an initialize function, enter it in this field. By default, this parameter is empty.
- **Terminate functions** — Enter a function to run when a program terminates. The default setting is not to include a specific termination function.

When you enter a path to a file, library, or other custom code, use the string

```
$(install_dir)
```

to refer to the VisualDSP++ software installation directory.

Enter new paths or files (custom code items) one entry per line. Include the full path to the file for libraries and source code.

**Board custom code** options do not support functions that use return arguments or values. Only functions of type `void fname void` are valid as entries in these parameters.

## Session name

Contains a list of all the sessions defined in VisualDSP++ IDE. From the list of available sessions, select the one to which you are targeting your code.

## Processor name

Lists the processors on the board you selected for targeting in **Session name**. In most cases, only one name appears because

# Target Preferences

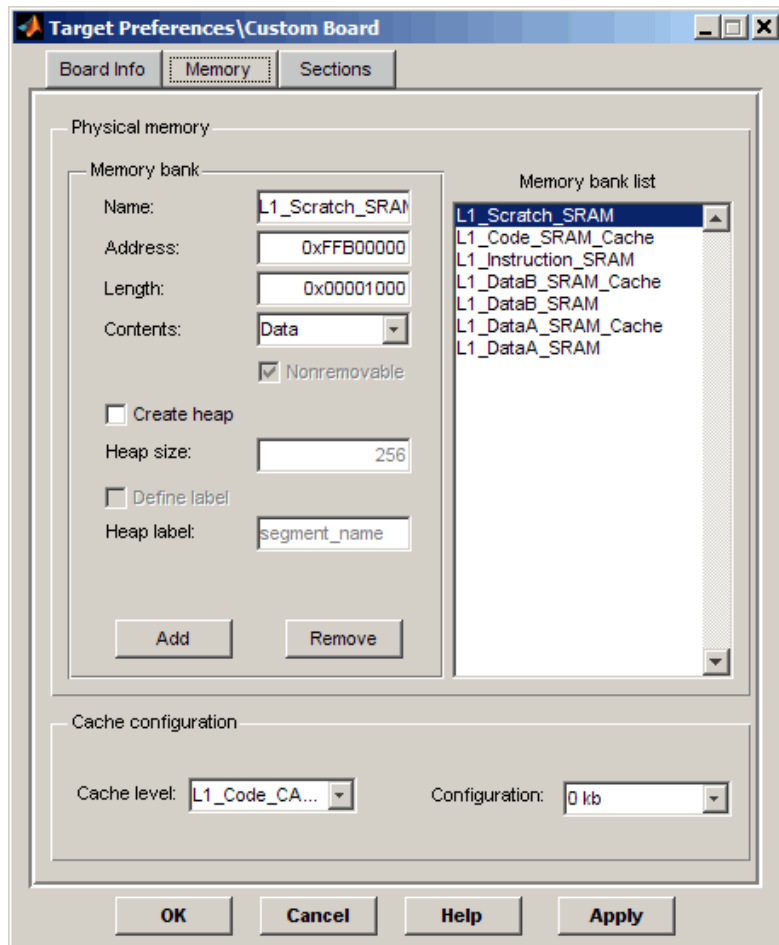
---

the board has one processor. In the multiprocessor case, you select the processor by name from the list.

## **Memory Pane**

When you develop models for any processor, you need to specify the layout of the physical memory on your processor and board to determine how use it for your program. For supported boards, the board-specific target preferences blocks set the default memory map.





The **Memory** pane contains memory options in three areas:

- **Physical Memory** — Specify the processor and board memory map
- **Heap** — Specify whether you use a heap and determine the size in words

# Target Preferences

---

- **Cache configuration** — Enables the cache (where available) and sets the size in kilobytes

---

**Note** Your **Physical Memory**, **Heap**, and **Cache configuration** settings on this pane may affect options on the **Sections** pane. Your choices on the **Memory** pane may change how you configure some options on the **Sections** pane.

---

Most of the information about memory segments and memory allocation is available from the online help system for the VisualDSP++ product.

## Physical Memory Options

This list shows the physical memory segments available on the board and processor. By default, target preferences blocks show the memory segments found on the selected processor. In addition, the **Memory** pane on preconfigured target preferences blocks shows memory segments that are available on the board, but that are external to the processor (external memory). Target preferences blocks set default starting addresses, lengths, and contents of the default memory segments.

The default memory segments for each processor and board are different. For example:

- Custom boards based on Blackfin processors provide SRAM memory segments by default.
- SHARC-based boards provide RAM memory segments by default.

### Name

When you highlight an entry on the **Physical memory** list, the name of the entry appears in this field. To change the name of the existing memory segment, select it in the **Physical memory** list and then type the new name in this field.

---

**Note** You cannot change the names of default processor memory segments.

---

To add a new physical memory segment to the list, click **Add**, replace the temporary label in **Name** with the one to use, and press **Return**. Your new segment appears on the list.

After you add the segment, you can configure the starting address, length, and contents for the new segment. New segments start with code and data as the type of content that can be stored in the segment (refer to the **Contents** option).

Names are case sensitive. `NewSegment` is not the same as `newsegment` or `newSegment`.

## Address

**Address** reports the starting address for the memory segment showing in the **Name** field. Address entries are in hexadecimal format and limited only by the board or processor memory.

When you are using a processor-specific preferences block, the starting address shown is the default value. You can change the starting value by entering the new value directly in the **Address** field when you select the memory segment to change.

## Length

From the starting address, **Length** sets the length of the memory allocated to the segment in the **Name** field. As in all memory entries, specify the length in hexadecimal format, in minimum addressable data units (MADUs).

When you are using a processor-specific preferences block, the length shown is the default value. You can change the value by entering the new value directly in this option.

# Target Preferences

---

## Contents

**Contents** details the kind of program sections that you can store in the memory segment in **Name**. As the processor type for the target preferences block changes, the kinds of information you store in listed memory segments may change. Generally, the **Contents** list contains these strings:

- **Code** — Allow code to be stored in the memory segment in **Name**.
- **Data** — Allow data to be stored in the memory segment in **Name**.
- **Code and Data** — Allow code and data to be stored in the memory segment in the **Name** field. When you add a new memory segment, this string is the default setting for the contents of the new element.

You may add or use as many segments of each type as you need, within the limits of the memory on your processor.

## Add

Click **Add** to add a new memory segment to the processor memory map. When you click **Add**, a new segment name appears, for example NEWMEM1, in **Name** and on the **Physical memory** list. In **Name**, change the temporary name NEWMEM1 by entering the new segment name. Entering the new name or clicking **Apply** updates the temporary name on the list to the name you enter in this field.

## Remove

Remove a memory segment from the memory map. Select the segment to remove on the **Physical memory** list, and click **Remove** to delete the segment.

## Memory bank list

Displays all available memory banks for the selected processor. When you select one of the entries on this list, the **Name**, **Address**, **Length**, and **Contents** parameters change to reflect the memory block selection. With the contents list, you can change the type of material stored in the block—data or code or both.

## Create Heap

If your processor supports using a heap, as the Blackfin and SHARC processors do, selecting this option enables creating the heap, and enables the **Heap size** option. **Create heap** is not available on processors that either do not provide a heap or do not allow you to configure the heap.

Use this option to create a heap in any memory segment on the **Physical memory** list. Select the memory segment on the list, and then select **Create heap** to create a heap in the selected segment. After you create the heap, use the **Heap size** and **Define label** options to configure the heap.

The location of the heap in the memory segment is not under your control. The only way to control the location of the heap in a segment is to make the segment and the heap the same size. Otherwise, the compiler determines the location of the heap in the segment.

## Heap Size

After you select **Create heap**, this option lets you specify the size of the heap in words. Enter the number of words in decimal format. When you enter the heap size in decimal words, the system converts the decimal value to hexadecimal format. You can enter the value directly in hexadecimal format as well. Processors may support different maximum heap sizes.

## Define Label

Selecting **Create heap** enables this option that allows you to name the heap. Enter your label for the heap in the **Heap label** option.

## Heap Label

Use this option which you enable by selecting **Define label**, to provide the label for the heap. Any combination of characters is accepted for the label, except reserved characters in ANSI C/C++ compilers.

# Target Preferences

---

The block does not verify that the label you enter is valid. Invalid labels can cause errors during code generation.

## Cache level

Blackfin, SHARC, and TigerSHARC processors support different cache arrangements. For Blackfin processors, you can select one of the following options from the list:

- L1\_Code\_CACHE
- L1\_DataA\_CACHE
- L1\_DataB\_CACHE

On SHARC processors, the cache is always `Instruction_CACHE`. Set the cache size in **Configuration**.

On TigerSHARC processors, the cache is always `CACHE`, used for both data and code, and you can only enable the cache. You cannot choose the size or configuration. Use the **Configuration** option to enable the cache.

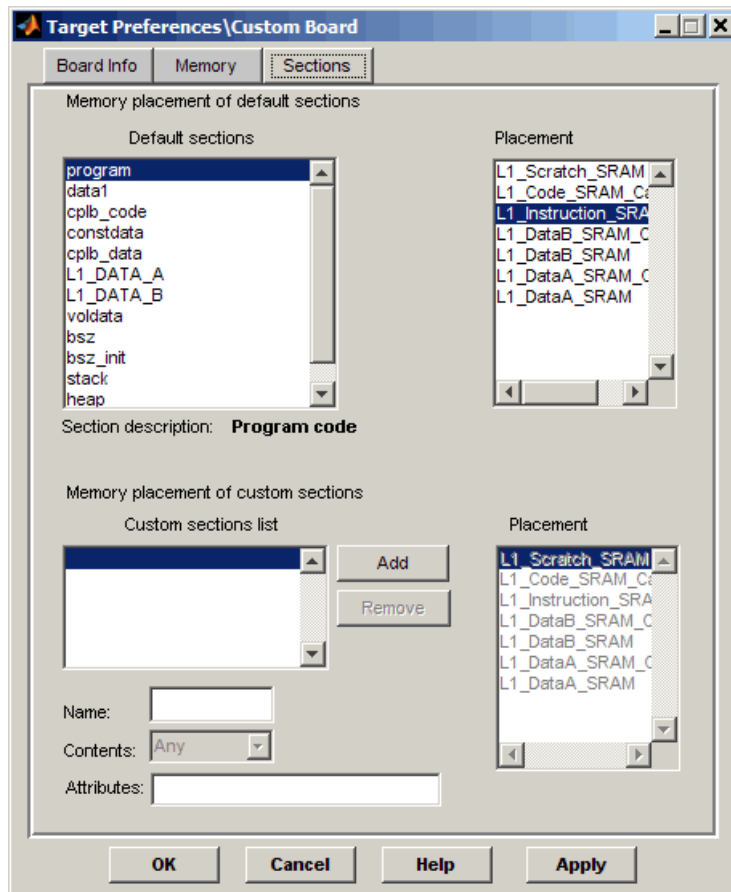
## Configuration

Select the size of the cache from the list to determine the size of the cache allocated. SHARC processors support 1536 bits or 0 bits (no cache). Blackfin processors support 0 bits or 16 bits. For TigerSHARC processors, your choices are `disable` or `enable` only.

## Sections Pane

Options on this pane let you specify where various program sections should go in memory. Program sections are distinct from memory segments—sections are portions of the executable code stored in contiguous memory locations. Commonly used sections include `.program`, `.bsz`, `.data1`, and `.stack`.

For more information about program sections and objects, refer to the Analog Devices VisualDSP++ product online help.



Within this pane, you allocate the memory needed for the **Default sections** and **Custom sections**.

The following table provides brief definitions of the sections in the **Default sections**, and **Custom sections** lists in the pane. All sections do not appear for all processors.

# Target Preferences

---

<b>String</b>	<b>Description of the Section Contents</b>
bsz	Global zero initialized data
bsz_init	Run-time initialization data
constdata	Constant data, usually defined with the ANSI C qualifier and string constants
cplb_code	CPLB management routines
cplb_data	CPLB configuration tables
data1	Global program data for execution
heap	System heap allocation
L1_Data_A	L1 band A SRAM data
L1_Data_B	L1 band B SRAM data
noncache_code	Code not assigned to the cache
program	Program code
seg_argv	Command line arguments that PGO uses
seg_dmda	Global data
seg_heap	System heap
seg_init	Stack and heap location and size info
seg_int_code	Interrupt latch register modifier code
seg_pmco	Program code
seg_pmda	Global program data qualified with pm keyword
seg_rth	Interrupt vector table
seg_stak	System stack
stack	Global system stack
voldata	Volatile data

You can learn more about memory sections and objects in your Analog Devices VisualDSP++ product online help.



## Default sections

During program compilation, the compiler produces both uninitialized and initialized blocks of data and code. These blocks get allocated into memory as required by the configuration of your system. On the **Default sections** list you find both initialized sections that contain data or executable code and uninitialized sections that reserve space in memory.

The following sections are initialized:

- `bsz`
- `bsz_init`
- `constdata`
- `seg_pmco`
- `seg_pmda`
- `voldata` (created by the assembler)

The following sections are not initialized:

- (created by the assembler)
- `heap`
- `stack`
- 

The following sections appear on the list as well:

- (created by the assembler)
- 
- 

---

**Note** The ANSI C/C++ compiler does not use the `.data` section.

---

# Target Preferences

---

When you highlight a section on the list, **Section description** shows a brief description of the section. Also, **Placement** shows you where the section is presently allocated in memory.

## Section description

Describes the contents of the selected entry on the **Default sections** list.

## Placement

Shows you where the selected **Default sections** list entry is allocated in memory. You change the memory allocation by selecting a different location from the **Placement** list. The list contains the memory segments as defined in the physical memory map on the **Memory** pane. Select one of the listed memory segments to allocate the highlighted compiler section to the segment.

## Custom sections list

When your program uses code or data sections that are not included in the **Default sections** list, add the new sections to this list. Initially, the **Custom sections list** parameter contains no fixed entries. Only a placeholder for a section for you to define.

## Name

Enter the name for your new section in this field. To add a new section, click **Add**. Then, replace the temporary name with the name to use. Although the temporary name includes a period at the beginning you do not need to include a period in your new name. Names are case sensitive. `NewSection` is not the same as `newsection`, or `newSection`.

## Contents

Select the kind of data to assign to the new section. Choose from one of the following list entries:

- **Any** — Indicates the section can store either code or data. New sections use **Any** by default.
- **Code** — Indicates the section stores code.
- **Data** — Indicates the section stores data.

## Attributes

Not used.

## Placement

After you have added the new section to the **Name** list, select the memory segment to which to add your new section. Limited only by the restrictions imposed by the hardware and compiler, you can select any segment that appears on the list.

## Add

Click **Add** to add a new entry on the list of custom sections. When you click **Add**, a new temporary name, for example `NEWMEM1` appears in the **Name** field. Enter the new custom section name to add the section to the **Custom sections** list. After you enter the new name, click **Apply** to add the new section to the list. You can also click **OK** to add the section to the list and close the dialog box.

## Remove

Remove a section from the **Custom sections** list. To remove a section, select the section, and click **Remove**.

## New Processor Dialog Box

Clicking **Add new** on the **General** pane opens this dialog box to add a new processor to the list of supported processors. The new processor must be a member of one of the supported families of processors.

The first time you click **Save** to add a new processor definition to the list of supported processors, a dialog box opens that directs you to select a destination folder for the saved processor definitions file `customChipInfo.dat`. You must select a directory to which you have write access. The location you specify becomes part of your MATLAB software preferences. Future processors that you add become entries in the file `customChipInfo.dat`.

To add a new processor, enter values for the following parameters:

### Name

Provide a name to identify your new processor. You can use any valid ANSI C string value in this field. The name you enter in

# Target Preferences

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this field appears on the list of processors after you add the new processor.

## **Processor Class**

Identifies the class of the new processor. Your new processor must be a member of a family of processors that Embedded IDE Link VS software supports. For example, you can add a new Blackfin processor because the product supports the Blackfin processor family.

## **CPU clock**

Provide a name to identify your new processor. You can use any valid ANSI C string value in this field. The name you enter in this field appears on the list of processors after you add the new processor.

Enter the clock speed of the processor in MHz. When you enter a value, you are not setting the CPU clock rate on the processor. You are reporting the rate. If the value you enter does not match the rate on the processor, your model's real-time results may be wrong, and code profiling results are not correct.

Setting **CPU clock** to the actual board rate allows the generated code to run correctly according to the actual clock rate of the hardware.

## **Compiler switch**

This string ensures that the compile operation works successfully.

## **Code generation hook**

This string provides the prefix that the calling code uses to call hook functions during code generation.

## **Define internal memory banks** (one or more memory banks)

Parameters in this group configure the memory map for the new processor.

## **Define default sections** (one or more default sections)

Parameters in this group configure the default sections for your new processor.

# Target Preferences

If you do not provide an entry for each of these parameters, Embedded IDE Link VS software returns an error message and does not create the new processor entry.

**New Processor**

General

Name:  Processor class:

CPU clock:  MHz Compiler switch:

Code generation hook:

Define internal memory banks

Name:  Contents:  Add

Address:  Length:  Remove

Define cache configuration

Label:  Options:  Add

Start:  Default:  Remove

Growth:

Define default sections

Label:  Placement:  Add

Description:  Remove

Contents:

Processor custom code

Source files

Include paths

Libraries (Little Endian)

Libraries (Big Endian)

Preprocessor symbols

Save Close Help

# Target Preferences

---

## General

### Name

Provide a name to identify your new processor. You can use any valid ANSI C string in this field. The name you enter appears on the list of processors after you add the new processor.

### CPU clock

Enter the clock speed of the processor in MHz. When you enter a value, you are not setting the CPU clock rate on the processor. You are reporting the rate. If the value you enter does not match the rate on the processor, your model's real-time results and code profiling results may not be correct.

Setting **CPU clock** to the actual board rate allows the code you generate to run correctly according to the actual clock rate of the hardware.

### Processor class

This represents the class for the new processor. New processors must be members of processor families that Embedded IDE Link VS software supports, such as a new Blackfin or TigerSHARC processor.

You cannot add a new processor class to support your new processor.

Generally, processors in a family share common design elements such as interrupt architecture and clock. They may have different memory maps. By selecting the processor class, you identify the common features of the processor family. The parameters in **Define internal memory banks** and **Define default sections** enable you to specify the memory mapping for your new processor.

For example, to add a new Blackfin processor, enter the string BFxxx where xxx is the processor number.

The following table shows the strings for the supported processor families.

Processor Family	Processor Class String
Blackfin	BFxxx where xxx is the numerical designation of the processor, such as BF532
SHARC	xxxxx where xxxxx is the numerical designation for the processor, such as 21366
TigerSHARC	xxx where xxx is the numerical designation for the processor, such as 202

Here is an example of using the code generation hook when you begin to generate a project from a model intended for the BF532 processor. At the start of the code generation process, the process calls `BFxxx_validateModelEntry.m` to validate the model settings for the processor. The `BFxxx` prefix is the code generation hook.

### Compiler switch

Identifies the processor family of the new processor to the compiler. Successful compilation requires this switch. The string depends on the processor family or class. The software does not use this string.

### Code generation hook

This string represents a prefix to add when the code generation process call certain hook functions. The hook allows the code to call into handling functions that are specific to the processor selected.

The code generation hook strings for the supported processors appear in the following table.

Processor Class or Family	Code Generation Hook String
Blackfin	blackfin

# Target Preferences

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Processor Class or Family	Code Generation Hook String
SHARC	sharc
TigerSHARC	tigersharc

## Define internal memory banks

### Name

To add a new physical memory segment to the internal memory banks list, click **Add**, replace the temporary label in **Name** with the one to use, and press **Return**. Your new segment appears on the list.

After you add the segment, you can configure the starting address, length, and contents for the new segment. New segments start with code and data as the type of content that can be stored in the segment (refer to the **Contents** option).

Names are case sensitive. `NewSegment` is not the same as `newsegment` or `newSegment`.

### Address

**Address** reports the starting address in hexadecimal format for the memory segment showing in **Name**. Address entries are limited only by the board or processor memory.

When you are using a processor-specific preferences block, the starting address shown is the default value. You can change the starting value by entering the new value directly in **Address** when you select the memory segment to change.

### Length

From the starting address, **Length** sets the length of the memory allocated to the segment in **Name**. As in all memory entries, specify the length in hexadecimal format, in minimum addressable data units (MADUs). For the Analog Devices processor families, for example, the MADU is 8 bytes, 1 word.



## Contents

**Contents** specifies the kind of program sections that you can store in the memory segment in **Name**. When you change the processor type, the kinds of information you can store in listed memory segments may change. Generally, the **Contents** list contains these strings:

- **Code** — Allow code to be stored in the memory segment in **Name**.
- **Data** — Allow data to be stored in the memory segment in **Name**.
- **Code and Data** — Allow code and data to be stored in the memory segment in **Name**. When you add a new memory segment, this setting is the default for the contents of the new element.

You may add or use as many segments of each type as you need, within the limits of the memory on your processor.

## Add

Click **Add** to add a new memory segment to the processor memory map. When you click **Add**, a new segment name appears, for example NEWMEM1, in **Name** and on the list. In **Name**, change the temporary name NEWMEM1 by entering the new segment name. Entering the new name, or clicking **OK** updates the temporary name on the list to the name you enter.

## Remove

Remove a memory segment from the memory map. Select the segment to remove from the list, and click **Remove** to delete the segment.

## Define cache configuration

### Options

Enter the label for each option of the selected cache configuration, one label on each line, such as 0kb, 16kb, 32kb and so on.

# Target Preferences

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## Add

Click **Add** to add a new cache configuration to the list. When you click **Add**, the new cache label appears on the list.

## Remove

Remove a cache configuration from the cache list. Select the configuration to remove from the list, and click **Remove** to delete the cache.

Cache configurations and related options are defined as symbols to the project generator component. Cache options for new processors are not labeled until you add the labels.

## Label

Enter your label for the heap in the **Label** field. Entering the label updates the label of the selected configuration.

## Define Default Sections

Options in this region let you specify where various program sections go in memory and the contents and label for each section. You can add text to describe each section. Program sections are distinct from memory segments—sections are portions of the executable code stored in contiguous memory locations. Commonly used sections include `.text`, `.bss`, `.data`, and `.stack`. Some sections relate to the compiler, and some can be custom sections as you require.

## Label

The name of the section corresponds to the symbolic name recognized by the linker program used with the respective processor.

## Contents

**Contents** provides the information about the native of the program section. As the processor type for the target preferences block changes, the kinds of information you store in listed sections may change. Generally, the **Contents** list contains these strings:

- Code — Allow code to be stored in the section in **Name**.

- **Data** — Allow data to be stored in the section in **Name**.
- **Code and Data** — Allow code and data to be stored in the section in **Name**. When you add a new section, this setting is the default for the contents.

You may add or use as many sections of each type as you need, within the limits of the memory on your processor.

## Add

Click **Add** to add a new section to the list. When you click **Add**, the new section appears on the list.

## Remove

This option lets you remove a section from the section list. Select the section to remove from the list, and click **Remove** to delete the section.

Sections and related options are defined as symbols to the project generator component. Section options for new processors are not labeled until you add the labels.

## Processor Custom Code

The list on the left side of the pane shows the kinds of custom code you can specify for your processor. Each time you use your custom processor as defined in this dialog box, the custom code you enter in this field applies. You can enter custom code in the categories in the following table.

Custom Code Entry	Description
Source files	Enter the full paths to source code files to use with this processor. By default there are no entries in this parameter. Enter each source file on a new line.

# Target Preferences

---

Custom Code Entry	Description
Include paths	If you require additional header files on your path, add them by typing the path into the text area, one file per line. The default setting does not include additional paths.
Libraries (Little Endian)	These entries identify specific little endian libraries that the processor requires. Add more as you require by entering the full path to the library with the library file in the text area. Enter one library per line. No additional libraries appear in the default configuration.
Libraries (Big Endian)	These entries identify specific big endian libraries that the processor requires. Add more as you require by entering the full path to the library with the library file in the text area. No additional libraries appear in the default configuration. Enter one library per line.
Preprocessor symbols	Enter any preprocessor symbols that the new processor requires for operation and compilation. No preprocessor symbols appear in the default configuration. Add the required symbols one symbol per line.

You can use two types of tokens when you specify custom code paths:

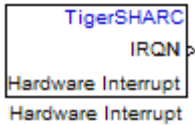
- `$(Install_dir)` — Refers to the installation directory of VisualDSP++ software. One example of this token is  

```
$(Install_dir) \vdsplink\csl\lib\...
```
- `$(MATLAB_ROOT)` — Refers to the directory where you installed your MATLAB software.

# TigerSHARC Hardware Interrupt

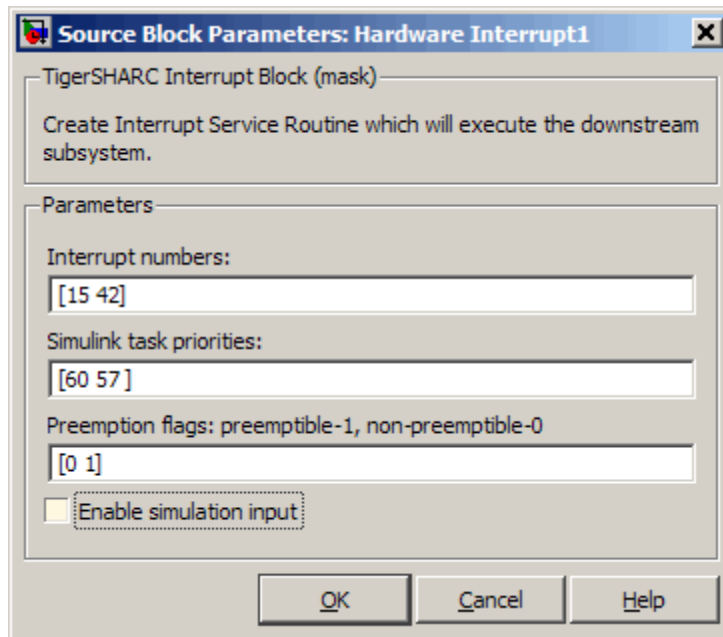
**Purpose** Generate Interrupt Service Routine

**Library** TigerSHARC DSP Support in Embedded IDE Link VS



**Description** Create interrupt service routines (ISR) in the software generated by the build process. When you incorporate this block in your model, code generation results in ISRs on the processor that run the processes that are downstream from the this block or an Idle Task block connected to this block.

## Dialog Box



# TigerSHARC Hardware Interrupt

---

## **Interrupt numbers**

Specify an array of interrupt numbers for the interrupts to install. The valid interrupts are 2, 3, 6-9, 14-17, 22-25, 29-32, 37, 38, 41-44, 52.

The width of the block output signal corresponds to the number of interrupt numbers specified in this field. Combined with the **Simulink task priorities** that you enter and the preemption flag you enter for each interrupt, these three values define how the code and processor handle interrupts during asynchronous scheduler operations.

## **Simulink task priorities**

Each output of the Hardware Interrupt block drives a downstream block (for example, a function call subsystem). Simulink model task priority specifies the priority of the downstream blocks. Specify an array of priorities corresponding to the interrupt numbers entered in **Interrupt numbers**.

Simulink model task priority values are required to generate the proper rate transition code (refer to Rate Transitions and Asynchronous Blocks in the Real-Time Workshop documentation). The task priority values are also required to ensure absolute time integrity when the asynchronous task needs to obtain real time from its base rate or its caller. Typically, you assign priorities for these asynchronous tasks that are higher than the priorities assigned to periodic tasks.

## **Preemption flags preemptible – 1, non-preemptible – 0**

Higher priority interrupts can preempt interrupts that have lower priority. To allow you to control preemption, use the preemption flags to specify whether an interrupt can be preempted.

Entering 1 indicates that the interrupt can be preempted. Entering 0 indicates the interrupt cannot be preempted. When **Interrupt numbers** contains more than one interrupt priority, you can assign different preemption flags to each interrupt by entering a vector of flag values, corresponding to the order of

the interrupts in **Interrupt numbers**. If **Interrupt numbers** contains more than one interrupt, and you enter only one flag value in this field, that status applies to all interrupts.

In the default settings [0 1], the interrupt with priority 15 in **Interrupt numbers** is not preemptible and the priority 42 interrupt can be preempted.

### **Enable simulation input**

When you select this option, Simulink software adds an input port to the Hardware Interrupt block. This port is used in simulation only. Connect one or more simulated interrupt sources to the simulation input.

# TigerSHARC Hardware Interrupt

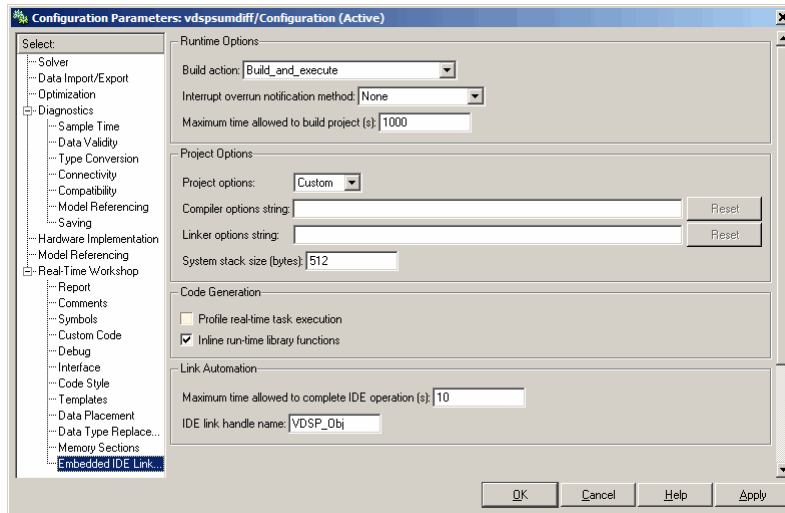
---



# Embedded IDE Link VS Software Configuration Parameters

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## Embedded IDE Link VS Pane



### In this section...

- “Embedded IDE Link VS Overview” on page 9-4
- “IDE link handle name” on page 9-6
- “Profile real-time execution” on page 9-7
- “Profile by” on page 9-9
- “Number of profiling samples to collect” on page 9-10
- “Inline run-time library functions” on page 9-12
- “Project options” on page 9-14
- “Compiler options string” on page 9-16
- “Linker options string” on page 9-18
- “System stack size (MAUs)” on page 9-20
- “Build action” on page 9-21
- “Interrupt overrun notification method” on page 9-24
- “Interrupt overrun notification function” on page 9-26

**In this section...**

“PIL block action” on page 9-27

“Maximum time allowed to build project (s)” on page 9-29

“Maximum time to complete IDE operations (s)” on page 9-31

## **Embedded IDE Link VS Overview**

Options on this pane configure the generated projects and code for Analog Devices processors. They also enable PIL block generation and provide real-time task execution and stack use profiling.



## IDE link handle name

specifies the name of the `adivdsp` object that the build process creates.

### Settings

**Default:** `VDSP_Obj`

- Enter any valid C variable name, without spaces.
- The name you use here appears in the MATLAB workspace browser to identify the `adivdsp` object.
- The handle name is case sensitive.

### Command-Line Information

**Parameter:** `ideObjName`

**Type:** string

**Value:**

**Default:** `VDSP_Obj`

### Recommended Settings

Application	Setting
Debugging	Enter any valid C program variable name, without spaces
Traceability	No impact
Efficiency	No impact
Safety precaution	No impact

### See Also

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## Profile real-time execution

Enables real-time execution profiling in the generated code by adding instrumentation for task functions or atomic subsystems.

### Settings

**Default:** Off

- On  
Adds instrumentation to the generated code to support task execution profiling and generate the profiling report.
- Off  
Does not instrument the generated code to produce the profile report.

### Dependencies

This parameter adds **Number of profiling samples to collect**.

Selecting this parameter disables **ID link handle name**.

Setting **Build action** to `Archive_library` or `Create_processor_in_the_loop` project removes this parameter.

### Command-Line Information

**Parameter:** ProfileGenCode  
**Type:** string  
**Value:** 'on' | 'off'  
**Default:** 'off'

### Recommended Settings

Application	Setting
Debugging	On
Traceability	On

<b>Application</b>	<b>Setting</b>
Efficiency	No impact
Safety precaution	No impact

**See Also**

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.



## Profile by

Defines how to profile the executing program.

### Settings

**Default:** Task

Task

Profiles model execution by the tasks defined in the model and program.

Atomic subsystem

Profiles model execution by the atomic subsystems in the model.

### Dependencies

Selecting **Profile real-time execution** enables this parameter.

### Command-Line Information

**Parameter:** profileBy

**Type:** string

**Value:** Task | Atomic subsystem

**Default:** Task

### Recommended Settings

Application	Setting
Debugging	Task or Atomic subsystem
Traceability	Archive_library
Efficiency	No impact
Safety precaution	No impact

### See Also

For more information, refer to “Embedded IDE Link VS Pane” on page 9-2.

For more information about PIL, refer to “Using Processor-in-the-Loop” on page 4-3.

## Number of profiling samples to collect

Specifies the number of profiling samples to collect. Collection stops when the buffer for profiling data is full.

### Settings

**Default:** 100

**Minimum:** 1

**Maximum:** Buffer capacity in samples

### Tips

- Collecting profiling data on a simulator may take a very long time.
- Data collection stops after collecting the specified number of samples. The application and processor continue to run.

### Dependencies

This parameter is enabled by **Profile real-time execution**.

### Command-Line Information

**Parameter:** ProfileNumSamples

**Type:** int

**Value:** Positive integer

**Default:** 100

### Recommended Settings

Application	Setting
Debugging	100
Traceability	No impact
Efficiency	No impact
Safety precaution	No impact

**See Also**

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## Inline run-time library functions

Marks run-time library functions generated by the Signal Processing Toolbox™ and Video and Image Processing Blockset block algorithms. These functions as marked with the `inline` keyword.

### Settings

**Default:** On



On

Adds the keyword `inline` to each instance of an algorithm generated from blocks in the Signal Processing Blockset software and Video and Image Processing Blockset software.



Off

Does not mark the algorithms with the keyword.

### Tips

The following list shows cases where inlining run-time library functions may not be appropriate:

- Few or no numerical parameters in the function
- One algorithm that is already fixed in capability, such as it has no optional modes or alternate algorithms
- Function supports only one data type
- Significant or large code size in the `mdlOutputs()` function
- Your models use multiple instances of this library function

### Command-Line Information

**Parameter:** `InlineDSPBlks`

**Type:** string

**Value:** 'on' | 'off'

**Default:** on

## Recommended Settings

Application	Setting
Debugging	Off
Traceability	On
Efficiency	On
Safety precaution	No impact

## See Also

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## Project options

Sets the project options for building your project from the model.

### Settings

**Default:** Custom

#### Custom

Applies a custom project configuration that provides a specialized combination of build and optimization settings.

The default settings are the same as the Release project configuration in VisualDSP++ software, except for the compiler and memory options. For the compiler options, Custom uses the Function(-o2) compiler setting. For memory configuration, Custom specifies the -m11 memory model that uses near functions and data.

#### Debug

Applies the Debug project options defined by Code Composer Studio™ software to the generated project and code.

#### Release

Applies the Release project configuration defined by Code Composer Studio software to the generated project and code.

### Dependencies

Selecting Custom disables the reset options for **Compiler options string** and **Linker options string**.

### Command-Line Information

**Parameter:** projectOptions

**Type:** string

**Value:** Custom | Debug | Release

**Default:** Custom

## Recommended Settings

Application	Setting
Debugging	Custom or Debug
Traceability	Custom, Debug, Release
Efficiency	Release
Safety precaution	No impact

### See Also

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## Compiler options string

Lets you enter a string of compiler options to define your project configuration.

### Settings

**Default:** No default

### Tips

- To reset the compiler options to the default values, click **Reset**.
- Use spaces between options.
- Verify that the options are valid. The software does not validate the option string.
- Setting **Project options** to Custom applies -g as the default compiler options string.
- Setting **Project options** to Debug applies -g -d \_Debug as the default compiler options string.
- Setting **Project options** to Release applies -o2 as the default compiler options string.

### Command-Line Information

**Parameter:** compilerOptionsStr

**Type:** string

**Value:** Custom | Debug | Release

**Default:** Custom

### Recommended Settings

Application	Setting
Debugging	Custom
Traceability	Custom
Efficiency	No impact
Safety precaution	No impact



**See Also**

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## Linker options string

Enables you to specify linker command options that determine how to link your project when you build your project.

### Settings

**Default:** No default

### Tips

- Use spaces between options.
- Verify that the options are valid. The software does not validate the options string.
- To reset the linker command options to the default values, click **Reset**.

### Dependencies

Setting **Build action** to `Archive_library` removes this parameter.

### Command-Line Information

**Parameter:** `linkerOptionsStr`

**Type:** string

**Value:**

**Default:**

### Recommended Settings

Application	Setting
Debugging	No impact
Traceability	No impact
Efficiency	No impact
Safety precaution	No impact

**See Also**

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## System stack size (MAUs)

Allocates memory for the system stack on the processor.

### Settings

**Default:** 512

**Minimum:** 0

**Maximum:** Available memory

- Enter the stack size in minimum addressable unit (MAUs).
- The software does not verify that your size is valid. Be sure that you enter an acceptable value.

### Dependencies

Setting **Build action** to `Archive_library` removes this parameter.

### Command-Line Information

**Parameter:** `systemStackSize`

**Type:** `int`

**Default:** 512

### Recommended Settings

Application	Setting
Debugging	<code>int</code>
Traceability	<code>int</code>
Efficiency	<code>int</code>
Safety precaution	No impact

### See Also

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## Build action

Defines how Real-Time Workshop software responds when you press Ctrl+B to build your model.

## Settings

**Default:** Build\_and\_execute

### Build\_and\_execute

Builds your model, generates code from the model, and then compiles and links the code. After linking, this setting downloads and runs the executable on the processor.

### Create\_project

Directs Real-Time Workshop software to create a new project in the IDE.

### Archive\_library

Invokes the IDE Archiver to build and compile your project, but It does not run the linker to create an executable project. Instead, the result is a library project.

### Build

Builds a project from your model. Compiles and links the code. Does not download and run the executable on the processor.

### Create\_processor\_in\_the\_loop\_project

Directs the Real-Time Workshop code generation process to create PIL algorithm object code as part of the project build.

## Dependencies

Selecting Archive\_library removes the following parameters:

- **Interrupt overrun notification method**
- **Interrupt overrun notification function**
- **Profile real-time task execution**
- **Number of profiling samples to collect**
- **Linker options string**
- **Reset**

- **Export IDE link handle to base workspace**

Selecting `Create_processor_in_the_loop_project` removes the following parameters:

- **Interrupt overrun notification method**
- **Interrupt overrun notification function**
- **Profile real-time task execution**
- **Number of profiling samples to collect**
- **Linker options string**
- **Reset**
- **Export IDE link handle to base workspace** with the option set to export the handle

### Command-Line Information

**Parameter:** `buildAction`

**Type:** string

**Value:** `Build` | `Build_and_execute` | `Create_project` `Archive_library` | `Create_processor_in_the_loop_project`

**Default:** `Build_and_execute`

### Recommended Settings

Application	Setting
Debugging	<code>Build_and_execute</code>
Traceability	<code>Archive_library</code>
Efficiency	No impact
Safety precaution	No impact

### See Also

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

For more information about PIL, refer to “Using Processor-in-the-Loop” on page 4-3.

## Interrupt overrun notification method

Specifies how your program responds to overrun conditions during execution.

### Settings

**Default:** None

None

Your program does not notify you when it encounters an overrun condition.

Print\_message

Your program prints a message to standard output when it encounters an overrun condition.

Call\_custom\_function

When your program encounters an overrun condition, it executes a function that you specify in **Interrupt overrun notification function**.

### Tips

- The definition of the standard output depends on your configuration.
- The custom function must exist in the current working directory.

### Dependencies

Selecting `Call_custom_function` enables the **Interrupt overrun notification function** parameter.

Setting this parameter to `Call_custom_function` enables the **Interrupt overrun notification function** parameter.

### Command-Line Information

**Parameter:** `overrunNotificationMethod`

**Type:** string

**Value:** `None` | `Print_message` | `Call_custom_function`

**Default:** `None`



## Recommended Settings

Application	Setting
Debugging	Print_message or Call_custom_function
Traceability	Print_message
Efficiency	None
Safety precaution	No impact

## See Also

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## Interrupt overrun notification function

Specifies the name of a custom function your code runs when it encounters an overrun condition during execution.

### Settings

No Default

### Tips

Specify a function that exists in your current working directory.

### Dependencies

This parameter is enabled by setting **Interrupt overrun notification method** to `Call_custom_function`.

### Command-Line Information

**Parameter:** `overrunNotificationFcn`

**Type:** string

**Value:** no default

**Default:** no default

### Recommended Settings

Application	Setting
Debugging	String
Traceability	String
Efficiency	No impact
Safety precaution	No impact

### See Also

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## PIL block action

Specifies whether Real-Time Workshop software builds the PIL block and downloads the block to the processor

### Settings

**Default:** Create\_PIL\_block\_and\_download

Create\_PIL\_block\_build\_and\_download

Builds and downloads the PIL application to the processor after creating the PIL block. Adds PIL interface code that exchanges data with Simulink.

Create\_PIL\_block

Creates a PIL block, places the block in a new model, and then stops without building or downloading the block. The resulting project will not compile in the IDE.

None

Configures model to generate a VisualDSP++ software project that contains the PIL algorithm code. Does not build the PIL object code or block. The new project will not compile in the IDE.

### Tips

- When you click **Build** on the PIL dialog box, the build process adds the PIL interface code to the project and compiles the project in the IDE.
- If you select **Create PIL block**, you can build manually from the block right-click context menu
- After you select **Create PIL Block**, *copy* the PIL block into your model to replace the original subsystem. Save the original subsystem in a different model so you can restore it in the future. Click **Build** to build your model with the PIL block in place.
- *Add* the PIL block to your model to use cosimulation to compare PIL results with the original subsystem results. Refer to the demo “Getting Started with Application Development” in the product demos Embedded IDE Link VS

- When you select `None` or `Create_PIL_block`, the generated project will not compile in the IDE. To use the PIL block in this project, click **Build** followed by **Download** in the PIL block dialog box.

### Dependency

Enable this parameter by setting **Build action** to `Create_processor_in_the_loop_project`.

### Command-Line Information

**Parameter:** `configPILBlockAction`

**Type:** `string`

**Value:** `None` | `Create_PIL_block` |  
`Create_PIL_block_build_and_download`

**Default:** `Create_PIL_block`

### Recommended Settings

Application	Setting
Debugging	<code>Create_PIL_block_build_and_download</code>
Traceability	<code>Create_PIL_block_build_and_download</code>
Efficiency	<code>None</code>
Safety precaution	No impact

### See Also

For more information, refer to “Using Processor-in-the-Loop” on page 4-3.

## Maximum time allowed to build project (s)

Specifies how long, in seconds, the software waits for the project build process to return a completion message.

### Settings

**Default:** 1000

**Minimum:** 1

**Maximum:** No limit

### Tips

- The build process continues even if MATLAB does not receive the completion message in the allotted time.
- This time-out value does not depend on the global time-out value in a `adivdsp` object or the **Maximum time to complete IDE operations** time-out value.

### Dependency

This parameter is disabled when you set **Build action** to `Create_project`.

### Command-Line Information

**Parameter:**TBD

**Type:** int

**Value:** Integer greater than 0

**Default:** 100

### Recommended Settings

Application	Setting
Debugging	No impact
Traceability	No impact

<b>Application</b>	<b>Setting</b>
Efficiency	No impact
Safety precaution	No impact

**See Also**

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.

## Maximum time to complete IDE operations (s)

specifies how long the software waits for IDE functions, such as read or write, to return completion messages.

### Settings

**Default:** 10

**Minimum:** 1

**Maximum:** No limit

### Tips

- The IDE operation continues even if MATLAB does not receive the message in the allotted time. Click Chapter 6, “Functions — Alphabetical List” to see a list of the functions and methods.
- This time-out value does not depend on the global time-out value in a `adivdsp` object or the **Maximum time allowed to build project (s)** time-out value

### Command-Line Information

**Parameter:**TBD

**Type:** int

**Value:**

**Default:** 10

### Recommended Settings

Application	Setting
Debugging	No impact
Traceability	No impact
Efficiency	No impact
Safety precaution	No impact

**See Also**

For more information, refer to “Setting Embedded IDE Link VS Options” on page 3-22.



# Examples

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Use this list to find examples in the documentation.

## **Automation Interface**

“Getting Started with Automation Interface” on page 2-2

## **Working with adivdsp Objects**

“Example — Constructor for adivdsp Objects” on page 2-18

“Example — Setting Object Property Values at Construction” on page 2-21

“Example — Setting Object Property Values Using set” on page 2-22

“Example — Retrieving Object Property Values Using get” on page 2-22

## **Working with adivdsp objects**

“Example — Direct Property Referencing in Links” on page 2-22

## **Asynchronous Scheduler**

“Asynchronous Scheduler Examples” on page 3-12

“Idle Task” on page 3-15

“Hardware Interrupt Triggered Task” on page 3-16

## **Project Generator**

“Project Generator Tutorial” on page 3-17

## **Verification**

“PIL Block” on page 4-6

“Profiling Execution by Tasks” on page 4-12

“Profiling Execution By Subsystems” on page 4-15

“Profiling System Stack Use” on page 4-19



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