

# EDA Simulator Link™ MQ 2

## User's Guide



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*EDA Simulator Link™ MQ User's Guide*

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# Getting Started

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## Product Overview

In this section...
“Integration with Other Products” on page 1-2
“Hardware Description Language (HDL) Support” on page 1-4
“Linking with MATLAB and the HDL Simulator” on page 1-4
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“Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8

### Integration with Other Products

The EDA Simulator Link™ MQ cosimulation interface integrates MathWorks™ tools into the Electronic Design Automation (EDA) workflow. This integration enhances capabilities for field programmable gate array (FPGA) and application-specific integrated circuit (ASIC) development. The software provides a bidirectional link between the Mentor Graphics hardware description language (HDL) simulator, ModelSim™, and The MathWorks™ MATLAB® and Simulink® products. Such linking makes direct hardware design verification and cosimulation possible. The integration of these tools allows users to apply each product to the tasks it does best:

- ModelSim — Hardware modeling in HDL and simulation
- MATLAB — Numerical computing, algorithm development, and visualization
- Simulink — Simulation of system-level designs and complex models

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**Note** ModelSim software may also be referred to as *the HDL simulator* throughout this document.

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The EDA Simulator Link MQ software consists of MATLAB functions and HDL simulator commands that establish communication links between the HDL simulator and The MathWorks products. In addition, the link software

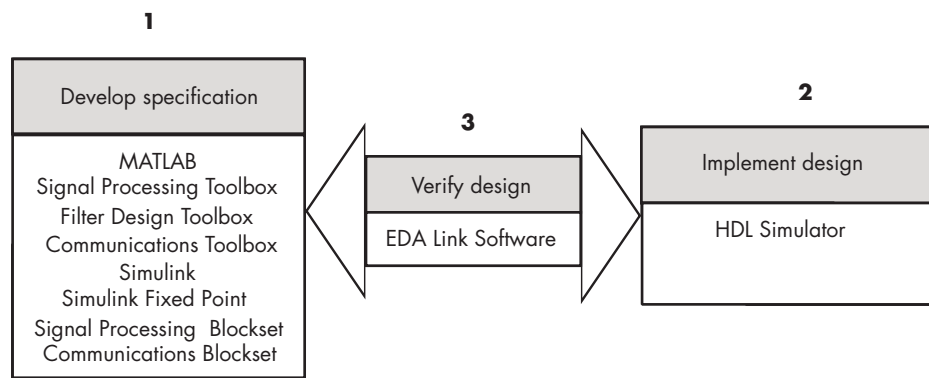


contains a library of Simulink blocks that you may use to include HDL simulator designs in Simulink models for cosimulation.

EDA Simulator Link MQ software streamlines FPGA and ASIC development by integrating tools available for these processes:

- 1** Developing specifications for hardware design reference models
- 2** Implementing a hardware design in HDL based on a reference model
- 3** Verifying the design against the reference design

The following figure shows how the HDL simulator and MathWorks products fit into this hardware design scenario.



As the figure shows, EDA Simulator Link MQ software connects tools that traditionally have been used discretely to perform specific steps in the design process. By connecting these tools, the link simplifies verification by allowing you to cosimulate the implementation and original specification directly. This cosimulation results in significant time savings and the elimination of errors inherent to manual comparison and inspection.

In addition to the preceding design scenario, EDA Simulator Link MQ software enables you to work with tools in the following ways:

- Use MATLAB or Simulink to create test signals and software test benches for HDL code
- Use MATLAB or Simulink to provide a behavioral model for an HDL simulation
- Use MATLAB analysis and visualization capabilities for real-time insight into an HDL implementation
- Use Simulink to translate legacy HDL descriptions into system-level views

---

**Note** You can cosimulate a module using SystemVerilog, SystemC or both with MATLAB or Simulink using the EDA Simulator Link MQ software. Write simple wrappers around the SystemC and make sure that the SystemVerilog cosimulation connections are to ports or signals of data types supported by the link cosimulation interface.

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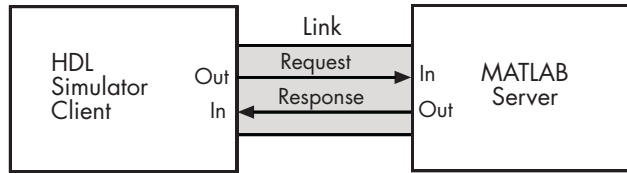
## Hardware Description Language (HDL) Support

All EDA Simulator Link MQ MATLAB functions and the HDL Cosimulation block offer the same language-transparent feature set for both Verilog and VHDL models.

EDA Simulator Link MQ software also supports mixed-language HDL models (models with both Verilog and VHDL components), allowing you to cosimulate VHDL and Verilog signals simultaneously. Both MATLAB and Simulink software can access components in different languages at any level.

## Linking with MATLAB and the HDL Simulator

When linked with MATLAB, the HDL simulator functions as the client, as the following figure shows.

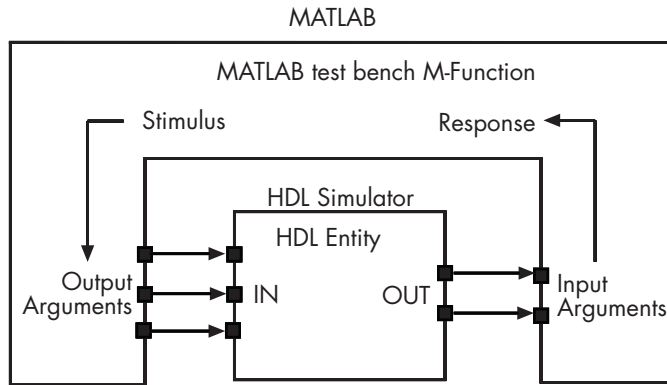


In this scenario, a MATLAB server function waits for service requests that it receives from an HDL simulator session. After receiving a request, the server establishes a communication link and invokes a specified MATLAB function that computes data for, verifies, or visualizes the HDL module (coded in VHDL or Verilog) that is under simulation in the HDL simulator.

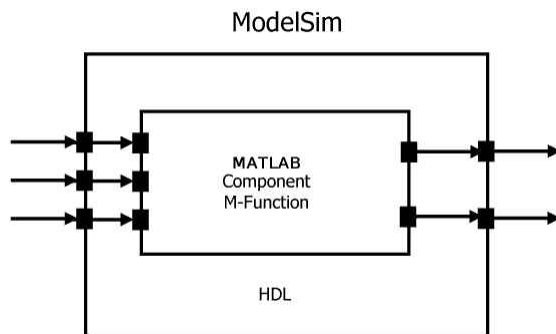
After the server is running, you can start and configure the HDL simulator or use with MATLAB with the supplied EDA Simulator Link MQ function `vsim`. Required and optional parameters allow you to specify the following:

- Tcl commands that execute as part of startup
- A specific ModelSim executable to start
- The name of a ModelSim DO file to store the complete startup script for future use or reference

The following figure shows how a MATLAB test bench function wraps around and communicates with the HDL simulator during a test bench simulation session.



The following figure shows how a MATLAB component function is wrapped around by and communicates with the HDL simulator during a component simulation session.



During the configuration process, EDA Simulator Link MQ software equips the HDL simulator with a set of customized command extensions you use to perform the following tasks:

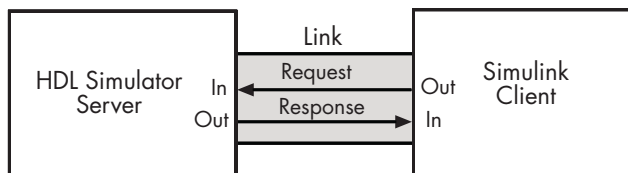
- Load the HDL simulator with an instance of an HDL module to be tested with MATLAB
- Begin a MATLAB test bench or component session for that instance

When you begin a specific test bench session, you specify parameters that identify the following information:

- The mode and, if appropriate, TCP/IP data necessary for connecting to a MATLAB server
- The MATLAB function that is associated with and executes on behalf of the HDL instance
- Timing specifications and other control data that specifies when the module's MATLAB function is to be called

## Linking with Simulink and the HDL Simulator

When linked with Simulink, the HDL simulator functions as the server, as shown in the following figure.



In this case, the HDL simulator responds to simulation requests it receives from cosimulation blocks in a Simulink model. You begin a cosimulation session from Simulink. After a session is started, you can use Simulink and the HDL simulator to monitor simulation progress and results. For example, you might add signals to an HDL simulator Wave window to monitor simulation timing diagrams.

Using the Block Parameters dialog box for an HDL Cosimulation block, you can configure the following:

- Block input and output ports that correspond to signals (including internal signals) of an HDL module. You can specify sample times and fixed-point data types for individual block output ports if desired.

- Type of communication and communication settings used for exchanging data between the simulation tools.
- Rising-edge or falling-edge clocks to apply to your module. The period of each clock is individually specifiable.
- Tcl commands to run before and after the simulation.

EDA Simulator Link MQ software equips the HDL simulator with a set of customized command extensions. Using the supplied command extension `vsimulink`, you execute the HDL simulator with an instance of an HDL module for cosimulation with Simulink. After the module is loaded, you can start the cosimulation session from Simulink.

EDA Simulator Link MQ software also includes a block for generating value change dump (VCD) files. You can use VCD files generated with this block to perform the following tasks:

- View Simulink simulation waveforms in your HDL simulation environment
- Compare results of multiple simulation runs, using the same or different simulation environments
- Use as input to post-simulation analysis tools

## **Communicating with MATLAB or Simulink and the HDL Simulator**

The mode of communication that you use for a link between the HDL simulator and MATLAB or Simulink depends on whether your simulation application runs in a local, single-system configuration or in a network configuration. If the HDL simulator and The MathWorks products can run locally on the same system and your application requires only one communication channel, you have the option of choosing between shared memory and TCP/IP socket communication. Shared memory communication provides optimal performance and is the default mode of communication.

TCP/IP socket mode is more versatile. You can use it for single-system and network configurations. This option offers the greatest scalability. For more on TCP/IP socket communication, see “Specifying TCP/IP Socket Communication” on page 7-13.

## Requirements

In this section...
“What You Need to Know” on page 1-9
“Required Products” on page 1-9

### What You Need to Know

The documentation provided with the EDA Simulator Link MQ software assumes users have a moderate level of prerequisite knowledge in the following subject areas:

- Hardware design and system integration
- VHDL and/or Verilog
- ModelSim simulators
- MATLAB

Experience with Simulink and Simulink Fixed Point software is required for applying the Simulink component of the product.

Depending on your application, experience with the following MATLAB toolboxes and Simulink blocksets might also be useful:

- Signal Processing Toolbox™
- Filter Design Toolbox™
- Communications Toolbox™
- Signal Processing Blockset™
- Communications Blockset™
- Video and Image Processing Blockset™

### Required Products

EDA Simulator Link MQ software requires the following:

**Platform** Visit the EDA Simulator Link MQ requirements page on The MathWorks Web site for specific platforms supported with the current release.

**Application software** Requires ModelSim SE/PE, a Mentor Graphics product.  
Visit the EDA Simulator Link MQ requirements page on The MathWorks Web site for specific versions supported with the current release.

**Application software required for cosimulation** MATLAB  
Simulink  
Simulink Fixed Point  
Fixed-Point Toolbox

**Optional application software** Communications Blockset  
Signal Processing Blockset  
Filter Design Toolbox  
Signal Processing Toolbox  
Video and Image Processing Blockset

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**Note** Many EDA Simulator Link MQ demos require one or more of the optional products listed.

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**Platform-specific software** On the Linux platform, the `gcc c++` libraries (3.2 or later) are required by the EDA Simulator Link MQ software. You should install a recent version of the `gcc c++` library on your computer. To determine which libraries are installed on your computer, type the command:

```
gcc -v
```



# Setting Up Your Environment for the EDA Simulator Link MQ Software

## In this section...

“Installing the Link Software” on page 1-11

“Installing Related Application Software” on page 1-11

“Setting Up the HDL Simulator for Use with the Link Software” on page 1-11

“Using the EDA Simulator Link MQ Libraries” on page 1-17

## Installing the Link Software

For details on how to install the EDA Simulator Link MQ software, see the MATLAB installation instructions.

## Installing Related Application Software

Based on your configuration decisions and the software required for your EDA Simulator Link MQ application, identify software you need to install and where you need to install it. For example, if you need to run multiple instances of the link MATLAB server on different machines, you need to install MATLAB and any applicable toolbox software on multiple systems. Each instance of MATLAB can run only one instance of the server.

For details on how to install the HDL simulator, see the installation instructions for that product. For information on installing and activating MathWorks products, see the MATLAB installation and activation instructions.

## Setting Up the HDL Simulator for Use with the Link Software

EDA Simulator Link MQ software provides a guided set-up script (syscheckmq) for configuring your simulator. This script works whether you have installed the link software and MATLAB on the same machine as the HDL simulator or installed them on different machines.

The set-up script creates a configuration file containing the location of the appropriate EDA Simulator Link MQ MATLAB and Simulink libraries. You can then include this configuration with any other calls you make using the command `vsim` from the HDL simulator. You only need to run this script once.

---

**Note** The EDA Simulator Link MQ configuration and diagnostic script works only on UNIX and Linux. Windows users: please see instructions below.

---

If you plan to use the MATLAB `vsim.m` function instead, no setup is required.

Refer to “Using the EDA Simulator Link MQ Libraries” on page 1-17 for the correct link application library for your platform. Then see “Starting the HDL Simulator from MATLAB” on page 1-22.

After you have created your configuration files, see “Starting the ModelSim Software from a Shell” on page 1-24.

### Using the Configuration and Diagnostic Script for UNIX/Linux

`syscheckmq` provides an easy way to configure your simulator setup to work with the EDA Simulator Link MQ software.

The following is an example of running `syscheckmq` on a Linux 64 machine with EDA Simulator Link MQ libraries in a different location than where they were first installed and specifying a TCP/IP connection.

Start `syscheckmq`:

```
% syscheckmq
*****

Kernel name: Linux
Kernel release: 2.6.11.4-20a-smp
Machine: x86_64
*****
```

The script first returns the location of the HDL simulator installation (`vsim.exe`). If it does not find an installation, you receive an error message. Either provide the path to the installation or quit the script and install the HDL simulator. You are then prompted to accept this installation or provide a path to another one, after which you receive a message confirming the HDL simulator installation:

```
Found /hub/share/apps/ModelSim/v60e/se/modeltech/bin/vsim on the path.
Press Enter to use the path we found or enter another one:
```

```
*****

/hub/share/apps/ModelSim/v60e/se/modeltech/bin/vsim -version
Model Technology ModelSim SE-64 vsim 6.0e Simulator 2005.06 Jun 17 2005
ModelSim mode: 32 bits
*****
```

Next, the script needs to know if the EDA Simulator Link MQ libraries are in the default directory (where they were first installed) or if you have moved them to another directory. If you have the HDL simulator and MATLAB on separate machines, move the link libraries to the machine with the HDL simulator.

```
Select method to search for EDA Simulator Link MQ libraries:
1. Use libraries installed with EDA Simulator Link MQ.
2. Prompt me to specify the direct path to the libraries.
2
Enter the path to liblfmhd1c_gcc41.so and liblfmhd1s_gcc41.so:
/tmp/lfmconfig/linux64
Found /tmp/lfmconfig/linux64/liblfmhd1c_gcc41.so
and /tmp/lfmconfig/linux64/liblfmhd1s_gcc41.so.
```

The script then runs a dependency checker to check for supporting libraries. If any of the libraries cannot be found, you probably need to append your environment path to find them.

```
*****

Running dependency checker "ldd /tmp/lfmconfig/linux64/liblfmhd1c_gcc41.so".
Dependency checker passed.
```

```
Dependency status:
  librt.so.1 => /lib64/tls/librt.so.1 (0x00002aaaaac0a000)
  libpthread.so.0 => /lib64/tls/libpthread.so.0 (0x00002aaaaad12000)
  libstdc++.so.6 => /devel/Ahdl/nightly/matlab/sys/os/glnxa64/libstdc++.so
.6 (0x00002aaaaae27000)
  libm.so.6 => /lib64/tls/libm.so.6 (0x00002aaaaab029000)
  libgcc_s.so.1 => /devel/Ahdl/nightly/matlab/sys/os/glnxa64/libgcc_s.so.1
(0x00002aaaaab180000)
  libc.so.6 => /lib64/tls/libc.so.6 (0x00002aaaaab28d000)
  /lib64/ld-linux-x86-64.so.2 (0x0000555555555000)
*****
```

This next step loads the EDA Simulator Link MQ libraries and compiles a test module to verify the libraries loaded correctly.

Press Enter to load EDA Simulator Link MQ or enter 'n' to skip this test:

```
Reading /mathworks/hub/share/apps/ModelSim/v60e/se/modeltech/linux_x86_64/./modelsim.ini
"worklfx24154" maps to directory worklfx24154. (Default mapping)
Model Technology ModelSim SE-64 vlog 6.0e Compiler 2005.06 Jun 17 2005
-- Compiling module d24154
```

Top level modules:

d24154

\*\*\*\*\*

```
Reading /mathworks/hub/share/apps/ModelSim/v60e/se/modeltech/tcl/vsim/pref.tcl
```

# 6.0e

```
# vsim -do exit -foreign {matlabclient /tmp/lfmconfig/linux64/liblfmhdlc_gcc41.so}
-c worklfx24154.d24154
```

```
# // ModelSim SE-64 6.0e Jun 17 2005 Linux 2.6.11.4-20a-smp
```

```
# //
```

```
# // Copyright Mentor Graphics Corporation 2005
```

```
# // All Rights Reserved.
```

```
# //
```

```
# // THIS WORK CONTAINS TRADE SECRET AND
```

```
# // PROPRIETARY INFORMATION WHICH IS THE PROPERTY
```

```

# // OF MENTOR GRAPHICS CORPORATION OR ITS LICENSORS
# // AND IS SUBJECT TO LICENSE TERMS.
# //
# Loading worklfx24154.d24154
# Loading /tmp/lfmconfig/linux64/liblfmhdlc_gcc41.so
# exit

*****

EDA Simulator Link MQ libraries loaded successfully.
*****

```

Next, the script checks a TCP connection. If you choose to skip this step, the configuration file specifies use of shared memory. Both shared memory and socket configurations are in the configuration file; depending on your choice, one configuration or the other is commented out.

Press Enter to check for TCP connection or enter 'n' to skip this test:

Enter an available port [5001]

Enter remote host [localhost]

Press Enter to continue

```

ttcp_glnx -t -p5001 localhost
Connection successful

```

Lastly, the script creates the configuration file, unless for some reason you choose not to do so at this time.

```

*****

Press Enter to Create Configuration files or 'n' to skip this step:

*****

Created template files simulink24255.arg and matlab24255.arg. Inspect and modify
if necessary.
*****

```

Diagnosis Completed

The template file names, in this example `simulink24255.arg` and `matlab24255.arg`, have different names each time you run this script.

After the script is complete, you can leave the configuration files where they are or move them to wherever it is convenient.

## Using the Configuration and Diagnostic Script with Windows

`syscheckmq` does not run on Windows. To use the configuration script on Windows, create two files according to the following instructions:

- 1 Create a MATLAB configuration file. You may name it whatever you like; there are no file-naming restrictions. Enter the following text:

```
//Command file for MATLAB EDA Simulator Link MQ.  
//Loading of foreign Library, usage example: vsim -f matlab14455.arg entity.  
//You can manually change the following line to point to the correct library.  
//The default location of the 32-bit Windows library is at  
//MATLABROOT/toolbox/modelsim/windows32/liblfmhdc_vs05.dll.  
  
-foreign "matlabclient c:/path/liblfmhdc_vs05.dll"
```

where *path* is the path to the particular EDA Simulator Link MQ shared library you want to invoke (in this example. See “Using the EDA Simulator Link MQ Libraries” on page 1-17).

For more information on the `-foreign` option, refer to your ModelSim documentation.

The comments in the above text are optional.

- 2 Create a Simulink configuration file and name it. There are no file-naming restrictions. Enter the following text:

```
//Command file for Simulink EDA Simulator Link MQ.  
//Loading of foreign Library, usage example: vsim -f simulink14455.arg entity.  
//You can manually change the following line to point to the correct library.  
//For example the default location of the 32-bit Windows library is at
```

```
//MATLABROOT/toolbox/modelsim/windows32/liblfmhds_vs05.so.  
  
//For socket connection uncomment and modify the following line:  
-foreign "simlinkserver c:/path/liblfmhds_vs05.so ; -socket 5001"  
  
//For shared connection uncomment and modify the following line:  
//-foreign "simlinkserver c:/path/liblfmhds_vs05.so"
```

Where *path* is the path to the particular EDA Simulator Link MQ shared library you want to invoke. See “Using the EDA Simulator Link MQ Libraries” on page 1-17.

---

**Note** If you are going to use a TCP/IP socket connection, first confirm that you have an available port to put in this configuration file. Then, comment out whichever type of communication you will not be using.

---

The comments in the above text are optional.

After you have finished creating the configuration files, you can leave the files where they are or move them to another location that is convenient.

## Using the EDA Simulator Link MQ Libraries

In general, you want to use the same compiler for all libraries linked into the same executable. The link software provides many versions of the same library compilers that are available with the HDL simulators (usually some version of GCC). Using the same libraries ensures compatibility with other C++ libraries that may get linked into the HDL simulator, including SystemC libraries.

If you have any of these conditions, choose the version of the EDA Simulator Link MQ library that matches the compiler used for that code:

- Link other third-party applications into your HDL simulator.
- Compile and link in SystemC code as part of your design or testbench.
- Write custom C/C++ applications and link them into your HDL simulator.

If you do not link any other code into your HDL simulator, you can use any version of the supplied libraries. The MATLAB `vsim` command chooses a default version of this library.

For examples on specifying EDA Simulator Link MQ libraries when cosimulating across a network, see “Performing Cross-Network Cosimulation” on page 7-5.

## Library Names

The EDA Simulator Link MQ HDL libraries use the following naming format:

```
productdir/arch/lib{product_short_name}{client_server_tag}_{compiler_tag}.{libext}
```

where

<code>productdir</code>	<code>modelsim</code>
<code>arch</code>	<code>linux32</code> , <code>linux64</code> , <code>solaris32</code> , <code>solaris64</code> , or <code>windows32</code>
<code>product_short_name</code>	<code>lfmhdl</code>
<code>client_server_tag</code>	<code>c</code> or <code>s</code> (MATLAB or Simulink)
<code>compiler_tag</code>	<code>gcc323</code> , <code>gcc33</code> , <code>gcc331</code> , <code>gcc402</code> , <code>gcc412</code> , <code>gcc421</code> , <code>tmwgcc</code> , <code>tmwspro</code> , <code>tmwvs</code>
<code>libext</code>	<code>dll</code> or <code>so</code>

Not all combinations are supported. See “Default Libraries” on page 1-18 for valid combinations.

For more on MATLAB build compilers, see MATLAB Build Compilers — Release 2009a.

## Default Libraries

EDA Simulator Link MQ scripts fully support the use of default libraries.

The following table lists all the libraries shipped with the link software. The default libraries for each platform are in bold text.



<b>Platform</b>	<b>MATLAB Library</b>	<b>Simulink Library</b>
Linux32	<b>liblfmhdlc_tmwgcc.so</b> liblfmhdlc_gcc323.so liblfmhdlc_gcc402.so liblfmhdlc_gcc412.so	<b>liblfmhdls_tmwgcc.so</b> liblfmhdls_gcc323.so liblfmhdls_gcc402.so liblfmhdls_gcc412.so
Linux 64	<b>liblfmhdlc_tmwgcc.so</b> liblfmhdlc_gcc402.so liblfmhdlc_gcc412.so	<b>liblfmhdls_tmwgcc.so</b> liblfmhdls_gcc402.so liblfmhdls_gcc412.so
Solaris32	<b>liblfmhdlc_tmwspro.so</b> liblfmhdlc_gcc33.so liblfmhdlc_gcc412.so	<b>liblfmhdls_tmwspro.so</b> liblfmhdls_gcc33.so liblfmhdls_gcc412.so
Solaris64	<b>liblfmhdlc_tmwspro.so</b>	<b>liblfmhdls_tmwspro.so</b>
Windows32	<b>liblfmhdlc_tmwvs.dll</b> liblfmhdlc_gcc323.dll liblfmhdlc_gcc331.dll liblfmhdlc_gcc421.dll	<b>liblfmhdls_tmwvs.dll</b> liblfmhdls_gcc323.dll liblfmhdls_gcc331.dll liblfmhdls_gcc421.dll

## Using an Alternative Library

You can use a different HDL-side library by specifying it explicitly using the `libfile` parameter to the `vsim` MATLAB command. You should choose the version of the library that matches the compiler and system libraries you are using for any other C/C++ libraries linked into the HDL simulator. Depending on the version of your HDL simulator, you may need to explicitly set additional paths in the `LD_LIBRARY_PATH` environment variable.

For example, if you want to use a nondefault library:

- 1 Copy the system libraries from the MATLAB installation (found in `matlabroot/sys/os/platform`) to the machine with the HDL simulator (where `matlabroot` is your MATLAB installation and `platform` is one of the above architecture, e.g., `linux32`).

- 2 Modify the `LD_LIBRARY_PATH` environment variable to add the path to the system libraries that were copied in step 1.

**Example: EDA Simulator Link MQ Alternative Library Using vsim.** In this example, you run the 32-bit Solaris version of ModelSim 6 software on the same 64-bit Solaris machine which is running MATLAB. Because you want to incorporate some SystemC designs, you are using the EDA Simulator Link MQ version compiled with GCC 3.3. You can download the appropriate version of GCC with its associated system libraries from Mentor Graphics, instead of using the default library version compiled with SunPro 11.

In MATLAB:

```
>> currPath = getenv('PATH');
>> currLdPath = getenv('LD_LIBRARY_PATH');
>> setenv('PATH', ['/tools/modelsim-6.1e/bin:' currPath]);
>> setenv('LD_LIBRARY_PATH', ['/tools/mtigcc/gcc-3.3-sunos510/lib:' currLdPath]);
>> setenv('MTI_VCO_MODE', '32');
>> vsim('tclstart', { 'vlib work', 'vcom inverter.vhd', 'vsimulink inverter' }, ...
        'libfile', 'liblfmhds_gcc33');
```

You change the *PATH* to ensure that you get the correct version of the ModelSim software. You change the *LD\_LIBRARY\_PATH* because the HDL simulator does not automatically add the necessary path to the system libraries. The EDA Simulator Link MQ function `vsim` automatically detects the use of the 32-bit version of the HDL simulator and uses the `solaris32` library directory in the link software installation; there is no need to specify the `libdir` parameter in this case.

The library resolution can be verified using `ldd` from within the ModelSim GUI:

```
vsim> exec ldd /path/to/liblfmhds_gcc33.so
#      librt.so.1 =>      /lib/librt.so.1
#      libpthread.so.1 => /lib/libpthread.so.1
#      libstdc++.so.5 =>  /tools/mtigcc/gcc-3.3-sunos510/lib/libstdc++.so.5
#      libm.so.2 =>      /lib/libm.so.2
#      libgcc_s.so.1 =>  /tools/mtigcc/gcc-3.3-sunos510/lib/libgcc_s.so.1
#      libaio.so.1 =>    /lib/libaio.so.1
#      libmd5.so.1 =>    /lib/libmd5.so.1
```

```
#      libc.so.1 =>          /lib/libc.so.1
#      /platform/SUNW,Sun-Blade-1000/lib/libmd5_psr.so.1
#      /platform/SUNW,Sun-Blade-1000/lib/libc_psr.so.1
```

### **Example: EDA Simulator Link MQ Alternate Library Using System Shell.**

This example shows how to load a ModelSim session by explicitly specifying the EDA Simulator Link MQ library (either the default or one of the alternatives). By explicitly using a system shell, you can execute this example on the same machine as MATLAB, on a different machine, and even on a machine with a different operating system.

In this example, you are running the 64-bit Linux version of QuestaSim 6.2c. It does not matter which machine is running MATLAB. Instead of using the EDA Simulator Link MQ default library version compiled with GCC 4.1.1, you are using the version compiled with GCC 4.0.2. You can download the appropriate version of GCC with its associated system libraries from Mentor Graphics.

In a csh-compatible system shell:

```
csh> setenv PATH /tools/modelsim-6.2c/bin:${PATH}
csh> setenv LD_LIBRARY_PATH /tools/mtigcc/gcc-4.0.2-linux_x86_64/lib64:${LD_LIBRARY_PATH}
csh> setenv MTI_VCO_MODE 64
csh> vlib work
csh> vcom +acc+inverter inverter.vhd
csh> vsim +acc+inverter -foreign
      "matlabclient /tools/matlab-7b/toolbox/modelsim/linux64/liblfmhdlc_gcc402.so" inverter.vhd
```

You change the *PATH* to ensure that you get the correct version of the ModelSim software. You change the *LD\_LIBRARY\_PATH* because the HDL simulator does not automatically add the necessary path to the system libraries unless you are working with 6.2+ and have placed GCC at the root of the ModelSim installation.

You can check the proper library resolution using `ldd` as in the previous example.

## Starting the HDL Simulator

In this section...
“Starting the HDL Simulator from MATLAB” on page 1-22
“Starting the ModelSim Software from a Shell” on page 1-24

### Starting the HDL Simulator from MATLAB

Start the ModelSim HDL simulator simulator directly from MATLAB or Simulink by calling the MATLAB function `vsim`. This function starts and configures the HDL simulator for use with the EDA Simulator Link MQ software. By default, the function starts the first version of the simulator executable (`vsim.exe`) that it finds on the system path (defined by the `path` variable), using a temporary `D0` file that is overwritten each time the HDL simulator starts.

---

**Note** If you want to start a different version of the simulator executable than the first one found on the system path, use the `setenv` and `getenv` MATLAB functions to set and get the environment of any sub-shells spawned by `UNIX()`, `DOS()`, or `system()`.

---

To start the HDL simulator from MATLAB, enter `vsim` at the MATLAB command prompt:

```
>> vsim
```

You can customize the `D0` startup file and communication mode to be used between MATLAB or Simulink and the HDL simulator by specifying the call to `vsim` with property name/property value pairs. Refer to `vsim` reference documentation for specific information regarding the property name/property value pairs.

See “Examples of Starting the ModelSim Simulator from MATLAB” on page 1-23 for examples of using `vsim` with various property/name value pairs and other parameters.

When you specify a communication mode using `vsim`, the function applies the specified communication mode to all MATLAB or Simulink/HDL simulator sessions.

### Examples of Starting the ModelSim Simulator from MATLAB

The following example changes the directory location to `VHDLproj` and then calls the function `vsim`. Because the command line omits the `'vsimdir'` and `'startupfile'` properties, `vsim` creates a temporary DO file. The `'tclstart'` property specifies Tcl commands that load and initialize the HDL simulator for test bench instance `modsimrand`.

```
cd VHDLproj
vsim('tclstart',...
     'vsimmatlab modsimrand; matlabtb modsimrand 10 ns -socket 4449')
```

The following example changes the directory location to `VHDLproj` and then calls the function `vsim`. Because the function call omits the `'vsimdir'` and `'startupfile'` properties, `vsim` creates a temporary DO file. The `'tclstart'` property specifies a Tcl command that loads the VHDL entity parse in library work for cosimulation between `vsim` and Simulink. The `'socketsimulink'` property specifies TCP/IP socket communication on the same computer, using socket port 4449.

```
cd VHDLproj
vsim('tclstart', 'vsimulink work.parse', 'socketsimulink', '4449')
```

The following example has the HDL compilation and simulation commands run automatically when you start the ModelSim software from MATLAB.

```
vsim('tclstart',
     {'vlib work', 'vlog +acc clocked_inverter.v hdl_top.v', 'vsim +acc hdl_top' });
```

This next example loads the HDL simulation just as in the previous example but it also loads in the Link to Simulink library, uses socket number 5678 to communicate with cosimulation blocks in Simulink models, and uses an HDL time precision of 10 ps.

```
vsim('tclstart',
     {'vlib work', 'vlog -novopt clocked_inverter.v hdl_top.v',
      'vsimulink hdl_top -socket 5678 -t 10ps'});
```

Or

```
vsim('tclstart',  
      {'vlib work', 'vlog -novopt clocked_inverter.v hdl_top.v',  
       'vsimulink hdl_top -t 10ps'},  
      'socketsimulink', 5678);
```

## Starting the ModelSim Software from a Shell

To start the HDL simulator from a shell and include the EDA Simulator Link MQ libraries, you need to first run the configuration script. See “Setting Up the HDL Simulator for Use with the Link Software” on page 1-11.

After you have the configuration files, you can start the ModelSim software from the shell by typing:

```
% vsim -f matlabconfigfile
```

*matlabconfigfile* should be the name of the MATLAB configuration file you created with `syscheckmq` (Linux/UNIX) or that you created yourself using our template (Windows). If you are connecting to Simulink, this should be the name of the Simulink configuration file. You must also specify the path to the configuration file even if it resides in the same directory as `vsim.exe`.

The configuration file mainly defines the `-foreign` option to `vsim` which in turn loads the EDA Simulator Link MQ shared library and specifies its entry point.

You can also specify any other existing configuration files you may also be using with this call.

If you are performing this step manually, the following use of `-foreign` with `vsim` loads the EDA Simulator Link MQ client shared library and specifies its entry point:

```
% vsim -foreign matlabclient /path/library
```

where *path* is the path to this particular EDA Simulator Link MQ library. See “Using the EDA Simulator Link MQ Libraries” on page 1-17 to find the correct library name for your machine.

---

**Note** You can also issue this exact same command from inside the HDL simulator.

---

## Learning More About the EDA Simulator Link MQ Software

In this section...
“Documentation Overview” on page 1-26
“Online Help” on page 1-27
“Demos and Tutorials” on page 1-28

### Documentation Overview

The following documentation is available with this product.

Chapter 1, “Getting Started”	Explains what the product is, the steps for installing and setting it up, how you might apply it to the hardware design process, and how to gain access to product documentation and online help. Directs you to product demos and tutorials.
Chapter 2, “Simulating an HDL Component in a MATLAB Test Bench Environment”	Explains how to code HDL models and MATLAB test bench functions for EDA Simulator Link MQ MATLAB applications. Provides details on how the link interface maps HDL data types to MATLAB data types and vice versa. Explains how to start and control HDL simulator and MATLAB test bench sessions.
Chapter 3, “Replacing an HDL Component with a MATLAB Component Function”	Discusses the same topics as the chapter for test bench cosimulation using MATLAB software but instead using MATLAB to visualize an HDL module component.
Chapter 4, “Simulating an HDL Component in a Simulink Test Bench Environment”	Explains how to use the HDL simulator and Simulink for cosimulation modeling where Simulink acts as the test bench.



Chapter 6, “Recording Simulink Signal State Transitions for Post-Processing”	Provides instruction for adding a Value Change Dump (VCD) file block to your Simulink model for signal state change capture.
Chapter 7, “Additional Deployment Options”	Contains several procedures for more complex cosimulation arrangements.
Chapter 8, “Advanced Operational Topics”	Contains a variety of topics that provide a deeper understanding of how cosimulation works.
Chapter 9, “M-Function Prototype Reference”	Describes how to use the input and output arguments to an M-function created for use with the EDA Simulator Link MQ commands <code>matlabtb</code> and <code>matlabcp</code> .
Chapter 10, “Functions — Alphabetical List”	Describes EDA Simulator Link MQ functions for use with MATLAB.
Chapter 11, “HDL Simulator Command Extensions — Alphabetical List”	Describes EDA Simulator Link MQ commands for use with the HDL simulator.
Chapter 12, “Blocks — Alphabetical List”	Describes EDA Simulator Link MQ blocks for use with Simulink.

## Online Help

The following online help is available:


- Online help in the MATLAB Help browser. Click the EDA Simulator Link MQ product link in the browser’s Contents or access using the MATLAB `doc` command at the MATLAB command prompt:

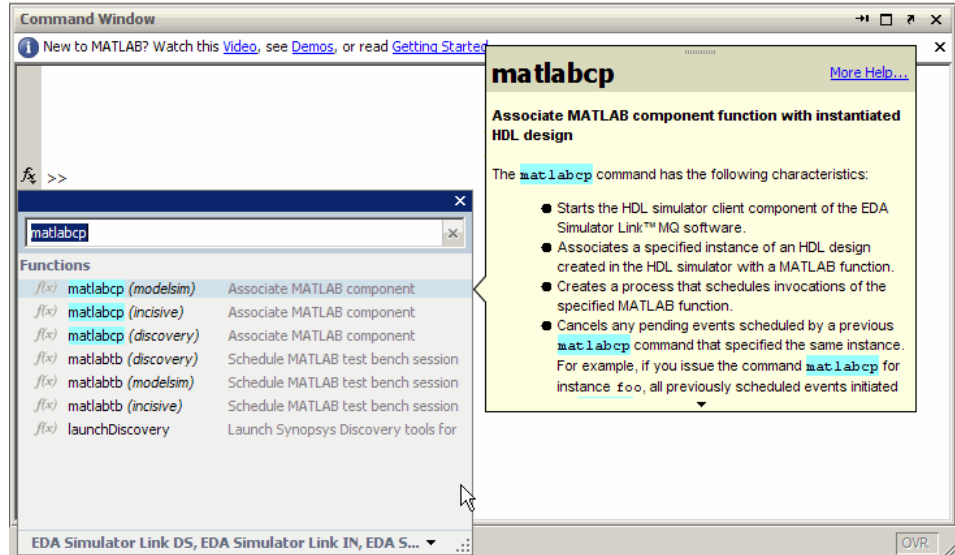
```
doc hdldaemon
```

- M-help for EDA Simulator Link MQ MATLAB functions and HDL simulator commands. This help is accessible with the MATLAB `help` command. For example, enter the command

```
help hdldaemon
```

at the MATLAB command prompt.

- Function help in the MATLAB command window by clicking the  icon:



- Block reference pages accessible through the Simulink interface.

## Demos and Tutorials

The EDA Simulator Link MQ software provides demos and tutorials to help you get started.

The demos give you a quick view of the product’s capabilities and examples of how you might apply the product. You can run them with limited product exposure. You can find the EDA Simulator Link MQ demos with the online documentation. To access demos, type at the MATLAB command prompt:

```
>> demos
```

Select **Links and Targets > EDA Simulator Link™ MQ** from the navigational pane.

Tutorials provide procedural instruction on how to apply the product. Some focus on features while others focus on application scenarios. The tutorials

listed here have a feature focus and addresses the use of the EDA Simulator Link MQ software with the ModelSim and Simulink products.

- “Tutorial – Running a Sample ModelSim and MATLAB Test Bench Session” on page 2-36
- “Tutorial — Verifying an HDL Model Using Simulink, ModelSim, and the EDA Simulator Link MQ Software” on page 4-46
- “To VCD File Block Tutorial” on page 6-6



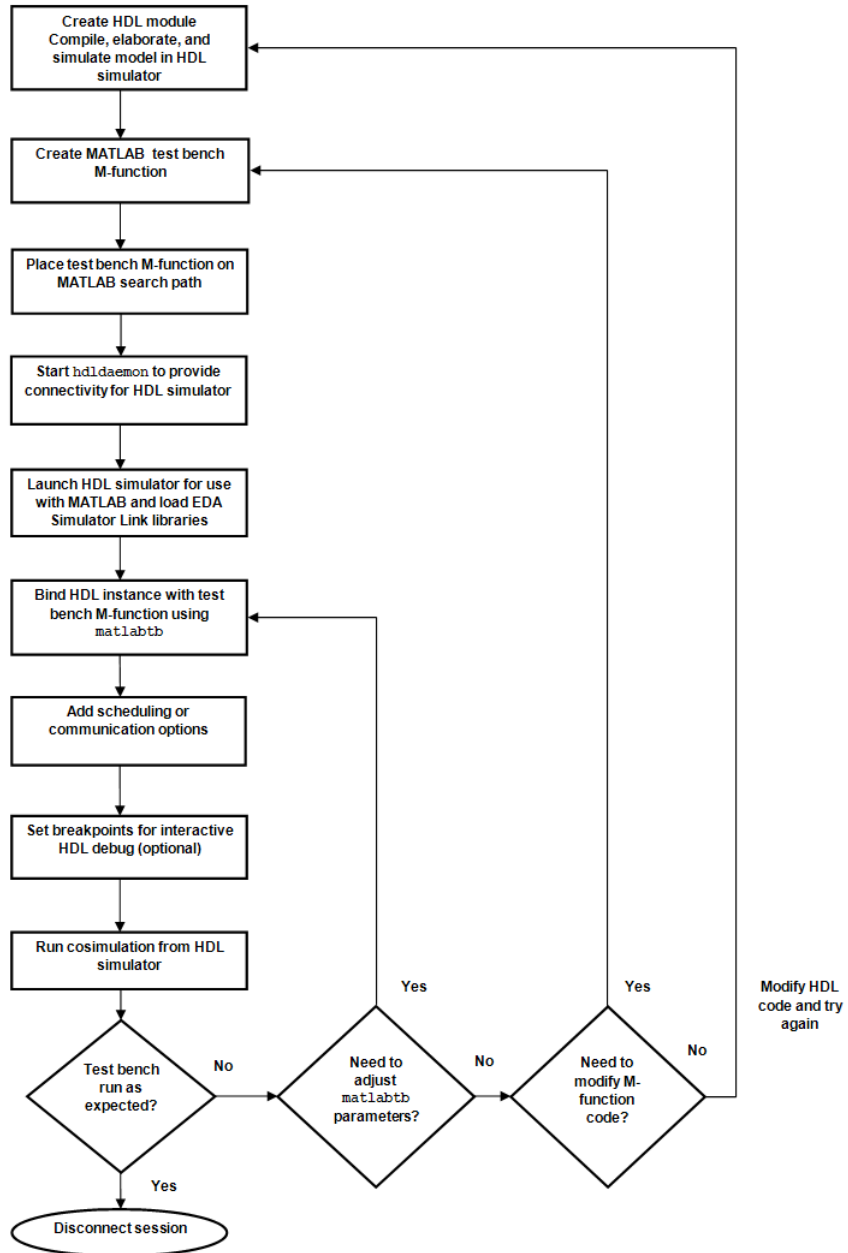
# Simulating an HDL Component in a MATLAB Test Bench Environment

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- “Workflow for Simulating an HDL Component with a MATLAB Test Bench Function” on page 2-2
- “Overview to Using MATLAB as a Test Bench” on page 2-5
- “Code HDL Modules for Verification Using MATLAB ” on page 2-7
- “Code an EDA Simulator Link MQ MATLAB Test Bench Function” on page 2-12
- “Place Test Bench Function on MATLAB Search Path” on page 2-22
- “Start hlldaemon to Provide Connection to HDL Simulator” on page 2-23
- “Launch HDL Simulator for Use with MATLAB” on page 2-25
- “Invoke matlabtb to Bind and Schedule MATLAB Test Bench Function Calls” on page 2-26
- “Run MATLAB Test Bench Simulation” on page 2-31
- “Stop Test Bench Simulation” on page 2-35
- “Tutorial – Running a Sample ModelSim and MATLAB Test Bench Session” on page 2-36

# **Workflow for Simulating an HDL Component with a MATLAB Test Bench Function**

The following workflow shows the steps necessary to create a MATLAB test bench session for cosimulation with the HDL simulator using EDA Simulator Link MQ.



The workflow is as follows:

- Create HDL module. Compile, elaborate, and simulate model in HDL simulator.
- Create MATLAB test bench M-function.
- Place test bench function on MATLAB search path.
- Start hdldaemon to provide connection to HDL simulator.
- Launch HDL simulator for use with MATLAB and load EDA Simulator Link MQ libraries.
- Bind HDL instance with test bench function.
- Add scheduling options.
- Set breakpoints for interactive HDL debug (optional).
- Run cosimulation from HDL simulator.
- End cosimulation session.

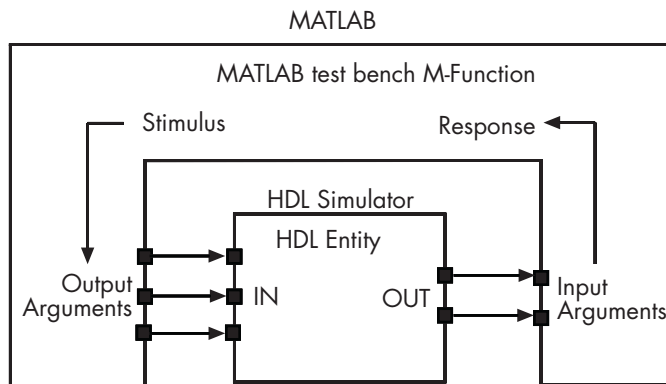


## Overview to Using MATLAB as a Test Bench

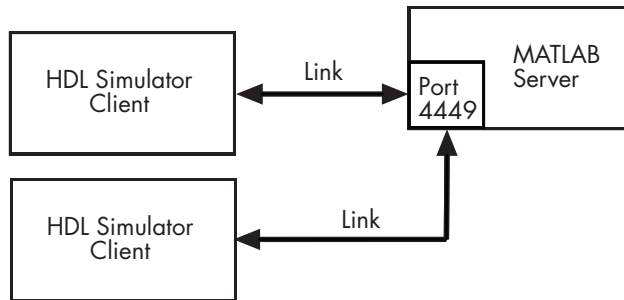
The EDA Simulator Link MQ software provides a means for verifying HDL modules within the MATLAB environment. You do so by coding an HDL model and a MATLAB M-function that can share data with the HDL model. This chapter discusses the programming, interfacing, and scheduling conventions for MATLAB test bench functions that communicate with the HDL simulator.

*MATLAB test bench* functions let you verify the performance of the HDL model, or of components within the model. A test bench function drives values onto signals connected to input ports of an HDL design under test and receives signal values from the output ports of the module.

The following figure shows how a MATLAB M-function wraps around and communicates with the HDL simulator during a test bench simulation session.



When linked with MATLAB, the HDL simulator functions as the client, with MATLAB as the server. The following figure shows a multiple-client scenario connecting to the server at TCP/IP socket port 4449.



The MATLAB server can service multiple simultaneous HDL simulator sessions and HDL modules. However, you should follow recommended guidelines to ensure the server can track the I/O associated with each module and session. The MATLAB server, which you start with the supplied MATLAB function `hdldaemon`, waits for connection requests from instances of the HDL simulator running on the same or different computers. When the server receives a request, it executes the specified MATLAB M-function you have coded to perform tasks on behalf of a module in your HDL design. Parameters that you specify when you start the server indicate whether the server establishes shared memory or TCP/IP socket communication links.

Refer to “Establishing EDA Simulator Link MQ Machine Configuration Requirements” on page 7-10 for valid machine configurations.

---

**Note** The programming, interfacing, and scheduling conventions for test bench functions and component functions (see Chapter 3, “Replacing an HDL Component with a MATLAB Component Function”) are virtually identical. Most of this chapter focuses on test bench functions, but in general all operations can be performed on and with both functions.

---

## Code HDL Modules for Verification Using MATLAB

### In this section...

“Overview to Coding HDL Modules for Use with MATLAB” on page 2-7

“Choosing an HDL Module Name” on page 2-7

“Specifying Port Direction Modes in HDL Components (MATLAB as Test Bench)” on page 2-8

“Specifying Port Data Types in HDL Components (MATLAB as Test Bench)” on page 2-8

“Sample VHDL Entity Definition” on page 2-10

“Compiling and Debugging the HDL Model” on page 2-10

### Overview to Coding HDL Modules for Use with MATLAB

The most basic element of communication in the EDA Simulator Link MQ interface is the HDL module. The interface passes all data between the HDL simulator and MATLAB as port data. The EDA Simulator Link MQ software works with any existing HDL module. However, when you code an HDL module that is targeted for MATLAB verification, you should consider its name, the types of data to be shared between the two environments, and the direction modes. The sections within this chapter cover these topics.

### Choosing an HDL Module Name

Although not required, when naming the HDL module, consider choosing a name that also can be used as a MATLAB M-function name. (Generally, naming rules for VHDL or Verilog and MATLAB are compatible.) By default, EDA Simulator Link MQ software assumes that an HDL module and its simulation function share the same name. See “Binding the HDL Module Component to the MATLAB Test Bench Function” on page 2-28.

For details on MATLAB function-naming guidelines, see “MATLAB Programming Tips” on files and file names in the MATLAB documentation.

## Specifying Port Direction Modes in HDL Components (MATLAB as Test Bench)

In your module statement, you must specify each port with a direction mode (input, output, or bidirectional). The following table defines these three modes.

Use VHDL Mode...	Use Verilog Mode...	For Ports That...
IN	input	Represent signals that can be driven by a MATLAB function
OUT	output	Represent signal values that are passed to a MATLAB function
INOUT	inout	Represent bidirectional signals that can be driven by or pass values to a MATLAB function

## Specifying Port Data Types in HDL Components (MATLAB as Test Bench)

This section describes how to specify data types compatible with MATLAB for ports in your HDL modules. For details on how the EDA Simulator Link MQ interface converts data types for the MATLAB environment, see “Performing Data Type Conversions” on page 8-5.

---

**Note** If you use unsupported types, the EDA Simulator Link MQ software issues a warning and ignores the port at run time. For example, if you define your interface with five ports, one of which is a VHDL access port, at run time, then the interface displays a warning and your M-code sees only four ports.

---

### Port Data Types for VHDL Entities

In your entity statement, you must define each port that you plan to test with MATLAB with a VHDL data type that is supported by the EDA Simulator Link MQ software. The interface can convert scalar and array data of the following VHDL types to comparable MATLAB types:

- STD\_LOGIC, STD\_ULOGIC, BIT, STD\_LOGIC\_VECTOR, STD\_ULOGIC\_VECTOR, and BIT\_VECTOR
- INTEGER and NATURAL
- REAL
- TIME
- Enumerated types, including user-defined enumerated types and CHARACTER

The interface also supports all subtypes and arrays of the preceding types.

---

**Note** The EDA Simulator Link MQ software does not support VHDL extended identifiers for the following components:

- Port and signal names used in cosimulation
- Enum literals when used as array indices of port and signal names used in cosimulation

However, the software does support basic identifiers for VHDL.

---

### Port Data Types for Verilog Modules

In your module definition, you must define each port that you plan to test with MATLAB with a Verilog port data type that is supported by the EDA Simulator Link MQ software. The interface can convert data of the following Verilog port types to comparable MATLAB types:

- reg
- integer
- wire

---

**Note** EDA Simulator Link MQ software does not support Verilog escaped identifiers for port and signal names used in cosimulation. However, it does support simple identifiers for Verilog.

---

### Sample VHDL Entity Definition

This sample VHDL code fragment defines the entity `decoder`. By default, the entity is associated with MATLAB test bench function `decoder`.

The keyword `PORT` marks the start of the entity's port clause, which defines two `IN` ports—`isum` and `qsum`—and three `OUT` ports—`adj`, `dvalid`, and `odata`. The output ports drive signals to MATLAB function input ports for processing. The input ports receive signals from the MATLAB function output ports.

Both input ports are defined as vectors consisting of five standard logic values. The output port `adj` is also defined as a standard logic vector, but consists of only two values. The output ports `dvalid` and `odata` are defined as scalar standard logic ports. For information on how the EDA Simulator Link MQ interface converts data of standard logic scalar and array types for use in the MATLAB environment, see “Performing Data Type Conversions” on page 8-5.

```
ENTITY decoder IS
PORT (
    isum    : IN std_logic_vector(4 DOWNTO 0);
    qsum    : IN std_logic_vector(4 DOWNTO 0);
    adj     : OUT std_logic_vector(1 DOWNTO 0);
    dvalid  : OUT std_logic;
    odata   : OUT std_logic);
END decoder ;
```

### Compiling and Debugging the HDL Model

After you create or edit your HDL source files, use the HDL simulator compiler to compile and debug the code.

You have the option of invoking the compiler from menus in the ModelSim graphic interface or from the command line with the `vcom` command. The following sequence of ModelSim commands creates and maps the design library `work` and compiles the VHDL file `modsimrand.vhd`:

```
ModelSim> vlib work
ModelSim> vmap work work
ModelSim> vcom modsimrand.vhd
```

The following sequence of ModelSim commands creates and maps the design library `work` and compiles the Verilog file `test.v`:

```
ModelSim> vlib work  
ModelSim> vmap work work  
ModelSim> vlog test.v
```

For more examples, see the EDA Simulator Link MQ tutorials. For details on using the HDL compiler, see the simulator documentation.

## Code an EDA Simulator Link MQ MATLAB Test Bench Function

### In this section...

“Process for Coding MATLAB EDA Simulator Link MQ Functions” on page 2-12

“Syntax of a Test Bench Function” on page 2-13

“Sample MATLAB Test Bench Function” on page 2-13

### Process for Coding MATLAB EDA Simulator Link MQ Functions

Coding a MATLAB M-function that is to verify an HDL module or component requires that you follow specific coding conventions. You must also understand the data type conversions that occur, and program data type conversions for operating on data and returning data to the HDL simulator.

To code a MATLAB function that is to verify an HDL module or component, perform the following steps:

- 1** Learn the syntax for a MATLAB EDA Simulator Link MQ test bench function (see “Syntax of a Test Bench Function” on page 2-13.).
- 2** Understand how EDA Simulator Link MQ software converts data from the HDL simulator for use in the MATLAB environment (see “Performing Data Type Conversions” on page 8-5 in Chapter 8, “Advanced Operational Topics”).
- 3** Choose a name for the MATLAB function (see “Binding the HDL Module Component to the MATLAB Test Bench Function” on page 2-28).
- 4** Define expected parameters in the function definition line (see “Defining EDA Simulator Link MQ M-Functions and Function Parameters” on page 9-2 in the Chapter 9, “M-Function Prototype Reference”).
- 5** Determine the types of port data being passed into the function (see “Defining EDA Simulator Link MQ M-Functions and Function Parameters” on page 9-2 in the Chapter 9, “M-Function Prototype Reference”).



- 6 Extract and, if appropriate for the simulation, apply information received in the `portinfo` structure (see “Gaining Access to and Applying Port Information” on page 9-5 in the Chapter 9, “M-Function Prototype Reference”).
- 7 Convert data for manipulation in the MATLAB environment, as necessary (see “Converting HDL Data to Send to MATLAB” on page 8-5 in Chapter 8, “Advanced Operational Topics”).
- 8 Convert data that needs to be returned to the HDL simulator (see “Converting Data for Return to the HDL Simulator” on page 8-10 in Chapter 8, “Advanced Operational Topics”).

## Syntax of a Test Bench Function

The syntax of a MATLAB test bench function is

```
function [iport, tnext] = MyFunctionName(oport, tnow, portinfo)
```

See the Chapter 9, “M-Function Prototype Reference” for an explanation of each of the function arguments.

## Sample MATLAB Test Bench Function

This section uses a sample MATLAB function to identify sections of a MATLAB test bench function required by the EDA Simulator Link MQ software. You can see the full text of the code used in this sample in the section MATLAB Function Example: `manchester_decoder.m` on page 2-18.

---

**Note** The example uses a VHDL entity and MATLAB function code drawn from the decoder portion of the Manchester Receiver demo. For the complete VHDL and M-code listings, see the following files:

```
matlabroot\toolbox\modelsim\modelsimdemos\vhdl\manchester\decoder.vhd
```

```
matlabroot\toolbox\modelsim\modelsimdemos\manchester_decoder.m
```

---

As the first step to coding a MATLAB test bench function, you must understand how the data modeled in the VHDL entity maps to data in the MATLAB environment. The VHDL entity decoder is defined as follows:

```
ENTITY decoder IS
PORT (
    isum    : IN std_logic_vector(4 DOWNTO 0);
    qsum    : IN std_logic_vector(4 DOWNTO 0);
    adj     : OUT std_logic_vector(1 DOWNTO 0);
    dvalid  : OUT std_logic;
    odata   : OUT std_logic
);
END decoder ;
```

The following discussion highlights key lines of code in the definition of the `manchester_decoder` MATLAB function:

### 1 Specify the MATLAB function name and required parameters.

The following code is the function declaration of the `manchester_decoder` MATLAB function.

```
function [iport,tnext] = manchester_decoder(oport,tnow,portinfo)
```

See “Defining EDA Simulator Link MQ M-Functions and Function Parameters” on page 9-2 in the Chapter 9, “M-Function Prototype Reference”.

The function declaration performs the following actions:

- Names the function. This declaration names the function `manchester_decoder`, which differs from the entity name `decoder`. Because the names differ, the function name must be specified explicitly later when the entity is initialized for verification with the `matlabtb` or `matlabtbeval` HDL simulator command. See “Binding the HDL Module Component to the MATLAB Test Bench Function” on page 2-28.
- Defines required argument and return parameters. A MATLAB test bench function *must* return two parameters, `iport` and `tnext`, and pass three arguments, `oport`, `tnow`, and `portinfo`, and *must* appear in the order shown. See “Defining EDA Simulator Link MQ M-Functions

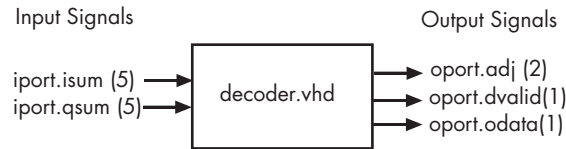
and Function Parameters” on page 9-2 in the Chapter 9, “M-Function Prototype Reference”.

The function outputs must be initialized to empty values, as in the following code example:

```
tnext = [];  
iport = struct();
```

You should initialize the function outputs at the beginning of the function, to follow recommended best practice.

The following figure shows the relationship between the entity’s ports and the MATLAB function’s `iport` and `oport` parameters.



For more information on the required MATLAB test bench function parameters, see “Defining EDA Simulator Link MQ M-Functions and Function Parameters” on page 9-2 in the Chapter 9, “M-Function Prototype Reference”.

## **2 Make note of the data types of ports defined for the entity being simulated.**

The EDA Simulator Link MQ software converts HDL data types to comparable MATLAB data types and vice versa. As you develop your MATLAB function, you must know the types of the data that it receives from the HDL simulator and needs to return to the HDL simulator.

The VHDL entity defined for this example consists of the following ports

**VHDL Example Port Definitions**

<b>Port</b>	<b>Direction</b>	<b>Type...</b>	<b>Converts to/Requires Conversion to...</b>
isum	IN	STD_LOGIC_VECTOR(4 DOWNTO 0)	A 5-bit column or row vector of characters where each bit maps to a standard logic character literal.
qsum	IN	STD_LOGIC_VECTOR(4 DOWNTO 0)	A 5-bit column or row vector of characters where each bit maps to a standard logic character literal.
adj	OUT	STD_LOGIC_VECTOR(1 DOWNTO 0)	A 2-element column vector of characters. Each character matches a corresponding character literal that represents a logic state and maps to a single bit.
dvalid	OUT	STD_LOGIC	A character that matches the character literal representing the logic state.
odata	OUT	STD_LOGIC	A character that matches the character literal representing the logic state.

For more information on interface data type conversions, see “Performing Data Type Conversions” on page 8-5 in Chapter 8, “Advanced Operational Topics”.

### 3 Set up any required timing parameters.

The `tnext` assignment statement sets up timing parameter `tnext` such that the simulator calls back the MATLAB function every nanosecond.

```
tnext = tnow+1e-9;
```

### 4 Convert output port data to appropriate MATLAB data types for processing.

The following code excerpt illustrates data type conversion of output port data.

```
%% Compute one row and plot
isum = isum + 1;
adj(isum) = mvl2dec(oport.adj');
data(isum) = mvl2dec([oport.dvalid oport.odata]);
.
.
.
```

The two calls to `mvl2dec` convert the binary data that the MATLAB function receives from the entity’s output ports, `adj`, `dvalid`, and `odata` to unsigned decimal values that MATLAB can compute. The function converts the 2-bit transposed vector `oport.adj` to a decimal value in the range 0 to 4 and `oport.dvalid` and `oport.odata` to the decimal value 0 or 1.

“Defining EDA Simulator Link MQ M-Functions and Function Parameters” on page 9-2 in the Chapter 9, “M-Function Prototype Reference” provides a summary of the types of data conversions to consider when coding simulation MATLAB functions.

### 5 Convert data to be returned to the HDL simulator.

The following code excerpt illustrates data type conversion of data to be returned to the HDL simulator.

```
if isum == 17
```

```
        iport.isum = dec2mv1(isum,5);
        iport.qsum = dec2mv1(qsum,5);
    else
        iport.isum = dec2mv1(isum,5);
    end
```

The three calls to `dec2mv1` convert the decimal values computed by MATLAB to binary data that the MATLAB function can deposit to the entity's input ports, `isum` and `qsum`. In each case, the function converts a decimal value to 5-element bit vector with each bit representing a character that maps to a character literal representing a logic state.

“Converting Data for Return to the HDL Simulator” on page 8-10 provides a summary of the types of data conversions to consider when returning data to the HDL simulator.

### **MATLAB Function Example: manchester\_decoder.m**

```
function [iport,tnext] = manchester_decoder(oport,tnow,portinfo)
% MANCHESTER_DECODER Test bench for VHDL 'decoder'
% [IPOINT,TNEXT]=MANCHESTER_DECODER(OPORT,TNOW,PORTINFO) -
% Implements a test of the VHDL decoder entity which is part
% of the Manchester receiver demo. This test bench plots
% the IQ mapping produced by the decoder.
%
%          iport          oport
%          +-----+
% isum -(5)->|          |-(2)-> adj
% qsum -(5)->| decoder  |-(1)-> dvalid
%           |          |-(1)-> odata
%           +-----+
%
% isum - Inphase Convolution value
% qsum - Quadrature Convolution value
% adj  - Clock adjustment ('01','00','10')
% dvalid - Data validity ('1' = data is valid)
% odata - Recovered data stream
%
% Adjust = 0 (00b), generate full 16 cycle waveform
```

```
% Copyright 2003-2004 The MathWorks, Inc.
% $Revision: 1.1.4.2 $ $Date: 2008/12/23 17:43:15 $

persistent isum;
persistent qsum;
%persistent ga;
persistent x;
persistent y;
persistent adj;
persistent data;
global testisdone;
% This useful feature allows you to manually
% reset the plot by simply typing: >manchester_decoder
tnext = [];
iport = struct();

if nargin == 0,
    isum = [];
    return;
end

if exist('portinfo') == 1
    isum = [];
end

tnext = tnow+1e-9;
if isempty(isum), %% First call
    scale = 9;
    isum = 0;
    qsum = 0;
    for k=1:2,
        ga(k) = subplot(2,1,k);
        axis([-1 17 -1 17]);
        ylabel('Quadrature');
        line([0 16],[8 8], 'Color', 'r', 'LineStyle', ':', 'LineWidth', 1)
        line([8 8],[0 16], 'Color', 'r', 'LineStyle', ':', 'LineWidth', 1)
    end
    xlabel('Inphase');
    subplot(2,1,1);
    title('Clock Adjustment (adj)');
```

```
        subplot(2,1,2);
        title('Data with Validity');
        iport.isum = '00000';
        iport.qsum = '00000';
        return;
    end

% compute one row, then plot
isum = isum + 1;
adj(isum) = bin2dec(oport.adj');
data(isum) = bin2dec([oport.dvalid oport.odata]);

if isum == 17,
    subplot(2,1,1);
    for k=0:16,
        if adj(k+1) == 0, % Bang on!
            line(k,qsum,'color','k','Marker','o');
        elseif adj(k+1) == 1, %
            line(k,qsum,'color','r','Marker','<');
        else
            line(k,qsum,'color','b','Marker','>');
        end
    end
    subplot(2,1,2);
    for k=0:16,
        if data(k+1) < 2, % Invalid
            line(k,qsum,'color','r','Marker','X');
        else
            if data(k+1) == 2, %Valid and 0!
                line(k,qsum,'color','g','Marker','o');
            else
                line(k,qsum,'color','k','Marker','.');
            end
        end
    end
end

isum = 0;
qsum = qsum + 1;
if qsum == 17,
    qsum = 0;
```



```
        disp('done');
        tnext = []; % suspend callbacks
        testisdone = 1;
        return;
    end
    iport.isum = dec2bin(isum,5);
    iport.qsum = dec2bin(qsum,5);
else
    iport.isum = dec2bin(isum,5);
end
```

### Place Test Bench Function on MATLAB Search Path

The MATLAB M-function that you are associating with an HDL component must be on the MATLAB search path or reside in the current working directory (see the MATLAB `cd` function). To verify whether the function is accessible, use the MATLAB `which` function. The following call to `which` checks whether the function `MyVhdlFunction` is on the MATLAB search path:

```
which MyVhdlFunction  
D:\work\modelsim\MySym\MyVhdlFunction.m
```

If the specified function is on the search path, `which` displays the complete path to the function's M-file. If the function is not on the search path, `which` informs you that the file was not found.

To add a MATLAB function to the MATLAB search path, open the Set Path window by clicking **File > Set Path**, or use the `addpath` command. Alternatively, for temporary access, you can change the MATLAB working directory to a desired location with the `cd` command.

## Start hdldaemon to Provide Connection to HDL Simulator

Start the MATLAB server as follows:

- 1 Start MATLAB.
- 2 In the MATLAB Command Window, call the `hdldaemon` function with property name/property value pairs that specify whether the EDA Simulator Link MQ software is to perform the following tasks:
  - Use shared memory or TCP/IP socket communication
  - Return time values in seconds or as 64-bit integers

See `hdldaemon` reference documentation for when and how to specify property name/property value pairs and for more examples of using `hdldaemon`.

For example, the following command specifies using socket communication on port 4449 and a 64-bit time resolution format for the MATLAB function's output ports.

```
hdldaemon('socket', 4449, 'time', 'int64')
```

---

**Note** The communication mode that you specify (shared memory or TCP/IP sockets) must match what you specify for the communication mode when you initialize the HDL simulator for use with a MATLAB link session using the `matlabtb` or `matlabtbeval` HDL simulator command. In addition, if you specify TCP/IP socket mode, the socket port that you specify with this function and the HDL simulator command must match. For more information on modes of communication, see “Specifying TCP/IP Socket Communication” on page 7-13.

---

The MATLAB server can service multiple simultaneous HDL simulator modules and clients. However, your M-code must track the I/O associated with each entity or client.

---

**Note** You cannot begin an EDA Simulator Link MQ transaction between MATLAB and the HDL simulator from MATLAB. The MATLAB server simply responds to function call requests that it receives from the HDL simulator.

---

## Launch HDL Simulator for Use with MATLAB

### In this section...

“Launching the HDL Simulator” on page 2-25

“Loading an HDL Design for Verification” on page 2-25

## Launching the HDL Simulator

### Starting vsim from MATLAB

Start the HDL simulator directly from MATLAB by calling the MATLAB function `vsim`. See “Starting the HDL Simulator” on page 1-22 for instructions on using `vsim`.

### Loading an HDL Design for Verification

After you start the HDL simulator from MATLAB with a call to `vsim`, load an instance of an HDL module for verification with the HDL simulator command `vsimmatlab`. By this point, you should have coded and compiled your HDL model as explained in “Code HDL Modules for Verification Using MATLAB” on page 2-7. Issue the HDL simulator command `vsimmatlab` for each instance of an entity or module in your model that you want to cosimulate. For example:

```
vsimmatlab work.modsimrand
```

This command loads the EDA Simulator Link MQ library, opens a simulation workspace for `modsimrand`, and displays a series of messages in the HDL simulator command window. These actions occur as the simulator loads the entity (see demo for remaining code).

## Invoke `matlabtb` to Bind and Schedule MATLAB Test Bench Function Calls

In this section...
“Invoking <code>matlabtb</code> ” on page 2-26
“Binding the HDL Module Component to the MATLAB Test Bench Function” on page 2-28
“Scheduling Options for a Test Bench Session” on page 2-28

### Invoking `matlabtb`

This section discusses associating an HDL module with a MATLAB test bench function and scheduling when the test bench function is called using the `-mfunc` and timing arguments to `matlabtb`.

For a full list of `matlabtb` parameters, see the `matlabtb` reference.

Keep in mind the path specifications for MATLAB test bench sessions when invoking `matlabtb`, as explained in the next section.

### Specifying HDL Signal/Port and Module Paths for MATLAB Test Bench Cosimulation

The rules stated in this section are for signal/port and module path specifications for MATLAB link sessions. Other specifications may work but are not guaranteed to work in this or future releases.

In the following example:

```
matlabtb u_osc_filter -mfunc oscfilter
```

`u_osc_filter` is the top level component. However, if you are specifying a subcomponent, you must follow valid module path specifications for MATLAB link sessions.

---

**Note** HDL designs generally do have hierarchy; that is the reason for this syntax. This specification does *not* represent a file name hierarchy.

---

### **Path Specifications for MATLAB Link Sessions with Verilog Top Level**

- The path specification must start with a top-level module name.
- The path specification can include "." or "/" path delimiters, but cannot include a mixture.
- The leaf module or signal must match the HDL language of the top-level module.

The following examples show valid signal and module path specifications:

```
top.port_or_sig
/top/sub/port_or_sig
top
top/sub
top.sub1.sub2
```

The following examples show invalid signal and module path specifications:

```
top.sub/port_or_sig
:sub:port_or_sig
:
:sub
```

### **Path Specifications for MATLAB Link Sessions with VHDL Top Level**

- The path specification may include the top-level module name, but it is not required.
- The path specification can include "." or "/" path delimiters, but cannot include a mixture.
- The leaf module or signal must match the HDL language of the top-level module.

The following are valid signal and module path specification examples:

```
top.port_or_sig
```

```
/sub/port_or_sig
top
top/sub
top.sub1.sub2
```

The following are invalid signal and module path specification examples:

```
top.sub/port_or_sig
:sub:port_or_sig
:
:sub
```

### Binding the HDL Module Component to the MATLAB Test Bench Function

By default, the EDA Simulator Link MQ software assumes the name for a MATLAB M-function matches the name of the HDL module that the function verifies. See the `-mfunc` argument of `matlabtb` for more information.

For details on MATLAB function naming guidelines, see "MATLAB Programming Tips" on files and file names in the MATLAB documentation.

In the next example, an association must be formed between the `inverter_v1` component and the MATLAB component function `inverter_tb`. To do so, the software invokes the HDL simulator command `matlabtb` with the `-mfunc` argument when the simulation is set up.

```
matlabtb inverter_v1 -mfunc inverter_tb
```

The `matlabtb` command instructs the HDL simulator to call back the `inverter_tb` function when `inverter_v1` executes in the simulation.

### Scheduling Options for a Test Bench Session

There are two ways to schedule the invocation of a test bench function:

- Using the arguments to the EDA Simulator Link MQ function `matlabtb`
- Inside the MATLAB M-function using the `tnext` parameter (see "Scheduling EDA Simulator Link MQ M-Functions Using the `tnext` Parameter" on page 9-8)



By default, the EDA Simulator Link MQ software invokes a MATLAB test bench function once (when time equals 0). If you want to apply more control and execute the MATLAB function more than once, decide on scheduling options that specify when and how often the EDA Simulator Link MQ software is to invoke the relevant MATLAB function. Depending on your choices, you may need to modify the function or specify specific arguments when you begin a MATLAB test bench session with the `matlabtb` function.

You can schedule a MATLAB test bench function to execute under any of the following conditions:

- At a time that the function passes to the HDL simulator with the `tnext` parameter
- Based on a time specification that can include discrete time values, repeat intervals, and a stop time
- When a specified signal experiences a rising edge—changes from '0' to '1'
- When a specified signal experiences a falling edge—changes from '1' to '0'
- Based on a sensitivity list—when a specified signal changes state

Decide on a combination of options that best meet your test bench application requirements. For details on using the `matlabtb` arguments for scheduling, see the reference page for `matlabtb`. For details on using the `tnext` parameter and information on setting other scheduling parameters, see “Scheduling EDA Simulator Link MQ M-Functions Using the `tnext` Parameter” on page 9-8.

### **Example: Invoke matlabtb on rising edge**

Consider the following `matlabtb` command:

```
VSIM n> matlabtb modsimrand -rising /modsimrand/clock
        -socket 4449
```

This command links an instance of the entity `modsimrand` to function `modsimrand.m`, which executes within the context of MATLAB based on specified timing parameters. In this case, the MATLAB function is called when the signal `/modsimrand/clock` experiences a rising edge.

Arguments in the command line specify the following conditions:

<code>modsimrand</code>	That an instance of the entity <code>modsimrand</code> be linked with the MATLAB function <code>modsimrand</code> .
<code>-rising /modsimrand/clock</code>	That the MATLAB function <code>modsimrand</code> be called when the signal <code>/modsimrand/clock</code> changes from '0' to '1'.

## Run MATLAB Test Bench Simulation

### In this section...

“Process for Running MATLAB Test Bench Cosimulation” on page 2-31

“Checking the MATLAB Server’s Link Status” on page 2-31

“Running a Test Bench Cosimulation” on page 2-32

“Applying Stimuli with the HDL Simulator force Command” on page 2-33

“Restarting a Test Bench Simulation” on page 2-34

### Process for Running MATLAB Test Bench Cosimulation

To start and control the execution of a simulation in the MATLAB environment, perform the following steps:

- 1 Check the MATLAB server’s link status.
- 2 Apply test bench stimuli.
- 3 Run and monitor the test bench session.
- 4 Restart simulator during a test bench session. (If necessary)

### Checking the MATLAB Server’s Link Status

The first step to starting an HDL simulator and MATLAB test bench session is to check the MATLAB server’s link status. Is the server running? If the server is running, what mode of communication and, if applicable, what TCP/IP socket port is the server using for its links? You can retrieve this information by using the MATLAB function `hdldaemon` with the `'status'` option. For example:

```
hdldaemon('status')
```

The function displays a message that indicates whether the server is running and, if it is running, the number of connections it is handling. For example:

```
HLDaemon socket server is running on port 4449 with 0 connections
```

If the server is not running, the message reads

```
HDLDaemon is NOT running
```

See "Link Status" in the `hdldaemon` reference documentation for information on determining the mode of communication and the TCP/IP socket in use.

### Running a Test Bench Cosimulation

These steps describe a typical sequence for running a simulation interactively from the main HDL simulator window:

- 1 Set breakpoints in the HDL and MATLAB code to verify and analyze simulation progress and correctness.

How you set breakpoints in the HDL simulator will vary depending on what simulator application you are using.

In MATLAB, there are several ways you can set breakpoints; for example, by using the **Set/Clear Breakpoint** button on the toolbar.

- 2 Start the simulation by entering the HDL simulator run command.

The run command offers a variety of options for applying control over how a simulation runs (refer to your HDL simulator documentation for details). For example, you can specify that a simulation run for several time steps.

The following command instructs the HDL simulator to run the loaded simulation for 50000 time steps:

```
run 50000
```

- 3 Step through the simulation and examine values.

How you step through the simulation in the HDL simulator will vary depending on what simulator application you are using.

In MATLAB, there are several ways you can step through code; for example, by clicking the **Step** toolbar button.

- 4 When you block execution of the MATLAB function, the HDL simulator also blocks and remains blocked until you clear all breakpoints in the function's M-code.
- 5 Resume the simulation, as needed.

How you resume the simulation in the HDL simulator will vary depending on what simulator application you are using.

In MATLAB, there are several ways you can resume the simulation; for example, by clicking the **Continue** toolbar button.

The following HDL simulator command resumes a simulation:

```
run -continue
```

For more information on HDL simulator and MATLAB debugging features, see the appropriate HDL simulator documentation and MATLAB online help or documentation.

## Applying Stimuli with the HDL Simulator force Command

After you establish a link between the HDL simulator and MATLAB, you can then apply stimuli to the test bench environment. One way of applying stimuli is through the `iport` parameter of the linked MATLAB function. This parameter forces signal values by deposit.

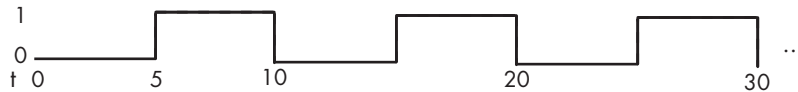
Other ways to apply stimuli include issuing `force` commands in the ModelSim main window or using the **Edit > Clock** option in the **ModelSim Signals** window.

For example, consider the following sequence of `force` commands:

```
VSIM n> force clk 0 0 ns, 1 5 ns -repeat 10 ns
VSIM n> force clk_en 1 0
VSIM n> force reset 0 0
```

These commands drive the following signals:

- The `clk` signal to 0 at 0 nanoseconds after the current simulation time and to 1 at 5 nanoseconds after the current HDL simulation time. This cycle repeats starting at 10 nanoseconds after the current simulation time, causing transitions from 1 to 0 and 0 to 1 every 5 nanoseconds, as the following diagram shows.



For example,

```
force /foobar/clk 0 0, 1 5 -repeat 10
```

- The `clk_en` signal to 1 at 0 nanoseconds after the current simulation time.
- The `reset` signal to 0 at 0 nanoseconds after the current simulation time.

### Restarting a Test Bench Simulation

Because the HDL simulator issues the service requests during a MATLAB test bench session, you must restart a test bench session from the HDL simulator. To restart a session, perform the following steps:

- 1** Make the HDL simulator your active window, if your input focus was not already set to that application.
- 2** Reload HDL design elements and reset the simulation time to zero.
- 3** Reissue the `matlabtb` command.

---

**Note** To restart a simulation that is in progress, issue a break command and end the current simulation session before restarting a new session.

---

## Stop Test Bench Simulation

When you are ready to stop a test bench session, it is best to do so in an orderly way to avoid possible corruption of files and to ensure that all application tasks shut down appropriately. You should stop a session as follows:

- 1** Make the HDL simulator your active window, if your input focus was not already set to that application.
- 2** Halt the simulation. You must quit the simulation at the HDL simulator side or MATLAB may hang until the simulator is quit.
- 3** Close your project.
- 4** Exit the HDL simulator, if you are finished with the application.
- 5** Quit MATLAB, if you are finished with the application. If you want to shut down the server manually, stop the server by calling `hdldaemon` with the `'kill'` option:

```
hdldaemon('kill')
```

For more information on closing HDL simulator sessions, see the HDL simulator documentation.

## Tutorial – Running a Sample ModelSim and MATLAB Test Bench Session

In this section...
“Tutorial Overview” on page 2-36
“Setting Up Tutorial Files” on page 2-36
“Starting the MATLAB Server” on page 2-37
“Setting Up the ModelSim Simulator” on page 2-39
“Developing the VHDL Code” on page 2-40
“Compiling the VHDL File” on page 2-43
“Loading the Simulation” on page 2-43
“Developing the MATLAB Function” on page 2-46
“Running the Simulation” on page 2-48
“Shutting Down the Simulation” on page 2-52

### Tutorial Overview

This chapter guides you through the basic steps for setting up an EDA Simulator Link MQ application that uses MATLAB to verify a simple HDL design. In this tutorial, you develop, simulate, and verify a model of a pseudorandom number generator based on the Fibonacci sequence. The model is coded in VHDL.

---

**Note** This tutorial requires MATLAB, the ModelSim HDL simulator, and the EDA Simulator Link MQ software.

---

### Setting Up Tutorial Files

To ensure that others can access copies of the tutorial files, set up a directory for your own tutorial work:



- 1 Create a directory outside the scope of your MATLAB installation directory into which you can copy the tutorial files. The directory must be writable. This tutorial assumes that you create a directory named MyPlayArea.
- 2 Copy the following files to the directory you just created:

```
matlabroot\toolbox\modelsim\modelsimdemos\modsimrand_plot.m  
matlabroot\toolbox\modelsim\modelsimdemos\VHDL\modsimrand\modsimrand.vhd
```

## Starting the MATLAB Server

This section describes starting MATLAB, setting up the current directory for completing the tutorial, starting the product's MATLAB server component, and checking for client connections, using the server's TCP/IP socket mode. These instructions assume you are familiar with the MATLAB user interface.

Perform the following steps:

- 1 Start MATLAB.
- 2 Set your MATLAB current directory to the directory you created in “Setting Up Tutorial Files” on page 2-36.
- 3 Check whether the MATLAB server is running. To do so, call the function `hdldaemon` with the 'status' option in the MATLAB Command Window as shown here:

```
hdldaemon('status')
```

If the server is not running, the function displays

```
HDLDaemon is NOT running
```

If the server is running in TCP/IP socket mode, the message reads

```
HDLDaemon socket server is running on Port portnum with 0 connections
```

If the server is running in shared memory mode, the message reads

```
HDLDaemon shared memory server is running with 0 connections
```

- 4** If the server is not currently running, skip to step 5. If the server is currently running, shut down the server by typing

```
hdldaemon('kill')
```

The following message appears, confirming that the server was shut down.

```
HDLDaemon server was shut down
```

- 5** The next step is to start the server in TCP/IP socket mode. To do so, call `hdldaemon` with the property name/property value pair `'socket' 0`. The value 0 specifies that the operating system assign the server a TCP/IP socket port that is available on your system. For example

```
hdldaemon('socket', 0)
```

The server informs you that it has started by displaying the following message. The `portnum` will be specific to your system:

```
HDLDaemon socket server is running on Port portnum with 0 connections
```

Other options that you can specify in the `hdldaemon` function call include the following:

- Shared memory communication instead of TCP/IP socket communication
- Whether time will be returned as scaled or a 64-bit integer

For details on how to specify the various options, see the description of `hdldaemon`.

---

**Note** The `hdldaemon` function can handle multiple connections that are initiated by multiple commands from a single ModelSim session or multiple sessions.

---

## Setting Up the ModelSim Simulator

This section describes the basic procedure for starting the ModelSim software and setting up a ModelSim design library. These instructions assume you are familiar with the ModelSim user interface.

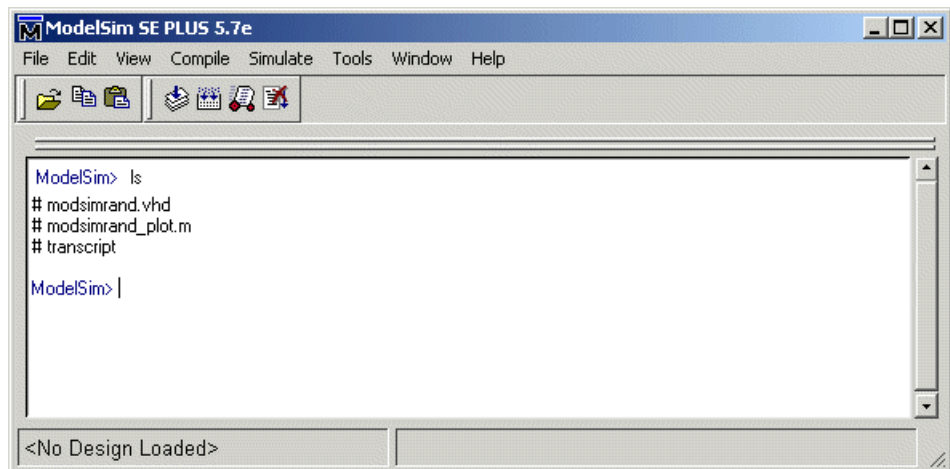
Perform the following steps:

- 1 Start ModelSim from the MATLAB environment by calling the function `vsim` in the MATLAB Command Window.

```
vsim
```

This function launches and configures ModelSim for use with the EDA Simulator Link MQ software. The first directory of ModelSim matches your MATLAB current directory.

- 2 Verify the current ModelSim directory. You can verify that the current ModelSim directory matches the MATLAB current directory by entering the `ls` command in the ModelSim command window.

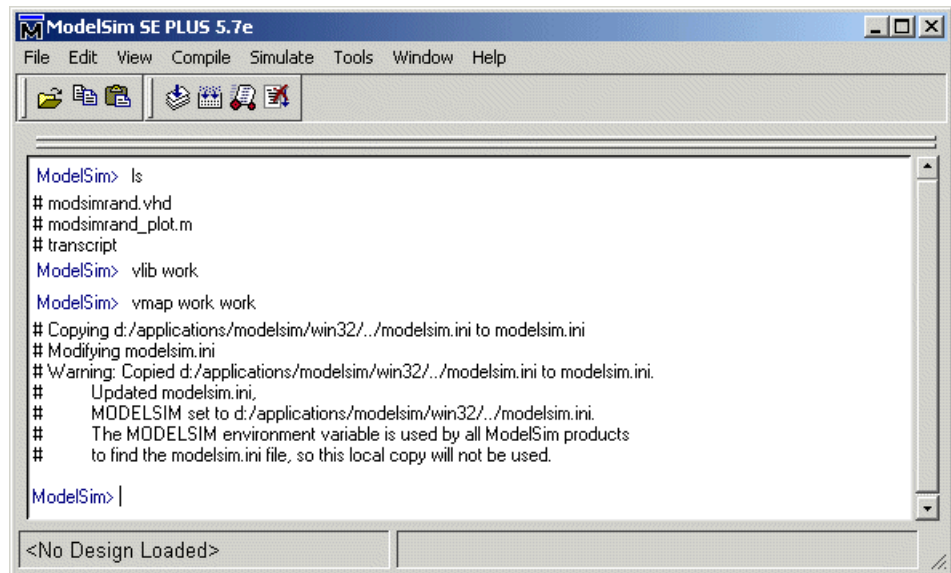


The command should list the files `modsimrand.vhd`, `modsimrand_plot.m`, and `transcript`.

- 3 Create a design library to hold your demo compilation results. To create the library and required `_info` file, enter the `vlib` and `vmap` commands as follows:

```
ModelSim> vlib work
```

```
ModelSim> vmap work work
```



The screenshot shows the ModelSim SE PLUS 5.7e interface. The terminal window displays the following commands and output:

```
ModelSim> ls
# modsimrand.vhd
# modsimrand_plot.m
# transcript
ModelSim> vlib work
ModelSim> vmap work work
# Copying d:/applications/modelsim/win32/./modelsim.ini to modelsim.ini
# Modifying modelsim.ini
# Warning: Copied d:/applications/modelsim/win32/./modelsim.ini to modelsim.ini.
# Updated modelsim.ini.
# MODELSIM set to d:/applications/modelsim/win32/./modelsim.ini.
# The MODELSIM environment variable is used by all ModelSim products
# to find the modelsim.ini file, so this local copy will not be used.
ModelSim> |
```

At the bottom of the window, the status bar indicates "<No Design Loaded>".

---

**Note** You must use the ModelSim **File** menu or `vlib` command to create the library directory to ensure that the required `_info` file is created. Do not create the library with operating system commands.

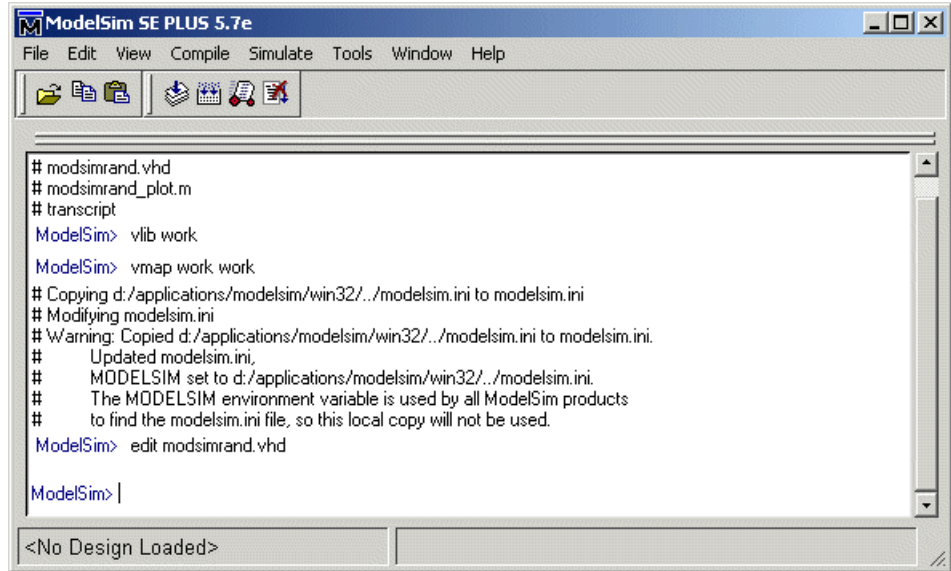
---

## Developing the VHDL Code

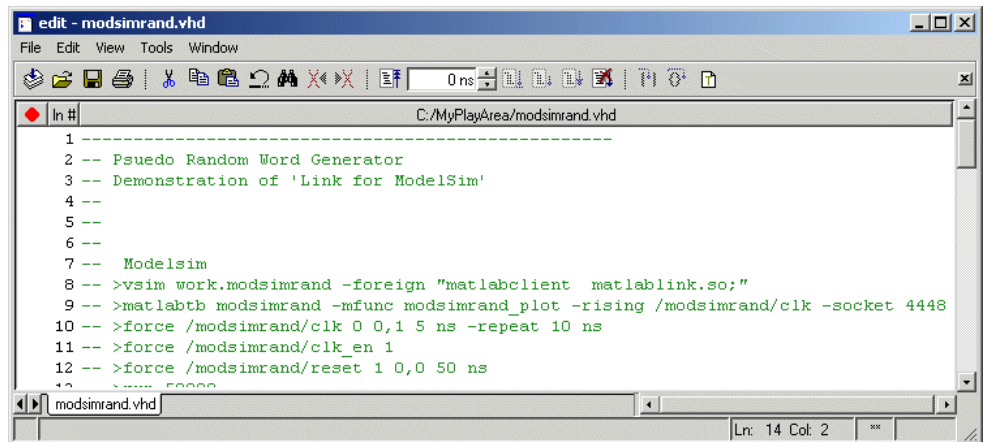
After setting up a design library, typically you would use the ModelSim Editor to create and modify your HDL code. For this tutorial, open and examine the existing file `modsimrand.vhd`. This section highlights areas of code in `modsimrand.vhd` that are of interest for a ModelSim and MATLAB test bench:

- 1 Open `modsimrand.vhd` in the edit window with the `edit` command, as follows:

```
ModelSim> edit modsimrand.vhd
```



ModelSim opens its **edit** window and displays the VHDL code for `modsimrand.vhd`.



- 2** Search for ENTITY `modsimrand`. This line defines the VHDL entity `modsimrand`:

```
ENTITY modsimrand IS
PORT (
    clk      : IN std_logic ;
    clk_en   : IN std_logic ;
    reset    : IN std_logic ;
    dout     : OUT std_logic_vector (31 DOWNT0 0);
END modsimrand;
```

This entity will be verified in the MATLAB environment. Note the following:

- By default, the MATLAB server assumes that the name of the MATLAB function that verifies the entity in the MATLAB environment is the same as the entity name. You have the option of naming the MATLAB function explicitly. However, if you do not specify a name, the server expects the function name to match the entity name. In this example, the MATLAB function name is `modsimrand_plot` and does not match.
- The entity must be defined with a PORT clause that includes at least one port definition. Each port definition must specify a port mode (IN, OUT, or INOUT) and a VHDL data type that is supported by the EDA Simulator Link MQ software. For a list of the supported types, see “Code HDL Modules for Verification Using MATLAB” on page 2-7.

The entity `modsimrand` in this example is defined with three input ports `clk`, `clk_en`, and `reset` of type `STD_LOGIC` and output port `dout` of type `STD_LOGIC_VECTOR`. The output port passes simulation output data out to the MATLAB function for verification. The optional input ports receive clock and reset signals from the function. Alternatively, the input ports can receive signals from ModelSim `force` commands.

For more information on coding port entities for use with MATLAB, see “Code HDL Modules for Verification Using MATLAB” on page 2-7.

- 3** Browse through the rest of `modsimrand.vhd`. The remaining code defines a behavioral architecture for `modsimrand` that writes a randomly generated Fibonacci sequence to an output register when the clock experiences a rising edge.

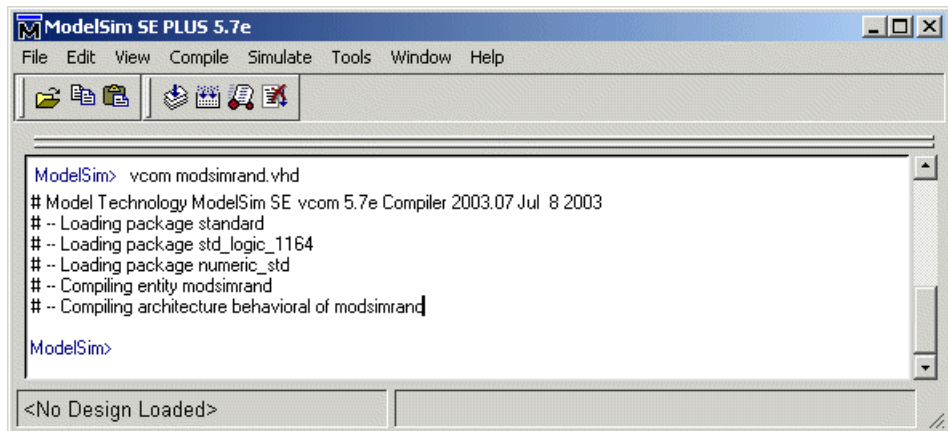
- 4 Close the ModelSim **edit** window.

## Compiling the VHDL File

After you create or edit your VHDL source files, compile them. As part of this tutorial, compile `modsimrand.vhd`. One way of compiling the file is to click the file name in the project workspace and select **Compile > Compile All**. Another alternative is to specify `modsimrand.vhd` with the `vcom` command, as follows:

```
ModelSim> vcom modsimrand.vhd
```

If the compilation succeeds, informational messages appear in the command window and the compiler populates the work library with the compilation results.



## Loading the Simulation

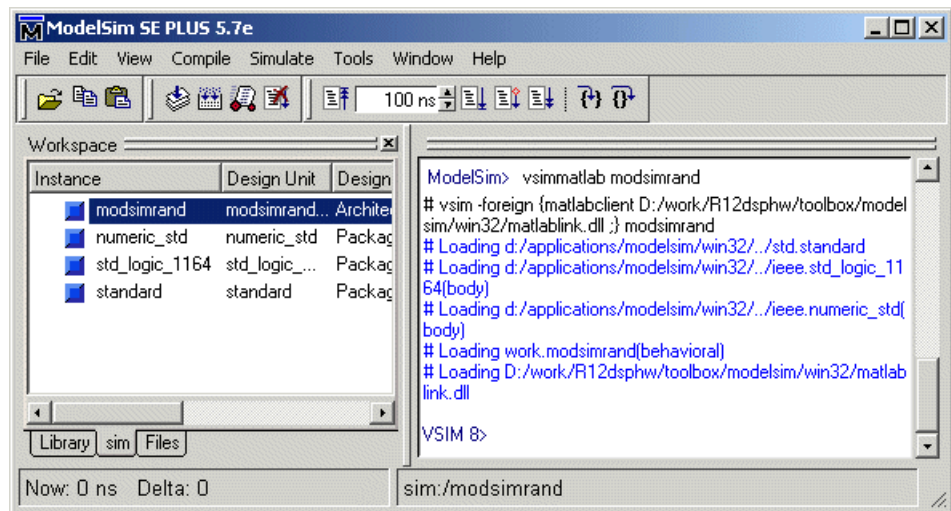
After you successfully compile the VHDL source file, you are ready to load the model for simulation. This section explains how to load an instance of entity `modsimrand` for simulation:

- 1 Load the instance of `modsimrand` for verification. To load the instance, specify the `vsimmatlab` command as follows:

```
ModelSim> vsimmatlab modsimrand
```

The `vsimmatlab` command starts the ModelSim simulator, `vsim`, specifically for use with MATLAB. You can specify `vsimmatlab` with any combination of valid ModelSim `vsim` command parameters and options.

ModelSim displays a series of messages in the command window as it loads the entity's packages and architecture.



- 2 Initialize the simulator for verifying `modsimrand` with MATLAB. You initialize ModelSim by using the `matlabtb` or `matlabtbval` ModelSim command. These commands define the communication link and a callback to a MATLAB function that executes in MATLAB on behalf of ModelSim. In addition, the `matlabtb` commands can specify parameters that control when the MATLAB function executes.

For this tutorial, enter the following `matlabtb` command:

```
VSIM n> matlabtb modsimrand -mfunc modsimrand_plot
-rising /modsimrand/clock -socket portnum
```

Remember that the port number or service name that you specify with `-socket` must match the port value returned by or specified with the call to `hdldaemon` that started the MATLAB server.



Arguments in the command line specify the following conditions:

Argument	Specifies
<code>modsimrand</code>	The instance of the VHDL entity that is to be associated with a MATLAB function.
<code>-mfunc modsimrand_plot</code>	The MATLAB function to be called on behalf of HDL instance <code>modsimrand</code> .
<code>-rising /modsimrand/clock</code>	That the function <code>modsimrand_plot.m</code> be called when the signal <code>/modsimrand/clock</code> changes from '0' to '1'. The signal specification uses a full path name format. If you do not specify a full path name, the command applies ModelSim rules to resolve signal specifications.
<code>-socket portnum</code>	The TCP/IP socket port <code>portnum</code> to be used to establish a communication link with MATLAB.

This command links an instance of the entity `modsimrand` to the function `modsimrand_plot.m`, which executes within the context of MATLAB based on specified timing parameters. In this case, the MATLAB function is called when the signal `/modsimrand/clock` experiences a rising edge.

- 3 Initialize clock and reset input signals. You can drive simulation input signals using several mechanisms, including ModelSim `force` commands and an `iport` parameter (see “Code an EDA Simulator Link MQ MATLAB Test Bench Function” on page 2-12). For now, enter the following `force` commands:

```
VSIM n> force /modsimrand/clock 0 0 ns, 1 5 ns -repeat 10 ns
VSIM n> force /modsimrand/clock_en 1
VSIM n> force /modsimrand/reset 1 0, 0 50 ns
```

The first command forces the `clk` signal to value 0 at 0 nanoseconds and to 1 at 5 nanoseconds. After 10 nanoseconds, the cycle starts to repeat every 10 nanoseconds. The second and third `force` commands set `clk_en` to 1 and `reset` to 1 at 0 nanoseconds and to 0 at 50 nanoseconds.

The ModelSim environment is ready to run a simulation. Now, you need to set up the MATLAB function.

### Developing the MATLAB Function

The EDA Simulator Link MQ software verifies HDL hardware in MATLAB as a function. Typically, at this point you would create or edit a MATLAB function that meets EDA Simulator Link MQ requirements. For this tutorial, open and examine the existing file `modsimrand_plot.m`.

`modsimrand_plot.m` is a lower-level component of the MATLAB Random Number Generator Demo. Plotting code within `modsimrand_plot.m` is not discussed in the next section. This tutorial focuses only on those parts of `modsimrand_plot.m` that are required for MATLAB to verify a VHDL model.

Perform the following steps:

- 1 Open `modsimrand_plot.m` in the MATLAB Edit/Debug window. For example:

```
edit modsimrand_plot.m
```

- 2 Look at line 1. On this line, you specify the MATLAB function name and required parameters:

```
function [iport,tnext] = modsimrand_plot(oport,tnow,portinfo)
```

This function definition is significant because it represents the communication channel between MATLAB and ModelSim. When coding the function definition, consider the following:

- By default, the EDA Simulator Link MQ software assumes the function name is the same as the name of the VHDL entity that it services. However, you can name the function differently, as in this case. The name of the VHDL entity is `modsimrand`, and the name of the function is

`modsimrand_plot`. Because the names differ, you must explicitly specify the function name when you request service from ModelSim.

- You *must* define the function with two output parameters, `oport` and `tnext`, and three input parameters, `oport`, `tnow`, and `portinfo`.

For more information on the required MATLAB function parameters, see “Code an EDA Simulator Link MQ MATLAB Test Bench Function” on page 2-12.

- You can use the `oport` parameter to drive input signals instead of, or in addition to, using other signal sources, such as ModelSim `force` commands. Depending on your application, you might use any combination of input sources. However, if multiple sources drive signals to a single `oport`, you will need a resolution function to handle signal contention.

- 3 Initialize the function outputs `oport` and `tnext` to empty values, as in the following code excerpt:

```
tnext = [];  
oport = struct();
```

- 4 Make note of the data types of ports defined for the entity under simulation. The EDA Simulator Link MQ software converts VHDL data types to comparable MATLAB data types and vice versa. As you develop your MATLAB function, you must know the types of the data that it receives from and needs to return to ModelSim. This tutorial includes the following port data type definitions and conversions:

- The entity defined for this tutorial consists of three input ports of type `STD_LOGIC` and an output port of type `STD_LOGIC_VECTOR`.
- Data of type `STD_LOGIC_VECTOR` consists of a column vector of characters with one bit per character.
- The interface converts scalar data of type `STD_LOGIC` to a character that matches the character literal for the corresponding enumerated type.

For more information on interface data type conversions, see “Performing Data Type Conversions” on page 8-5.

- 5 Search for `oport.dout`. This line of code shows how the data that a MATLAB function receives from ModelSim might need to be converted for use in the MATLAB environment:

```
ud.buffer(cyc) = mv12dec(oport.dout)
```

In this case, the function receives `STD_LOGIC_VECTOR` data on `oport`. The function `mv12dec` converts the bit vector to a decimal value that can be used in arithmetic computations. “Performing Data Type Conversions” on page 8-5 provides a summary of the types of data conversions to consider when coding your own MATLAB functions.

- 6 Browse through the rest of `modsimrand_plot.m`.

## Running the Simulation

This section explains how to start and monitor this simulation, and rerun it, if necessary. When you have completed as many simulation runs as desired, shut down the simulation as described in the next section.

### Running the Simulation for the First Time

Before running the simulation for the first time, you must verify the client connection. You may also want to set breakpoints for debugging.

Perform the following steps:

- 1 Open ModelSim and MATLAB windows.
- 2 In MATLAB, verify the client connection by calling `hdldaemon` with the `'status'` option:

```
hdldaemon('status')
```

This function returns a message indicating a connection exists:

```
HLDaemon socket server is running on port 4795 with 1 connection
```

---

**Note** If you attempt to run the simulation before starting the `hdldaemon` in MATLAB, you will receive the following warning:

```
#ML Warn - MATLAB server not available (yet),  
The entity 'modsimrand' will not be active
```

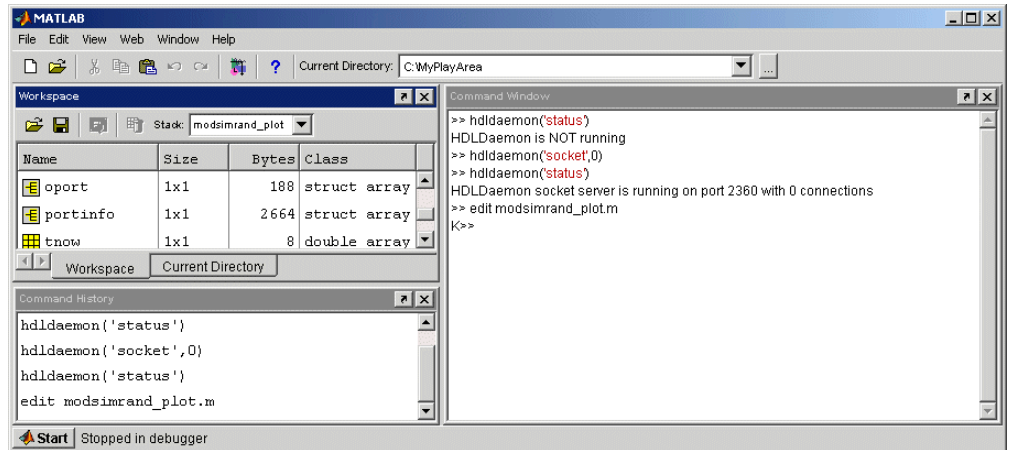
---

- 3 Open `modsimrand_plot.m` in the MATLAB Edit/Debug window.
- 4 Search for `oport.dout` and set a breakpoint at that line by clicking next to the line number. A red breakpoint marker will appear.
- 5 Return to ModelSim and enter the following command in the command window:

```
Vsim n> run 80000
```

This command instructs ModelSim to advance the simulation 80,000 time steps (80,000 nanoseconds using the default time step period). Because you previously set a breakpoint in `modsimrand_plot.m`, however, the simulation runs in MATLAB until it reaches the breakpoint.

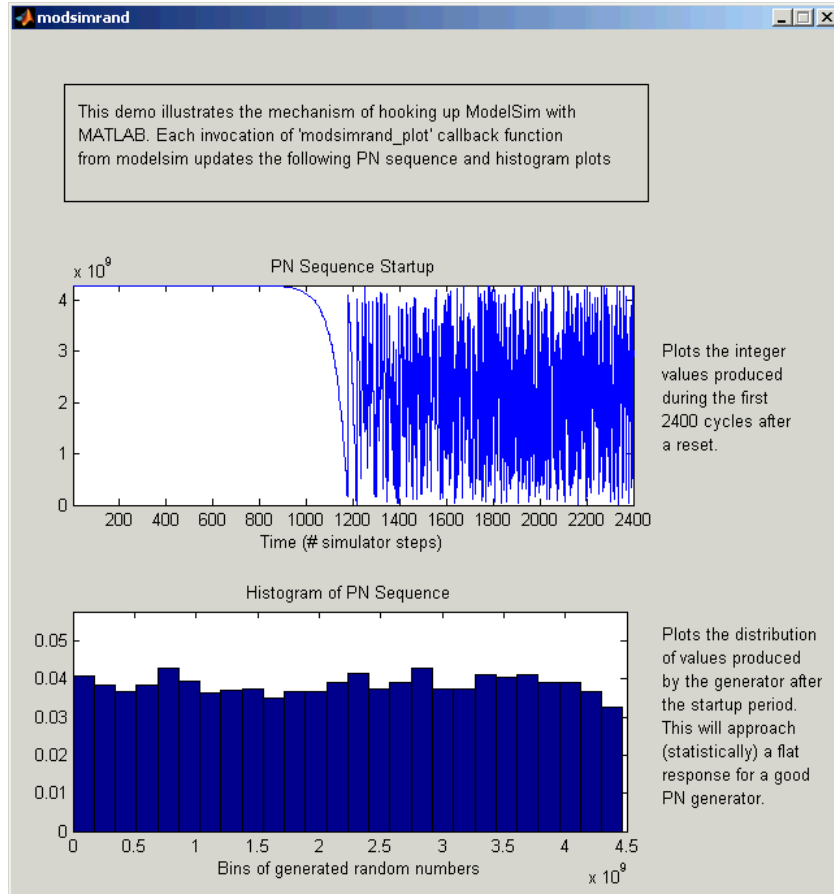
ModelSim is now blocked and remains blocked until you explicitly unblock it. While the simulation is blocked, note that MATLAB displays the data that ModelSim passed to the MATLAB function in the **Workspace** window.



An empty ModelSim figure window opens. You can use this window to plot data generated by the simulation.

- 6 Examine `oport`, `portinfo`, and `tnow`. Observe that `tnow`, the current simulation time, is set to 0. Also notice that, because the simulation has reached a breakpoint during the first call to `modsimrand_plot`, the `portinfo` is visible in the MATLAB workspace.
- 7 Click **Debug > Continue** in the MATLAB Edit/Debug window. The next time the breakpoint is reached, notice that `portinfo` no longer appears in the MATLAB workspace. The `portinfo` function does not show because it is passed in only on the first function invocation. Also note that the value of `tnow` advances from 0 to `5e-009`.
- 8 Clear the breakpoint by clicking the red breakpoint marker.
- 9 Unblock ModelSim and continue the simulation by clicking **Debug > Continue** in the MATLAB Edit/Debug window.

The simulation runs to completion. As the simulation progresses, it plots generated data in a figure window. When the simulation completes, the figure window appears as shown here.



The simulation runs in MATLAB until it reaches the breakpoint that you just set. Continue the simulation/debugging session as desired.

## Rerunning the Simulation

If you want to run the simulation again, you must restart the simulation in ModelSim, reinitialize the clock, and reset input signals. To do so:

- 1 Close the figure window.
- 2 Restart the simulation with the following command:

```
VSIM n> restart
```

The **Restart** dialog box appears. Leave all the options enabled, and click **Restart**.

---

**Note** The **Restart** button clears the simulation context established by a `matlabtb` command. Thus, after restarting ModelSim, you must reissue the previous command or issue a new command.

---

**3** Reissue the `matlabtb` command.

```
VSIM n> matlabtb modsimrand -mfunc modsimrand_plot  
-rising /modsimrand/clock -socket portnum
```

**4** Open `modsimrand_plot.m` in the MATLAB Edit/Debug window.

**5** Set a breakpoint at the same line as in the previous run.

**6** Return to ModelSim and re-enter the following commands to reinitialize clock and input signals:

```
Vsim n> force /modsimrand/clock 0 0,1 5 ns -repeat 10 ns  
Vsim n> force /modsimrand/clock_en 1  
Vsim n> force /modsimrand/reset 1 0, 0 50 ns
```

**7** Enter a command to start the simulation, for example:

```
Vsim n> run 80000
```

## Shutting Down the Simulation

This section explains how to shut down a simulation in an orderly way.

In ModelSim, perform the following steps:

**1** Stop the simulation on the client side by selecting **Simulate > End Simulation** or entering the quit command.

**2** Quit ModelSim.



In MATLAB, you can just quit the application, which will shut down the simulation and also close MATLAB.

To shut down the server without closing MATLAB, you have the option of calling `hdldaemon` with the `'kill'` option:

```
hdldaemon('kill')
```

The following message appears, confirming that the server was shut down:

```
HLDaemon server was shut down
```



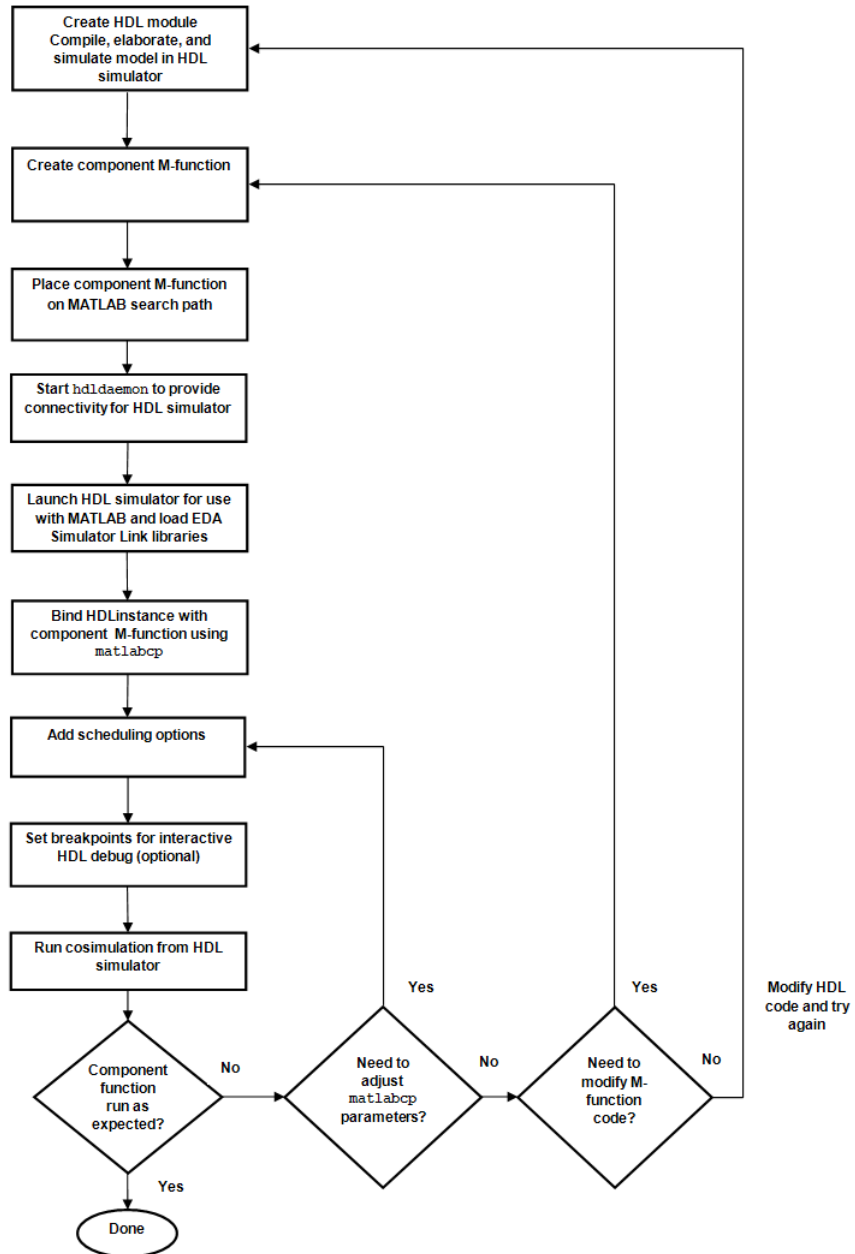
# Replacing an HDL Component with a MATLAB Component Function

---

- “Workflow for Creating a MATLAB Component Function for Use with the HDL Simulator” on page 3-2
- “Overview to Using a MATLAB Function as a Component” on page 3-5
- “Code HDL Modules for Visualization Using MATLAB” on page 3-7
- “Code an EDA Simulator Link MQ MATLAB Component Function” on page 3-8
- “Place Component Function on MATLAB Search Path” on page 3-10
- “Start hdd daemon to Provide Connection to HDL Simulator” on page 3-11
- “Start HDL Simulator for Use with MATLAB” on page 3-12
- “Invoke matlabcp to Bind and Schedule MATLAB Component Function Calls” on page 3-13
- “Run MATLAB Component Simulation” on page 3-14

## **Workflow for Creating a MATLAB Component Function for Use with the HDL Simulator**

The following workflow shows the steps necessary to create a MATLAB component function for cosimulation with the HDL simulator using EDA Simulator Link MQ.



The workflow is as follows:

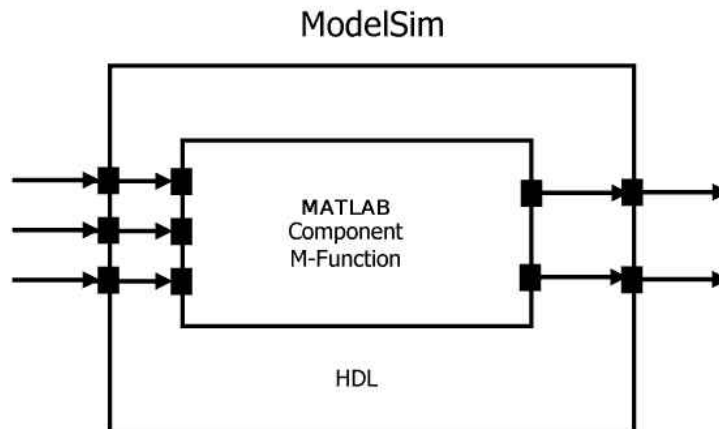
- Create HDL module. Compile, elaborate, and simulate model in HDL simulator.
- Create MATLAB component function.
- Place component function on MATLAB search path.
- Start hdldaemon to provide connection to HDL simulator.
- Launch HDL simulator for use with MATLAB and load EDA Simulator Link MQ libraries.
- Bind HDL instance with component function.
- Add scheduling options.
- Set breakpoints for interactive HDL debug (optional).
- Run cosimulation from HDL simulator.

## Overview to Using a MATLAB Function as a Component

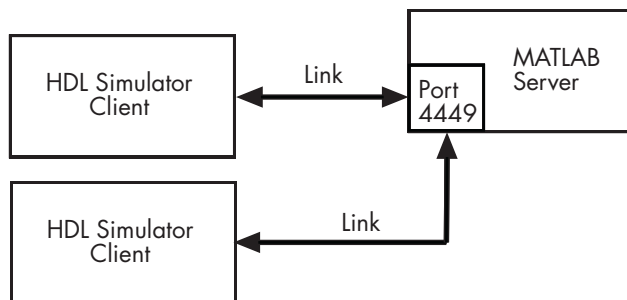
The EDA Simulator Link MQ software provides a means for visualizing HDL components within the MATLAB environment. You do so by coding an HDL model and a MATLAB M-function that can share data with the HDL model. This chapter discusses the programming, interfacing, and scheduling conventions for MATLAB component functions that communicate with the HDL simulator.

*MATLAB component* functions simulate the behavior of components in the HDL model. A stub module (providing port definitions only) in the HDL model passes its input signals to the MATLAB component function. The MATLAB component processes this data and returns the results to the outputs of the stub module. A MATLAB component typically provides some functionality (such as a filter) that is not yet implemented in the HDL code.

The following figure shows how an HDL simulator wraps around a MATLAB component function and how MATLAB communicates with the HDL simulator during a component simulation session.



When linked with MATLAB, the HDL simulator functions as the client, with MATLAB as the server. The following figure shows a multiple-client scenario connecting to the server at TCP/IP socket port 4449.



The MATLAB server can service multiple simultaneous HDL simulator sessions and HDL modules. However, you should follow recommended guidelines to ensure the server can track the I/O associated with each module and session. The MATLAB server, which you start with the supplied MATLAB function `hdldaemon`, waits for connection requests from instances of the HDL simulator running on the same or different computers. When the server receives a request, it executes the specified MATLAB function you have coded to perform tasks on behalf of a module in your HDL design. Parameters that you specify when you start the server indicate whether the server establishes shared memory or TCP/IP socket communication links.

Refer to “Establishing EDA Simulator Link MQ Machine Configuration Requirements” on page 7-10 for valid machine configurations.

---

**Note** The programming, interfacing, and scheduling conventions for test bench functions (see ) and component functions are virtually identical. Steps in the component workflow actually map to documentation for test bench functions; however, the same procedures apply to component functions.

---



## Code HDL Modules for Visualization Using MATLAB

The process for coding HDL modules for MATLAB visualization is as follows:

- Choose an HDL module name.
- Specify port direction modes in HDL components.
- Specify port data types in HDL components.
- Compile and debug the HDL model.

See “Code HDL Modules for Verification Using MATLAB ” on page 2-7 for full instructions on following this process.

## Code an EDA Simulator Link MQ MATLAB Component Function

### In this section...

“Overview to Coding an EDA Simulator Link MQ Component Function” on page 3-8

“Syntax of a Component Function” on page 3-9

### Overview to Coding an EDA Simulator Link MQ Component Function

Coding a MATLAB M-function that is to visualize an HDL module or component requires that you follow specific coding conventions. You must also understand the data type conversions that occur, and program data type conversions for operating on data and returning data to the HDL simulator.

To code a MATLAB function that is to verify an HDL module or component, perform the following steps:

- 1** Learn the syntax for a MATLAB EDA Simulator Link MQ component function (see “Syntax of a Component Function” on page 3-9).
- 2** Understand how EDA Simulator Link MQ software converts data from the HDL simulator for use in the MATLAB environment (see “Performing Data Type Conversions” on page 8-5 in Chapter 8, “Advanced Operational Topics”).
- 3** Choose a name for the MATLAB component function (see “Binding the HDL Module Component to the MATLAB Test Bench Function” on page 2-28).
- 4** Define expected parameters in the component function definition line (see “Defining EDA Simulator Link MQ M-Functions and Function Parameters” on page 9-2 in the Chapter 9, “M-Function Prototype Reference”).
- 5** Determine the types of port data being passed into the function (see “Defining EDA Simulator Link MQ M-Functions and Function Parameters” on page 9-2 in the Chapter 9, “M-Function Prototype Reference”).

- 6 Extract and, if appropriate for the simulation, apply information received in the `portinfo` structure (see “Gaining Access to and Applying Port Information” on page 9-5 in the Chapter 9, “M-Function Prototype Reference”).
- 7 Convert data for manipulation in the MATLAB environment, as necessary (see “Converting HDL Data to Send to MATLAB” on page 8-5 in Chapter 8, “Advanced Operational Topics”).
- 8 Convert data that needs to be returned to the HDL simulator (see “Converting Data for Return to the HDL Simulator” on page 8-10 in Chapter 8, “Advanced Operational Topics”).

## Syntax of a Component Function

The syntax of a MATLAB component function is

```
function [iport, tnext] = MyFunctionName(oport, tnow, portinfo)
```

The input/output arguments (`iport` and `oport`) for a MATLAB component function are the reverse of the port arguments for a MATLAB test bench function. That is, the MATLAB component function returns signal data to the *outputs* and receives data from the *inputs* of the associated HDL module.

Initialize the function outputs to empty values at the beginning of the function as in the following example:

```
tnext = [];  
oport = struct();
```

See the Chapter 9, “M-Function Prototype Reference” for an explanation of each of the function arguments. For more information on using `tnext` and `tnow` for simulation scheduling, see “Scheduling EDA Simulator Link MQ M-Functions Using the `tnext` Parameter” on page 9-8.

## **Place Component Function on MATLAB Search Path**

The MATLAB M-function that you are associating with an HDL component must be on the MATLAB search path or reside in the current working directory (see the MATLAB `cd` function). See “Place Test Bench Function on MATLAB Search Path” on page 2-22 for instructions on performing this process.

## **Start hlldaemon to Provide Connection to HDL Simulator**

See the “Start hlldaemon to Provide Connection to HDL Simulator” on page 2-23 section for instructions on starting hlldaemon.

## Start HDL Simulator for Use with MATLAB

See “Launching the HDL Simulator” on page 2-25 for instructions on starting the HDL simulator from MATLAB.

Refer to “Loading an HDL Design for Verification” on page 2-25 for instructions on loading an instance of an HDL module for visualization with the HDL simulator command `vsimmatlab`.

## **Invoke matlabcp to Bind and Schedule MATLAB Component Function Calls**

See “Invoking matlabb” on page 2-26 for instructions on invoking matlabcp (same as those for invoking matlabb).

See “Binding the HDL Module Component to the MATLAB Test Bench Function” on page 2-28 for instructions on binding the component function to the HDL module.

See “Scheduling Options for a Test Bench Session” on page 2-28 for instructions on scheduling component function calls using matlabcp. See “Scheduling EDA Simulator Link MQ M-Functions Using the tnext Parameter” on page 9-8 for instructions on scheduling component function calls using the tnext parameter of an M-function.

## Run MATLAB Component Simulation

Running a MATLAB component session is the same as running one for a test bench simulation. See “Run MATLAB Test Bench Simulation” on page 2-31 for instructions on running a MATLAB component cosimulation session with the HDL simulator.



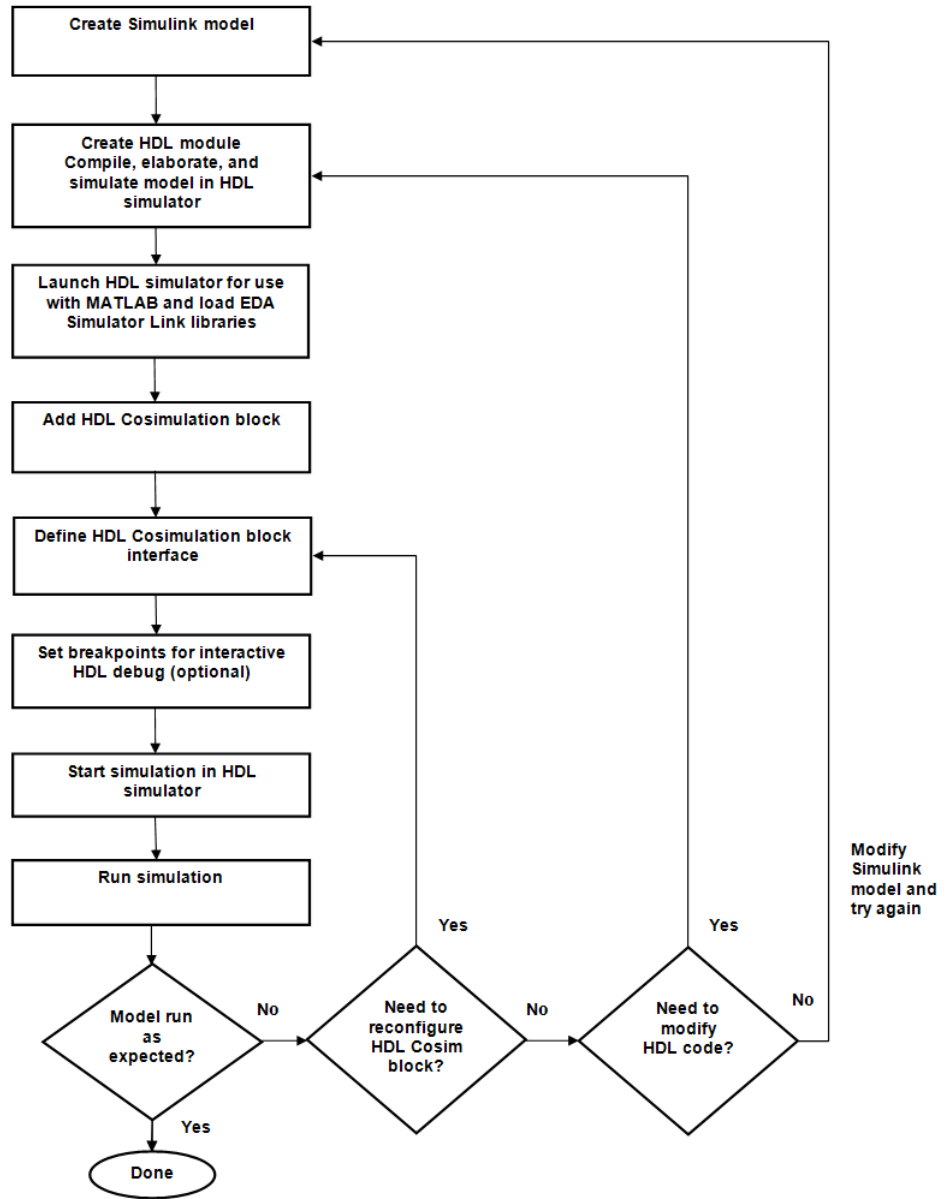
# Simulating an HDL Component in a Simulink Test Bench Environment

---

- “Workflow for Simulating an HDL Component in a Simulink Test Bench Environment” on page 4-2
- “Overview to Using Simulink as a Test Bench” on page 4-5
- “Create a Simulink Model for Test Bench Cosimulation with the HDL Simulator” on page 4-10
- “Code an HDL Component for Use with Simulink Test Bench Applications” on page 4-11
- “Launch HDL Simulator for Test Bench Cosimulation with Simulink” on page 4-12
- “Add the HDL Cosimulation Block to the Simulink Test Bench Model” on page 4-13
- “Define the HDL Cosimulation Block Interface (Simulink as Test Bench)” on page 4-14
- “Start the HDL Simulation” on page 4-41
- “Run a Test Bench Cosimulation Session (Simulink as Test Bench)” on page 4-42
- “Tutorial — Verifying an HDL Model Using Simulink, ModelSim, and the EDA Simulator Link MQ Software” on page 4-46

# **Workflow for Simulating an HDL Component in a Simulink Test Bench Environment**

The following workflow shows the steps necessary to cosimulate an HDL design using Simulink software as a test bench.



The workflow is as follows:

- Create Simulink model.
- Create HDL module. Compile, elaborate, and simulate model in HDL simulator.
- Launch HDL simulator for use with MATLAB and load EDA Simulator Link MQ libraries.
- Add HDL Cosimulation block.
- Define HDL Cosimulation block interfaces.
- Set breakpoints for interactive HDL debug (optional).
- Run cosimulation.

## Overview to Using Simulink as a Test Bench

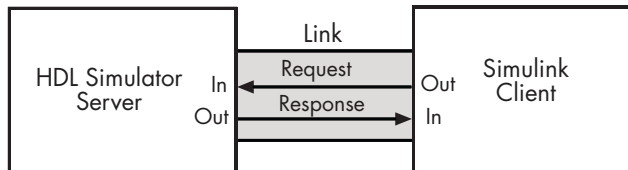
### In this section...

“Understanding How the HDL Simulator and Simulink Software Communicate Using EDA Simulator Link MQ” on page 4-5

“Introduction to the EDA Simulator Link MQ HDL Cosimulation Block” on page 4-8

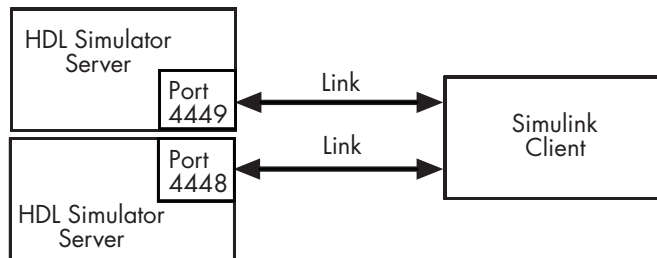
### Understanding How the HDL Simulator and Simulink Software Communicate Using EDA Simulator Link MQ

When you link the HDL simulator with a Simulink application, the simulator functions as the server, as shown in the following figure.



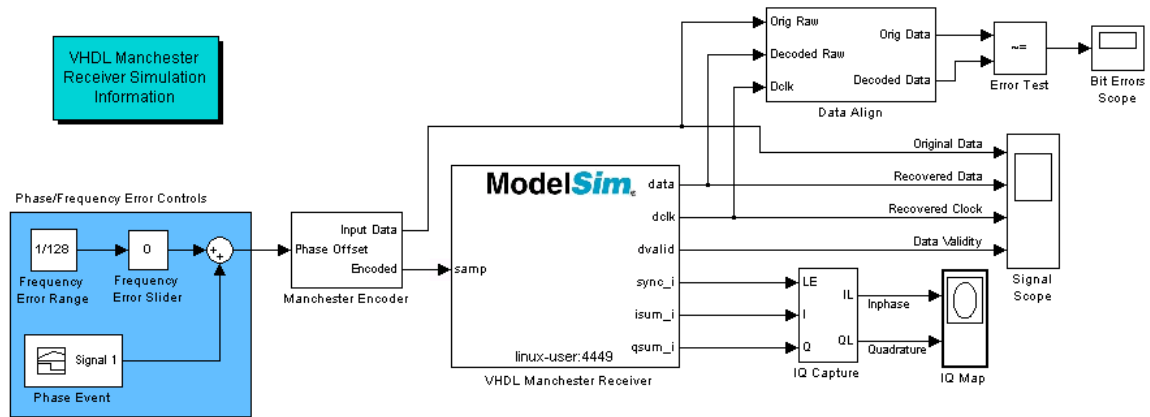
In this case, the HDL simulator responds to simulation requests it receives from cosimulation blocks in a Simulink model. You begin a cosimulation session from Simulink. After a session is started, you can use Simulink and the HDL simulator to monitor simulation progress and results. For example, you might add signals to a wave window to monitor simulation timing diagrams.

As the following figure shows, multiple cosimulation blocks in a Simulink model can request the service of multiple instances of the HDL simulator, using unique TCP/IP socket ports.



When you link the HDL simulator with a Simulink application, the simulator functions as the server. Using the EDA Simulator Link MQ communications interface, an HDL Cosimulation block cosimulates a hardware component by applying input signals to and reading output signals from an HDL model under simulation in the HDL simulator.

This figure shows a sample Simulink model that includes an HDL Cosimulation block. The connection is using shared memory.



Before running this model you must first launch ModelSim.  
 You can launch ModelSim on this computer using either a shared memory link or a TCP/IP socket link.

**Shared memory link:**

- 1) Be sure that the 'Connection' tab of the Cosimulation block dialog is set as follows:  
 'ModelSim running on this computer' is checked and 'Shared memory' is selected
- 2) Execute the following MATLAB command:  
`vsim('tclstart',manchestercmds)`
- 3) Start the Simulink simulation.

```
vsim('tclstart',manchestercmds)
%Double-click here to launch a new ModelSim
```

ModelSim Startup Command(Shared Memory)

**TCP/IP socket link:**

- 1) Be sure that the 'Connection' tab of the Cosimulation block dialog is set as follows:  
 'ModelSim running on this computer' is checked and 'Socket' is selected  
 'Port number or service' matches the port number used in the command below.
- 2) Execute the following MATLAB command:  
`vsim('tclstart',manchestercmds,'socketsimulink',4442)`
- 3) Start the Simulink simulation.

```
vsim('tclstart',manchestercmds,'socketsimulink',4442)
%Double-click here to launch a new ModelSim
```

ModelSim Startup Command(TCP/IP Socket)

The HDL Cosimulation block models a Manchester receiver that is coded in HDL. Other blocks and subsystems in the model include the following:

- Frequency Error Range block, Frequency Error Slider block, and Phase Event block
- Manchester encoder subsystem
- Data alignment subsystem
- Inphase/Quadrature (I/Q) capture subsystem
- Error Rate Calculation block from the Communications Blockset software

- Bit Errors block
- Data Scope block
- Discrete-Time Scatter Plot Scope block from the Communications Blockset software

For information on getting started with Simulink software, see the Simulink online help or documentation.

### Introduction to the EDA Simulator Link MQ HDL Cosimulation Block

The EDA Simulator Link MQ HDL Cosimulation Block links hardware components that are concurrently simulating in the HDL simulator to the rest of a Simulink model.

You can link Simulink and the HDL simulator in two possible ways:

- As a single HDL Cosimulation block fitted into the framework of a larger system-oriented Simulink model.
- As a Simulink model made up of a collection of HDL Cosimulation blocks, each representing a specific hardware component.

The block mask contains panels for entering port and signal information, setting communication modes, adding clocks, specifying pre- and post-simulation Tcl commands, and defining the timing relationship.

After you code one of your model's components in VHDL or Verilog and simulate it in the HDL simulator environment, you integrate the HDL representation into your Simulink model as an HDL Cosimulation block. This block, located in the Simulink Library, within the EDA Simulator Link MQ block library, is shown in the next figure.





You configure an HDL Cosimulation block by specifying values for parameters in a block parameters dialog box. The HDL Cosimulation block parameters dialog box consists of tabbed panes that specify the following information:

- **Ports Pane:** Block input and output ports that correspond to signals, including internal signals, of your HDL design, and an output sample time. See “Ports Pane” on page 12-4 in the Chapter 12, “Blocks — Alphabetical List”.
- **Connection Pane:** Type of communication and related settings to be used for exchanging data between simulators. See “Connection Pane” on page 12-10 in the Chapter 12, “Blocks — Alphabetical List”.
- **Timescales Pane:** The timing relationship between Simulink software and the HDL simulator. See “Timescales Pane” on page 12-14 in the Chapter 12, “Blocks — Alphabetical List”.
- **Clocks Pane:** Optional rising-edge and falling-edge clocks to apply to your model. See “Clocks Pane” on page 12-18 in the Chapter 12, “Blocks — Alphabetical List”.
- **Tcl Pane:** Tcl commands to run before and after a simulation. See “Tcl Pane” on page 12-22 in the Chapter 12, “Blocks — Alphabetical List”.

## Create a Simulink Model for Test Bench Cosimulation with the HDL Simulator

In this section...
“Creating Your Simulink Model” on page 4-10
“Running and Testing a Hardware Model in Simulink” on page 4-10
“Adding a Value Change Dump (VCD) File (Optional)” on page 4-10

### Creating Your Simulink Model

Create a Simulink test bench model by adding Simulink blocks from the Simulink Block libraries. For help with creating a Simulink model, see the Simulink documentation.

### Running and Testing a Hardware Model in Simulink

If you design a Simulink model first, run and test your model thoroughly before replacing or adding hardware model components as EDA Simulator Link MQ Cosimulation blocks.

### Adding a Value Change Dump (VCD) File (Optional)

You might want to add a VCD file to log changes to variable values during a simulation session. See Chapter 6, “Recording Simulink Signal State Transitions for Post-Processing” for instructions on adding the To VCD File block.

# Code an HDL Component for Use with Simulink Test Bench Applications

**In this section...**

“Overview to Coding HDL Components for Use with Simulink” on page 4-11

“Specifying Port Direction Modes in the HDL Component” on page 4-11

“Specifying Port Data Types in the HDL Component” on page 4-11

## Overview to Coding HDL Components for Use with Simulink

The most basic element of communication in the EDA Simulator Link MQ interface is the HDL module. The interface passes all data between the HDL simulator and Simulink as port data. The EDA Simulator Link MQ software works with any existing HDL module. However, when you code an HDL module that is targeted for Simulink verification, you should consider the types of data to be shared between the two environments and the direction modes. These factors are also ones you need to consider when you code an HDL component for use with Simulink as a test bench.

## Specifying Port Direction Modes in the HDL Component

In your module statement, you must specify each port with a direction mode (input, output, or bidirectional). See “Specifying Port Direction Modes in HDL Components (MATLAB as Test Bench)” on page 2-8 for descriptions of these port directions.

## Specifying Port Data Types in the HDL Component

You must specify data types compatible with Simulink for ports in your HDL modules. See “Specifying Port Data Types in HDL Components (MATLAB as Test Bench)” on page 2-8 for descriptions of supported port data types. For details on how the EDA Simulator Link MQ interface converts data types for the MATLAB and Simulink environments, see “Performing Data Type Conversions” on page 8-5.

# Launch HDL Simulator for Test Bench Cosimulation with Simulink

<b>In this section...</b>
“Starting the HDL Simulator from MATLAB” on page 4-12
“Loading an Instance of an HDL Module for Cosimulation” on page 4-12

## Starting the HDL Simulator from MATLAB

The options available for starting the HDL simulator for use with Simulink vary depending on whether you run the HDL simulator and Simulink on the same computer system.

If both tools are running on the same system, start the HDL simulator directly from MATLAB by calling the MATLAB function `vsim`. Alternatively, you can start the HDL simulator manually and load the EDA Simulator Link MQ libraries yourself. Either way, see “Starting the HDL Simulator” on page 1-22.

## Loading an Instance of an HDL Module for Cosimulation

After you start the HDL simulator from MATLAB, load an instance of an HDL module for cosimulation with the HDL simulator command extension `vsimulink`. Issue the command for each instance of an HDL module in your model that you want to cosimulate.

For example:

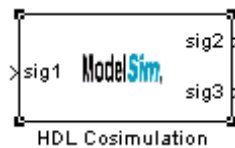
```
vsimulink work.manchester
```

This command opens a simulation workspace for `manchester` and displays a series of messages in the HDL simulator command window as the simulator loads the HDL module’s packages and architectures.

## Add the HDL Cosimulation Block to the Simulink Test Bench Model

After you code one of your model's components in VHDL or Verilog and simulate it in the HDL simulator environment, integrate the HDL representation into your Simulink model as an HDL Cosimulation block by performing the following steps:

- 1 Open your Simulink model, if it is not already open.
- 2 Delete the model component that the HDL Cosimulation block is to replace.
- 3 In the Simulink Library Browser, click the EDA Simulator Link MQ block library. The browser displays the HDL Cosimulation and To VCD block icons.



HDL  
Cosimulation

Block that has at least one input port and one output port.



To VCD File

Generates a Value Change Dump (VCD) file. For information on using this block, see Chapter 6, "Recording Simulink Signal State Transitions for Post-Processing".

- 4 Copy the HDL Cosimulation block icon from the Library Browser to your model. Simulink creates a link to the block at the point where you drop the block icon.
- 5 Connect any HDL Cosimulation block ports to appropriate blocks in your Simulink model.
  - To model a sink device, configure the block with inputs only.
  - To model a source device, configure the block with outputs only.

## Define the HDL Cosimulation Block Interface (Simulink as Test Bench)

### In this section...

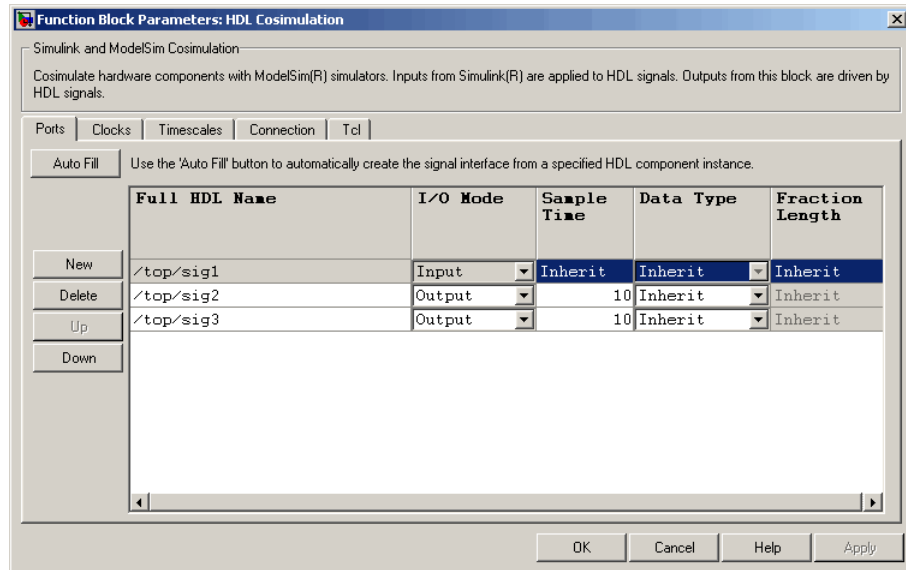
- “Accessing the HDL Cosimulation Block Interface” on page 4-14
- “Mapping HDL Signals to Block Ports” on page 4-15
- “Specifying the Signal Data Types” on page 4-27
- “Configuring the Simulink and HDL Simulator Timing Relationship” on page 4-27
- “Configuring the Communication Link in the HDL Cosimulation Block” on page 4-34
- “Specifying Pre- and Post-Simulation Tcl Commands with HDL Cosimulation Block Parameters Dialog Box” on page 4-36
- “Programmatically Controlling the Block Parameters” on page 4-38

### Accessing the HDL Cosimulation Block Interface

To open the block parameters dialog box for the HDL Cosimulation block, double-click the block icon.



Simulink displays the following Block Parameters dialog box.



## Mapping HDL Signals to Block Ports

The first step to configuring your EDA Simulator Link MQ Cosimulation block is to map signals and signal instances of your HDL design to port definitions in your HDL Cosimulation block. In addition to identifying input and output ports, you can specify a sample time for each output port. You can also specify a fixed-point data type for each output port.

The signals that you map can be at any level of the HDL design hierarchy.

To map the signals, you can perform either of the following actions:

- Enter signal information manually into the **Ports** pane of the HDL Cosimulation Block Parameters dialog box (see “Entering Signal Information Manually” on page 4-23). This approach can be more efficient when you want to connect a small number of signals from your HDL model to Simulink.
- Use the **Auto Fill** button to obtain signal information automatically by transmitting a query to the HDL simulator. This approach can save significant effort when you want to cosimulate an HDL model that has

many signals that you want to connect to your Simulink model. However, in some cases, you will need to edit the signal data returned by the query. See “Obtaining Signal Information Automatically from the HDL Simulator” on page 4-17 for details.

---

**Note** Verify that signals used in cosimulation have read/write access. You can check read/write access through the HDL simulator—see product documentation for details. This rule applies to all signals on the **Ports**, **Clocks**, and **Tcl** panes.

---

### Specifying HDL Signal/Port and Module Paths for Cosimulation

These rules are for signal/port and module path specifications in Simulink. Other specifications may work but are not guaranteed to work in this or future releases.

HDL designs generally do have hierarchy; that is the reason for this syntax. This specification does not represent a file name hierarchy.

Path specifications must follow these rules:

#### Path Specifications for Simulink Cosimulation Sessions with Verilog Top Level

- Path specification must start with a top-level module name.
- Path specification can include "." or "/" path delimiters, but cannot include a mixture.
- The leaf module or signal must match the HDL language of the top-level module.

The following examples show valid signal and module path specifications:

```
top.port_or_sig
/top/sub/port_or_sig
top
top/sub
top.sub1.sub2
```



The following examples show invalid signal and module path specifications:

```
top.sub/port_or_sig
:sub:port_or_sig
:
:sub
```

### **Path Specifications for Simulink Cosimulation Sessions with VHDL Top Level**

- Path specification may include the top-level module name but it is not required.
- Path specification can include "." or "/" path delimiters, but cannot include a mixture.
- The leaf module or signal must match the HDL language of the top-level module.

The following examples show valid signal and module path specifications:

```
top.port_or_sig
/sub/port_or_sig
top
top/sub
top.sub1.sub2
```

The following examples show invalid signal and module path specifications:

```
top.sub/port_or_sig
:sub:port_or_sig
:
:sub
```

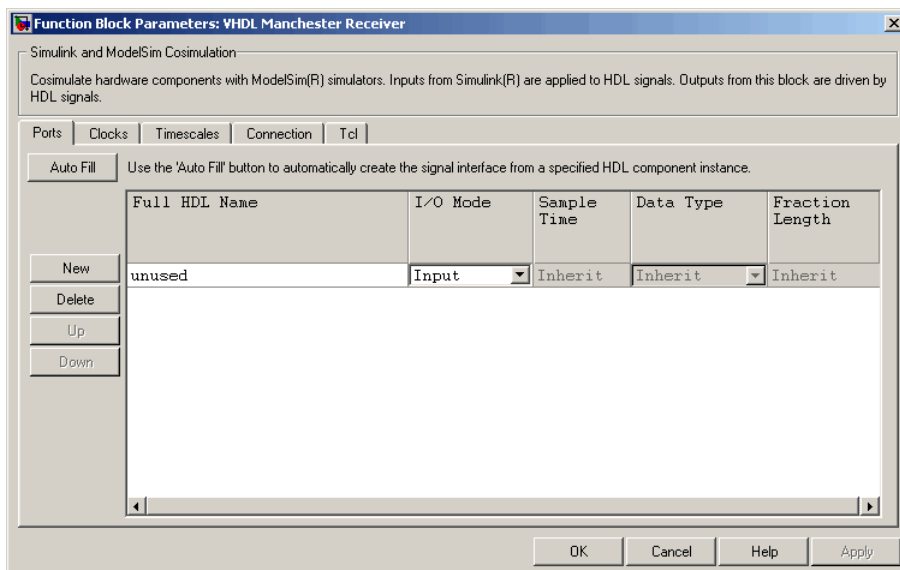
### **Obtaining Signal Information Automatically from the HDL Simulator**

The **Auto Fill** button lets you begin an HDL simulator query and supply a path to a component or module in an HDL model under simulation in the HDL simulator. Usually, some change of the port information is required after the query completes. You must have the HDL simulator running with the HDL module loaded for **Auto Fill** to work.

The following example describes the required steps.

The example is based on a modified copy of the Manchester Receiver model, in which all signals were first deleted from the **Ports** and **Clocks** panes.

- 1 Open the block parameters dialog box for the HDL Cosimulation block. Click the **Ports** tab. The **Ports** pane opens.

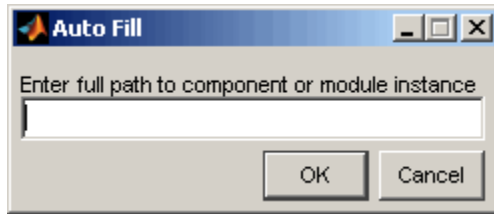


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**Tip** Delete all ports before performing **Auto Fill** to ensure that no unused signal remains in the Ports list at any time.

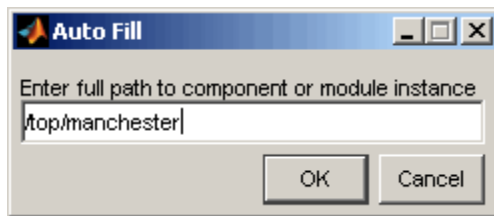
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- 2 Click the **Auto Fill** button. The **Auto Fill** dialog box opens.



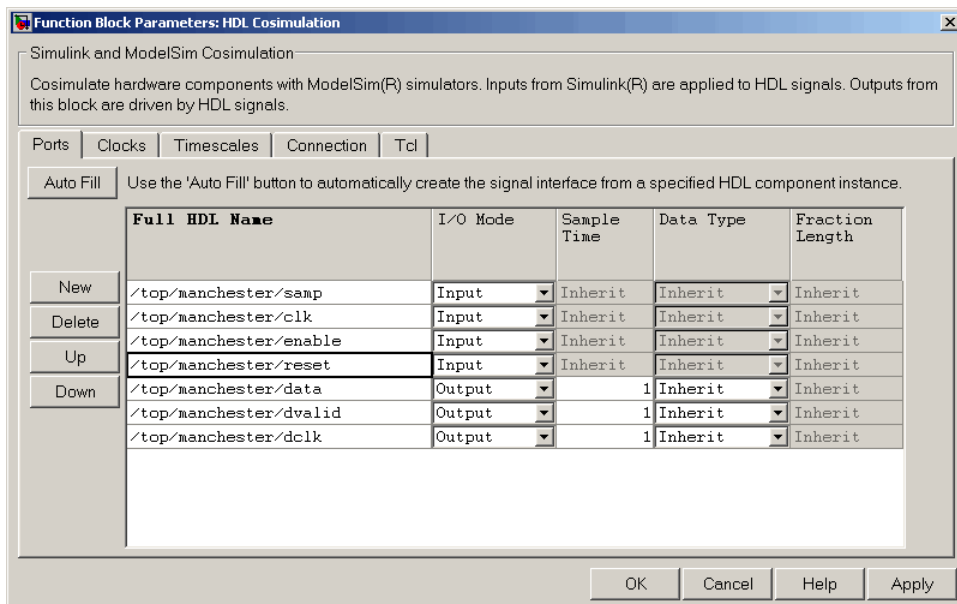
This modal dialog box requests an instance path to a component or module in your HDL model; here you enter an explicit HDL path into the edit field. The path you enter is not a file path and has nothing to do with the source files.

- 3** In this example, the Auto Fill feature obtains port data for a VHDL component called `manchester`. The HDL path is specified as `/top/manchester`.



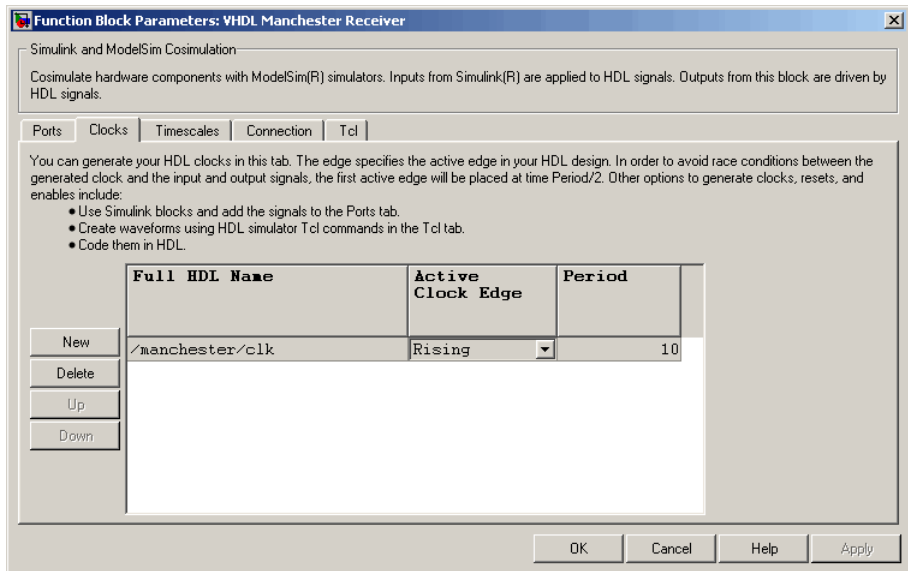
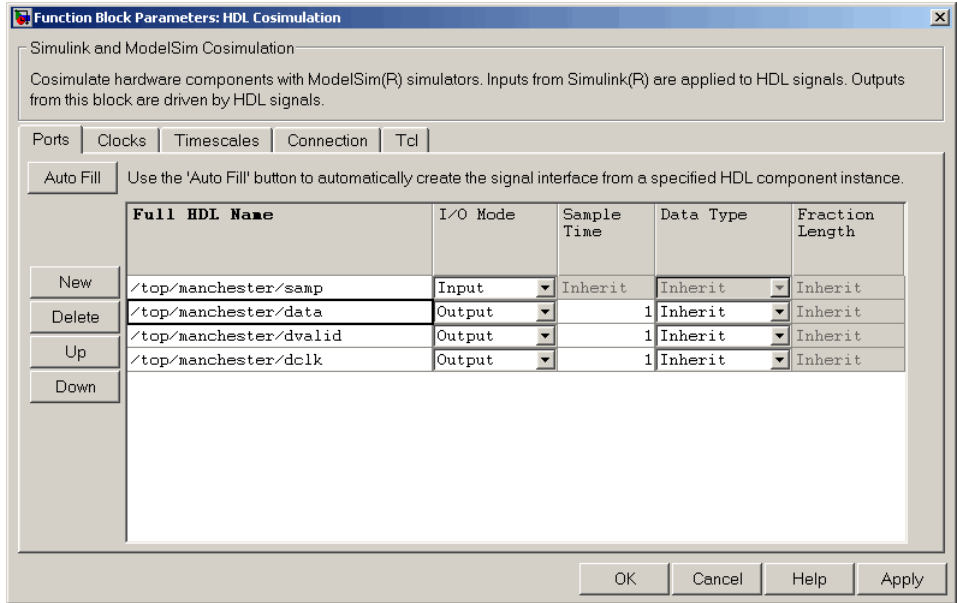
- 4** Click **OK** to dismiss the dialog box and the query is transmitted.
- 5** After the HDL simulator returns the port data, the Auto Fill feature enters it into the **Ports** pane, as shown in the following figure.

## 4 Simulating an HDL Component in a Simulink® Test Bench Environment



### 6 Click **Apply** to commit the port additions.

The preceding figure shows that the query entered clock, clock enable, and reset ports (labeled `clk`, `enable`, and `reset` respectively) into the ports list. In this example, the `clk` signal is entered in the **Clocks** pane, and the `enable` and `reset` signals are deleted from the **Ports** pane, as the next figures show.

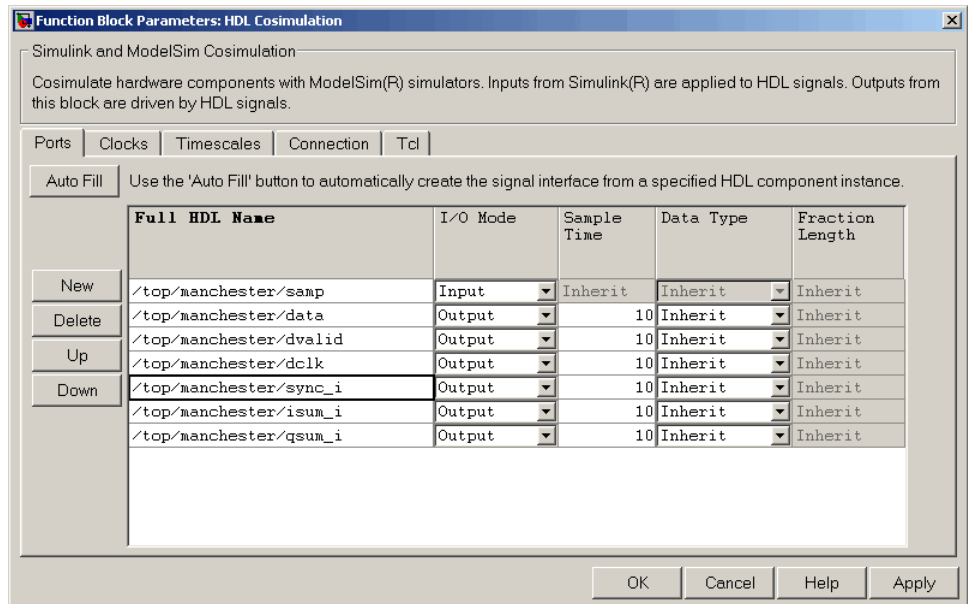


7 Auto Fill returns default values for output ports:

- **Sample time:** 1
- **Data type:** Inherit
- **Fraction length:** Inherit

You may need to change these values as required by your model. In this example, the **Sample time** should be set to 10 for all outputs. See also “Specifying the Signal Data Types” on page 4-27.

- 8 Before closing the HDL Cosimulation block parameters dialog box, click **Apply** to commit any edits you have made.



Observe that **Auto Fill** returned information about *all* inputs and outputs for the targeted component. In many cases, this will include signals that function in the HDL simulator but cannot be connected in the Simulink model. You may delete any such entries from the list in the **Ports** pane if they are unwanted. You *can* drive the signals from Simulink; you just have to define their values by laying down Simulink blocks.

Note that **Auto Fill** does not return information for internal signals. If your Simulink model needs to access such signals, you must enter them into the **Ports** pane manually. For example, in the case of the Manchester Receiver model, you would need to add output port entries for `top/manchester/sync_i`, `top/manchester/isum_i`, and `top/manchester/qsum_i`, as shown in step 8.

Note that `clk`, `reset`, and `clk_enable` *may* be in the Clocks and Tcl panes but they don't *have* to be. These signals can be ports if you choose to drive them explicitly from Simulink.

---

**Note** When you import VHDL signals using **Auto Fill**, the HDL simulator returns the signal names in all capitals.

---

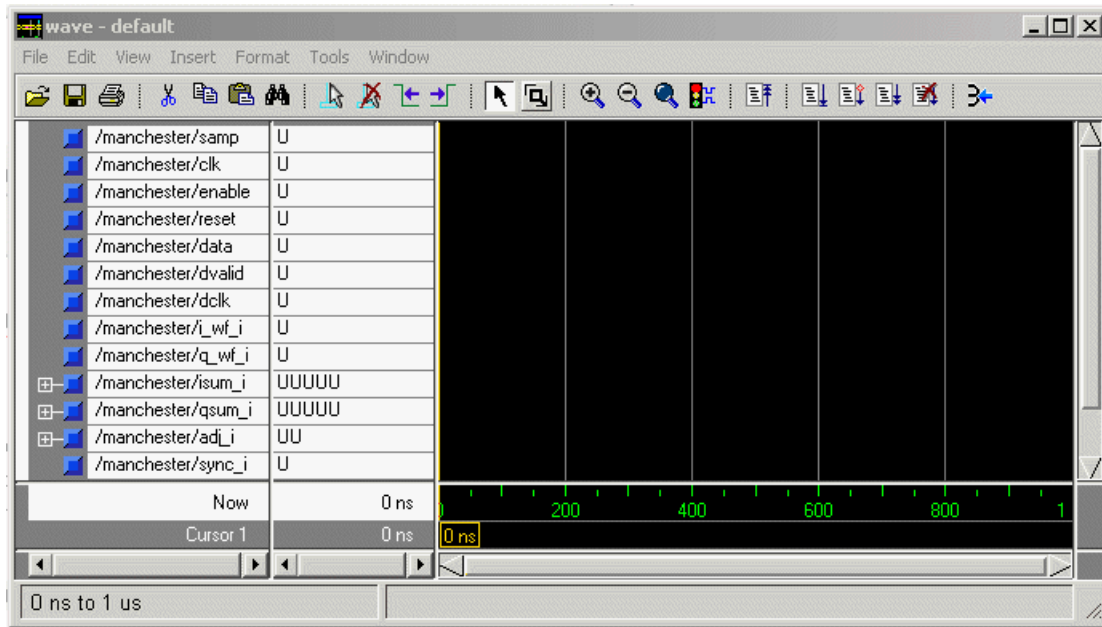
## Entering Signal Information Manually

To enter signal information directly in the **Ports** pane, perform the following steps:

- 1 In the HDL simulator, determine the signal path names for the HDL signals you plan to define in your block.

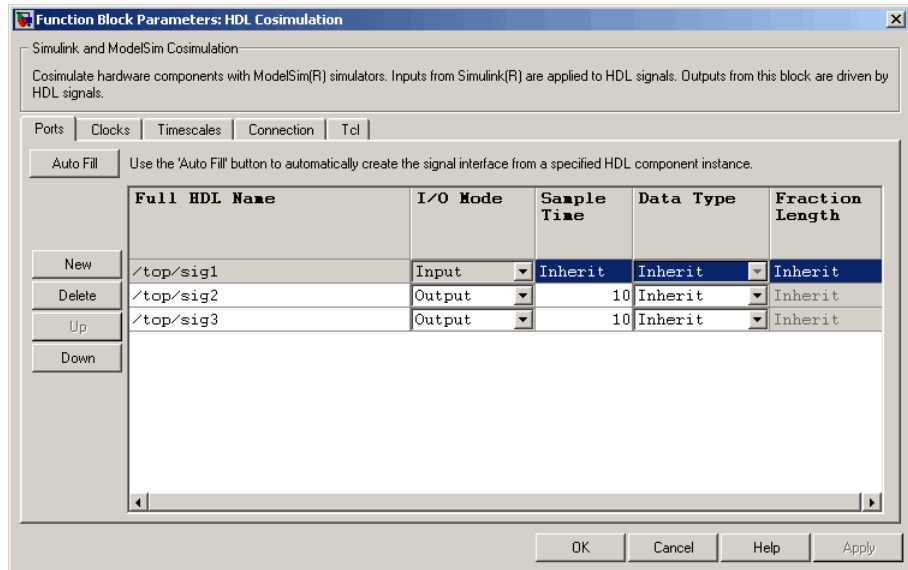
For example, the following shows all signals are subordinate to the top-level module `manchester`.

## 4 Simulating an HDL Component in a Simulink® Test Bench Environment



- 2 In Simulink, open the block parameters dialog box for your HDL Cosimulation block, if it is not already open.
- 3 Select the **Ports** pane tab. Simulink displays the following dialog box.





In this pane, you define the HDL signals of your design that you want to include in your Simulink block and set a sample time and data type for output ports. The parameters that you should specify on the **Ports** pane depend on the type of device the block is modeling as follows:

- For a device having both inputs and outputs: specify block input ports, block output ports, output sample times and output data types.

For output ports, accept the default or enter an explicit sample time.

Data types can be specified explicitly, or set to **Inherit** (the default). In the default case, the output port data type is inherited either from the signal connected to the port, or derived from the HDL model.

- For a sink device: specify block output ports.
- For a source device: specify block input ports.

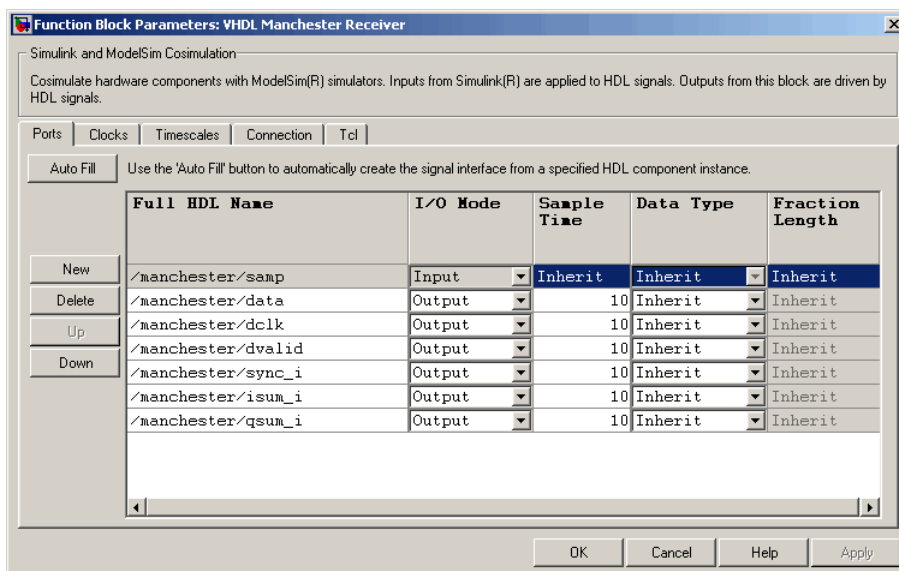
**4** Enter signal path names in the **Full HDL name** column by double-clicking on the existing default signal.

- Use HDL simulator path name syntax (see “Specifying HDL Signal/Port and Module Paths for Cosimulation” on page 4-16).

- If you are adding signals, click **New** and then edit the default values. Select either **Input** or **Output** from the **I/O Mode** column.
- If you want to, set the **Sample Time**, **Data Type**, and **Fraction Length** parameters for signals explicitly, as discussed in the remaining steps.

When you have finished editing clock signals, click **Apply** to register your changes with Simulink.

The following dialog box shows port definitions for an HDL Cosimulation block. The signal path names match path names that appear in the HDL simulator **wave** window.




---

**Note** When you define an input port, make sure that only one source is set up to force input to that port. If multiple sources drive a signal, your Simulink model may produce unpredictable results.

---

- 5 You must specify a sample time for the output ports. Simulink uses the value that you specify, and the current settings of the **Timescales** pane, to calculate an actual simulation sample time.

For more information on sample times in the EDA Simulator Link MQ cosimulation environment, see “Understanding the Representation of Simulation Time” on page 8-15.

- 6 You can configure the fixed-point data type of each output port explicitly if desired, or use a default (**Inherited**). In the default case, Simulink determines the data type for an output port as follows:

If Simulink can determine the data type of the signal connected to the output port, it applies that data type to the output port. For example, the data type of a connected Signal Specification block is known by back-propagation. Otherwise, Simulink queries the HDL simulator to determine the data type of the signal from the HDL module.

To assign an explicit fixed-point data type to a signal, perform the following steps:

- a Select either **Signed** or **Unsigned** from the **Data Type** column.
- b If the signal has a fractional part, enter the **Fraction Length**.

For example, if the model has an 8-bit signal with **Signed** data type and a **Fraction Length** of 5, the HDL Cosimulation block assigns it the data type `sfixed8_En5`. If the model has an **Unsigned** 16-bit signal with no fractional part (a **Fraction Length** of 0), the HDL Cosimulation block assigns it the data type `ufixed16`.

- 7 Before closing the dialog box, click **Apply** to register your edits.

## Specifying the Signal Data Types

The **Data Type** and **Fraction Length** parameters apply only to output signals. See **Data Type** and **Fraction Length** on the Ports pane description of the HDL Cosimulation block.

## Configuring the Simulink and HDL Simulator Timing Relationship

You configure the timing relationship between Simulink and the HDL simulator by using the **Timescales** pane of the block parameters dialog box. Before setting the **Timescales** parameters, you should read “Understanding the Representation of Simulation Time” on page 8-15 to understand the

supported timing modes and the issues that will determine your choice of timing mode.

You can specify either a relative or an absolute timing relationship between Simulink and the HDL simulator, as described in “Timescales Pane” on page 12-14 of the HDL Cosimulation block reference.

### Defining the Simulink and HDL Simulator Timing Relationship

The differences in the representation of simulation time can be reconciled in one of two ways using the EDA Simulator Link MQ interface:

- By defining the timing relationship manually (with **Timescales** pane)

When you define the relationship manually, you determine how many femtoseconds, picoseconds, nanoseconds, microseconds, milliseconds, seconds, or ticks in the HDL simulator represent 1 second in Simulink.

This quantity of HDL simulator time can be expressed in one of the following ways:

- In *relative* terms (i.e., as some number of HDL simulator ticks). In this case, the cosimulation is said to operate in *relative timing mode*. The HDL Cosimulation block defaults to relative timing mode for cosimulation. For more on relative timing mode, see “Relative Timing Mode” on page 8-18.
- In *absolute* units (such as milliseconds or nanoseconds). In this case, the cosimulation is said to operate in *absolute timing mode*. For more on absolute timing mode, see “Absolute Timing Mode” on page 8-21.

For more on relative and absolute time, see “Understanding the Representation of Simulation Time” on page 8-15.

- By allowing EDA Simulator Link MQ to define the timescale automatically (with **Auto Timescale** on the **Timescales** pane)

When you allow the link software to define the timing relationship, it attempts to set the timescale factor between the HDL simulator and Simulink to be as close as possible to 1 second in the HDL simulator = 1 second in Simulink. If this setting is not possible, the link product attempts to set the signal rate on the Simulink model port to the lowest possible number of HDL simulator ticks.

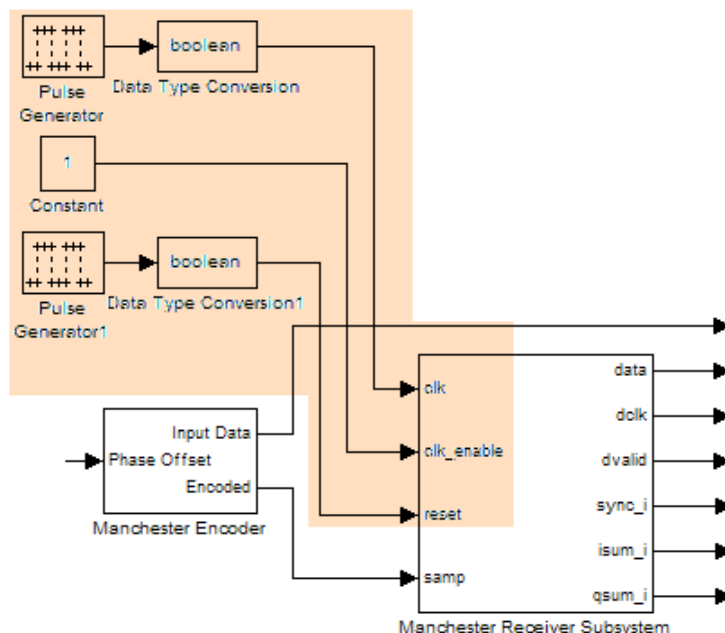
## Driving Clocks, Resets, and Enables

You can create rising-edge or falling-edge clocks, resets, or clock enable signals that apply internal stimuli to your model under cosimulation. You can add these signals in the following ways:

- “Adding Signals Using Simulink Blocks” on page 4-29
- “Creating Optional Clocks with the Clocks Pane of the HDL Cosimulation Block” on page 4-30
- “Driving Signals by Adding Force commands” on page 4-33
- Implement clocks, resets, and enable signals in HDL code. If your model is part of a much larger HDL design, you (or the larger model designer) may choose to implement these signals in the Verilog or VHDL files. However, that implementation exceeds the scope of this documentation; see an HDL reference for more information.

**Adding Signals Using Simulink Blocks.** Add rising-edge or falling-edge clocks, resets, or clock enable signals to your Simulink model using Simulink blocks.

In the following example excerpt, the shaded area shows a clock, a reset, and a clock enable signal as input to a multiple HDL Cosimulation block model. These signals are created using two Simulink data type conversion blocks and a constant source block

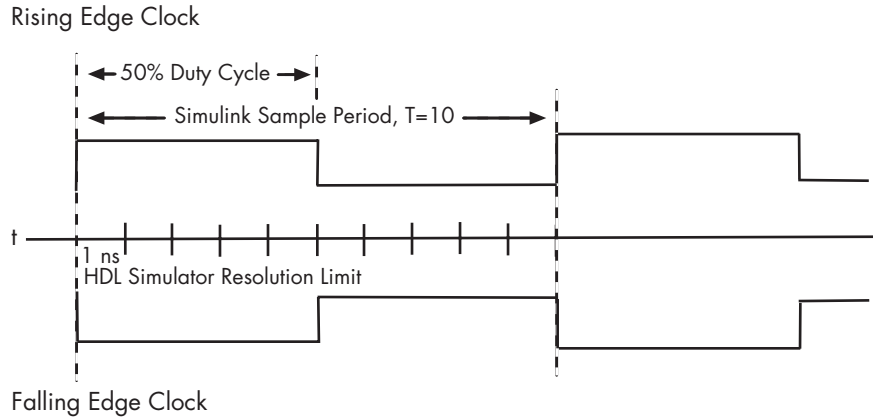


### Creating Optional Clocks with the Clocks Pane of the HDL Cosimulation Block.

When you specify a clock in your block definition, Simulink creates a rising-edge or falling-edge clock that drives the specified HDL signals by depositing them.

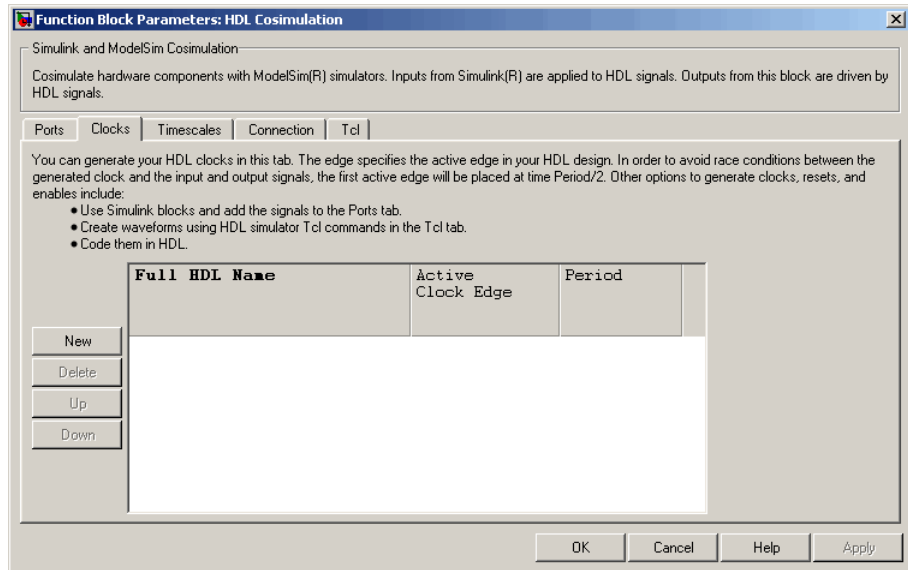
Simulink attempts to create a clock that has a 50% duty cycle and a predefined phase that is inverted for the falling edge case. If necessary, Simulink degrades the duty cycle to accommodate odd Simulink sample times, with a worst case duty cycle of 66% for a sample time of  $T=3$ .

The following figure shows a timing diagram that includes rising and falling edge clocks with a Simulink sample time of  $T=10$  and an HDL simulator resolution limit of 1 ns. The figure also shows that given those timing parameters, the clock duty cycle is 50%.



To create clocks, perform the following steps:

- 1** In the HDL simulator, determine the clock signal path names you plan to define in your block. To do so, you can use the same method explained for determining the signal path names for ports in step 1 of “Mapping HDL Signals to Block Ports” on page 4-15.
- 2** Select the **Clocks** tab of the Block Parameters dialog box. Simulink displays the dialog box as shown in the next figure.



**3** Click **New** to add a new clock signal.

**4** Edit the clock signal path name directly in the table under the **Full HDL Name** column. To do so, double-click the default clock signal name (/top/c1k). Then, specify your new clock using HDL simulator path name syntax. See “Specifying HDL Signal/Port and Module Paths for Cosimulation” on page 4-16.

The HDL simulator does not support vectored signals in the **Clocks** pane. Signals must be logic types with 1 and 0 values.

**5** To specify whether the clock generates a rising-edge or falling edge signal, select **Rising** or **Falling** from the **Active Clock Edge** list.

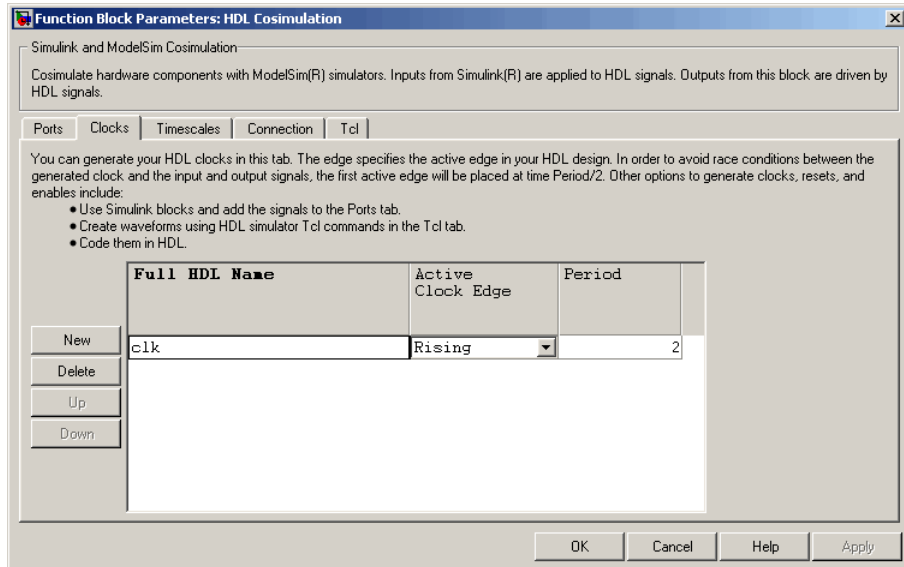
**6** The **Period** field specifies the clock period. Accept the default (2), or override it by entering the desired clock period explicitly by double-clicking in the **Period** field.

Specify the **Period** field as an even integer, with a minimum value of 2.

**7** When you have finished editing clock signals, click **Apply** to register your changes with Simulink.



The following dialog box defines the rising-edge clock `clk` for the HDL Cosimulation block, with a default period of 2.



**Driving Signals by Adding Force commands.** Drive clocks, resets, and enable signals by adding force commands to the **Tcl** pane.

For example:

```
force /iqconv/clk 1 0, 0 5 ns -repeat 10 ns
force /iqconv/clk_enable 1
force /iqconv/reset 1
```

You can also drive signals with the `vsim` and `force` commands.

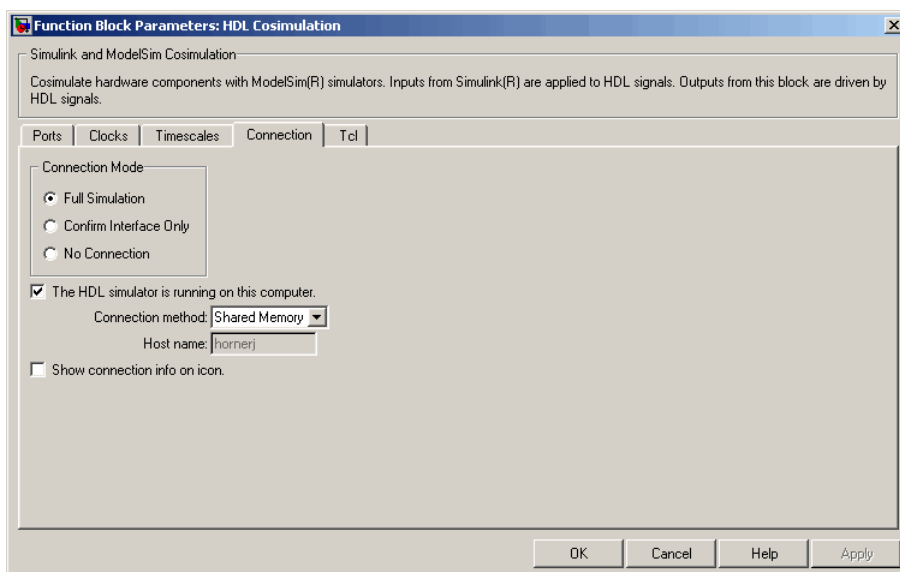
For example:

```
vsim('tclstart', {'force /iqconv/clk 1 0, 0 5 ns -repeat 10 ns ',
'force /iqconv/clk_enable 1', 'force /iqconv/reset 1'});
```

### Configuring the Communication Link in the HDL Cosimulation Block

You must select shared memory or socket communication (see “Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8).

After you decide, configure a block’s communication link with the **Connection** pane of the block parameters dialog box.



The following steps guide you through the communication configuration:

- 1 Determine whether Simulink and the HDL simulator are running on the same computer. If they are, skip to step 4.
- 2 Clear the **The HDL simulator is running on this computer** check box. (This check box defaults to selected.) Because Simulink and the HDL simulator are running on different computers, **Connection method** is automatically set to **Socket**.
- 3 Enter the host name of the computer that is running your HDL simulation (in the HDL simulator) in the **Host name** text field. In the **Port number**

**or service** text field, specify a valid port number or service for your computer system. For information on choosing TCP/IP socket ports, see “Choosing TCP/IP Socket Ports” on page 7-13. Skip to step 5.

- 4** If the HDL simulator and Simulink are running on the same computer, decide whether you are going to use shared memory or TCP/IP sockets for the communication channel. For information on the different modes of communication, see “Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8.

If you choose TCP/IP socket communication, specify a valid port number or service for your computer system in the **Port number or service** text field. For information on choosing TCP/IP socket ports, see “Choosing TCP/IP Socket Ports” on page 7-13.

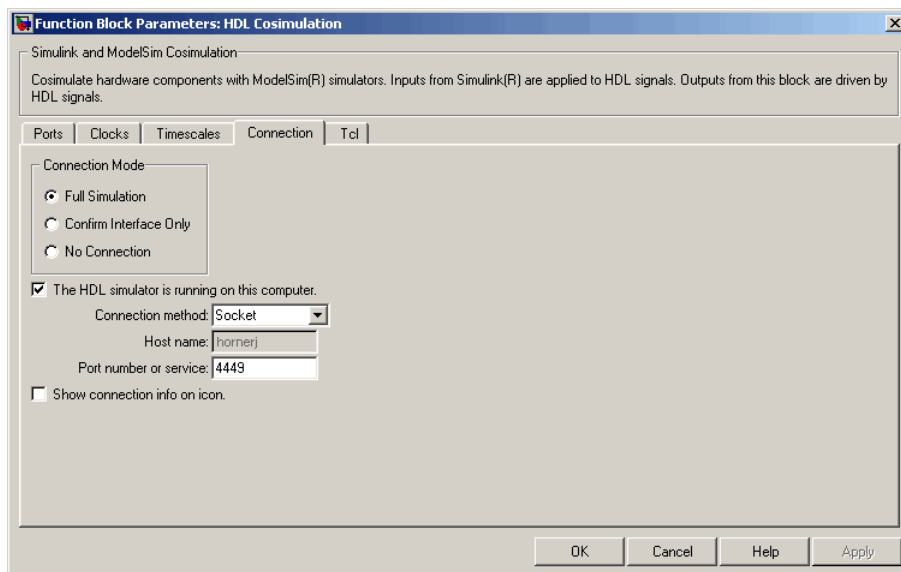
If you choose shared memory communication, select the **Shared memory** check box.

- 5** If you want to bypass the HDL simulator when you run a Simulink simulation, use the **Connection Mode** options to specify what type of simulation connection you want. Select one of the following options:
  - **Full Simulation:** Confirm interface and run HDL simulation (default).
  - **Confirm Interface Only:** Check HDL simulator for proper signal names, dimensions, and data types, but do not run HDL simulation.
  - **No Connection:** Do not communicate with the HDL simulator. The HDL simulator does not need to be started.

With the second and third options, EDA Simulator Link MQ software does not communicate with the HDL simulator during Simulink simulation.

- 6** Click **Apply**.

The following example dialog box shows communication definitions for an HDL Cosimulation block. The block is configured for Simulink and the HDL simulator running on the same computer, communicating in TCP/IP socket mode over TCP/IP port 4449.



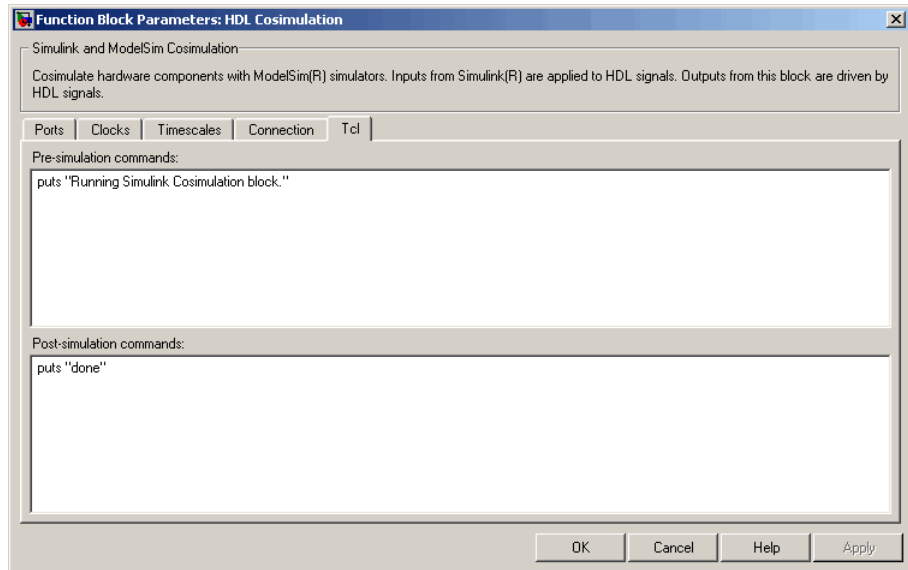
### Specifying Pre- and Post-Simulation Tcl Commands with HDL Cosimulation Block Parameters Dialog Box

You have the option of specifying Tcl commands to execute before and after the HDL simulator simulates the HDL component of your Simulink model. *Tcl* is a programmable scripting language supported by most HDL simulation environments. Use of Tcl can range from something as simple as a one-line puts command to confirm that a simulation is running or as complete as a complex script that performs an extensive simulation initialization and startup sequence. For example, you can use the **Post-simulation command** field on the Tcl Pane to instruct the HDL simulator to restart at the end of a simulation run.

You can specify the pre-simulation and post-simulation Tcl commands by entering Tcl commands in the **Pre-simulation** commands or **Post-simulation** commands text fields of the HDL Cosimulation block.

To specify Tcl commands, perform the following steps:

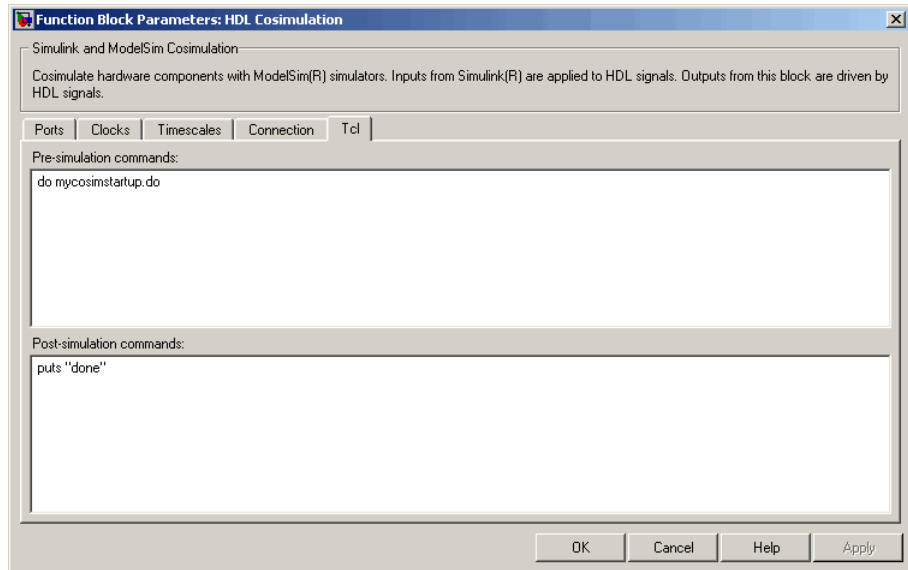
- 1 Select the **Tcl** tab of the Block Parameters dialog box. The dialog box appears as follows.



The **Pre-simulation commands** text box includes an puts command for reference purposes.

- 2 Enter one or more commands in the **Pre-simulation command** and **Post-simulation command** text boxes. You can specify one Tcl command per line in the text box or enter multiple commands per line by appending each command with a semicolon (;), which is the standard Tcl concatenation operator.

Alternatively, you can create a ModelSim DO file that lists Tcl commands and then specify that file with the ModelSim do command as shown in the following figure.



3 Click **Apply**.

### Programmatically Controlling the Block Parameters

One way to control block parameters is through the HDL Cosimulation block graphical dialog box. However, you can also control blocks by programmatically controlling the mask parameter values and the running of simulations. Parameter values can be read using the Simulink `get_param` function and written using the Simulink `set_param` function. All block parameters have attributes that indicate whether they are:

- Tunable — The attributes can change during the simulation run.
- Evaluated — The parameter string value undergoes an evaluation to determine its actual value used by the S-Function.

The HDL Cosimulation block does not have any tunable parameters; thus, you get an error if you try to change a value while the simulation is running. However, it does have a few evaluated parameters.

You can see the list of parameters and their attributes by performing a right-mouse click on the block, selecting **View Mask**, and then the

**Parameters** tab. The **Variable** column shows the programmatic parameter names. Alternatively, you can get the names programmatically by selecting the HDL Cosimulation block and then typing the following commands at the MATLAB prompt:

```
>> get_param(gcf, 'DialogParameters')
```

Some examples of using MATLAB to control simulations and mask parameter values follow. Usually, the commands are put into an M-script or M-function file and automatically called by several callback hooks available to the model developer. You can place the code in any of these suggested locations, or anywhere you choose:

- In the model workspace, e.g., **View > Model Explorer > Simulink Root > *model\_name* > Model Workspace > Data Source is M-Code**.
- In a model callback, e.g., **File > Model Properties > Callbacks**.
- A subsystem callback (right-mouse click on an empty subsystem and then select **Block Properties > Callbacks**). Many of the EDA Simulator Link MQ demos use this technique to start the HDL simulator by placing M-code in the OpenFcn callback.
- The HDL Cosimulation block callback (right-mouse click on HDL Cosimulation block, and then select **Block Properties > Callbacks**).

### Example: Scripting the Value of the Socket Number for HDL Simulator Communication

In a regression environment, you may need to determine the socket number for the Simulink/HDL simulator connection during the simulation to avoid collisions with other simulation runs. This example shows code that could handle that task. The script is for a 32-bit Linux platform.

```
ttcp_exec = [matlabroot '/toolbox/shared/hdlink/scripts/ttcp_glnx'];
[status, results] = system([ttcp_exec ' -a']);
if ~s
    parsed_result = strread(results,'%s');
    avail_port = parsed_result{2};
else
    error(results);
end
```

```
set_param('MyModel/HDL Cosimulation', 'CommPortNumber', avail_port);
```



## **Start the HDL Simulation**

Start the simulation running in the HDL simulator.

## Run a Test Bench Cosimulation Session (Simulink as Test Bench)

### In this section...

“Setting Simulink Software Configuration Parameters” on page 4-42

“Determining an Available Socket Port Number” on page 4-44

“Checking the Connection Status” on page 4-44

“Running and Testing a Cosimulation Model” on page 4-44

“Avoiding Race Conditions in HDL Simulation When Cosimulating With the EDA Simulator Link MQ HDL Cosimulation Block” on page 4-45

### Setting Simulink Software Configuration Parameters

When you create a Simulink model that includes one or more EDA Simulator Link MQ Cosimulation blocks, you might want to adjust certain Simulink parameter settings to best meet the needs of HDL modeling. For example, you might want to adjust the value of the **Stop time** parameter in the **Solver** pane of the Configuration Parameters dialog box.

You can adjust the parameters individually or you can use the M-file `dspstartup`, which lets you automate the configuration process so that every new model that you create is preconfigured with the following relevant parameter settings:

Parameter	Default Setting
'SingleTaskRateTransMsg'	'error'
'Solver'	'fixedstepdiscrete'
'SolverMode'	'singletasking'
'StartTime'	'0.0'
'StopTime'	'inf'
'FixedStep'	'auto'
'SaveTime'	'off'

<b>Parameter</b>	<b>Default Setting</b>
'SaveOutput'	'off'
'AlgebraicLoopMsg'	'error'

The default settings for `SaveTime` and `SaveOutput` improve simulation performance.

You can use `dspstartup` by entering it at the MATLAB command line or by adding it to the Simulink `startup.m` file. You also have the option of customizing `dspstartup` settings. For example, you might want to adjust the `StopTime` to a value that is optimal for your simulations, or set `SaveTime` to "on" to record simulation sample times.

For more information on using and customizing `dspstartup`, see the Signal Processing Blockset documentation. For more information about automating tasks at startup, see the description of the `startup` command in the MATLAB documentation.

### Determining an Available Socket Port Number

To determine an available socket number use: `ttcp -a` a shell prompt.

### Checking the Connection Status

You can check the connection status by clicking the Update diagram button



or by selecting **Edit > Update Diagram**. If there is a connection error, Simulink will notify you.

The MATLAB command `pingHdlSim` can also be used to check the connection status. If a `-1` is returned, then there is no connection with the HDL simulator.

### Running and Testing a Cosimulation Model

To run and test a cosimulation model in Simulink, click **Simulation > Start**



or the Start Simulation button in your Simulink model window. Simulink runs the model and displays any errors that it detects.

If you need to reset a clock during a cosimulation, you can do so by entering HDL simulator `force` commands at the HDL simulator command prompt or by specifying HDL simulator `force` commands in the **Post-simulation command** text field on the **Tcl** pane of your EDA Simulator Link MQ Cosimulation block's parameters dialog box.

If you change any part of the Simulink model, including the HDL Cosimulation block parameters, rerun the simulation or click the Update



diagram button or select **Edit > Update Diagram** so that the diagram reflects those changes.

## **Avoiding Race Conditions in HDL Simulation When Cosimulating With the EDA Simulator Link MQ HDL Cosimulation Block**

In the ModelSim HDL simulator, you cannot control the order in which clock signals (rising-edge or falling-edge) defined in the HDL Cosimulation block are applied, relative to the data inputs driven by these clocks. If you are careful to ensure the relationship between the data and active edges of the clock, you can avoid race conditions that could create nondeterministic cosimulation results.

For more on race conditions in hardware simulators, see “Avoiding Race Conditions in HDL Simulators” on page 8-2.

# Tutorial – Verifying an HDL Model Using Simulink, ModelSim, and the EDA Simulator Link MQ Software

### In this section...

“Tutorial Overview” on page 4-46

“Developing the VHDL Code” on page 4-47

“Compiling the VHDL File” on page 4-48

“Creating the Simulink Model” on page 4-50

“Setting Up ModelSim for Use with Simulink” on page 4-59

“Loading Instances of the VHDL Entity for Cosimulation with Simulink” on page 4-59

“Running the Simulation” on page 4-60

“Shutting Down the Simulation” on page 4-63

## Tutorial Overview

This chapter guides you through the basic steps for setting up an EDA Simulator Link MQ session that uses Simulink and the HDL Cosimulation block to verify an HDL model. The HDL Cosimulation block cosimulates a hardware component by applying input signals to and reading output signals from an HDL model under simulation in ModelSim. The HDL Cosimulation block supports simulation of either VHDL or Verilog models. In the tutorial in this section, you will cosimulate a simple VHDL model.

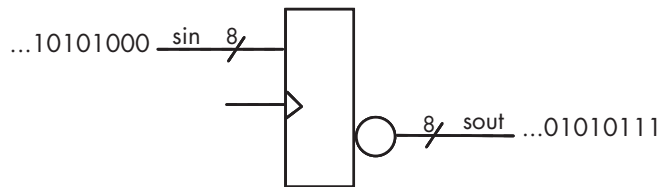
### Using the `invertercmds.m` File

Included with your EDA Simulator Link MQ installation is the file `invertercmds.m`, located in the directory `matlabroot/toolbox/modelsim/modelsimdemos`. The returned cell array can be passed as parameters (`cmd`) to `vsimulink`. These parameters, when used with the `vsimulink` command, launch ModelSim and build the VHDL source file created in “Developing the VHDL Code” on page 4-47.

Use of this file is not required. It is provided only for your convenience. You may complete each step manually and forego using this file, if you so choose.

## Developing the VHDL Code

A typical Simulink and ModelSim scenario is to create a model for a specific hardware component in ModelSim that you later need to integrate into a larger Simulink model. The first step is to design and develop a VHDL model in ModelSim. In this tutorial, you use ModelSim and VHDL to develop a model that represents the following inverter:



The VHDL entity for this model will represent 8-bit streams of input and output signal values with an IN port and OUT port of type STD\_LOGIC\_VECTOR. An input clock signal of type STD\_LOGIC will trigger the bit inversion process when set.

Perform the following steps:

- 1 Start ModelSim
- 2 Change to the writable directory MyPlayArea, which you may have created for another tutorial. If you have not created the directory, create it now. The directory must be writable.

```
ModelSim>cd C:/MyPlayArea
```

- 3 Open a new VHDL source edit window.
- 4 Add the following VHDL code:

```
-----
-- Simulink and ModelSim Inverter Tutorial
--
-- Copyright 2003-2004 The MathWorks, Inc.
-- $Date: 2008/12/23 17:43:14 $
-----
LIBRARY ieee;
```

```
USE ieee.std_logic_1164.ALL;
ENTITY inverter IS PORT (
    sin : IN  std_logic_vector(7 DOWNTO 0);
    sout: OUT std_logic_vector(7 DOWNTO 0);
    clk : IN  std_logic
);
END inverter;

LIBRARY ieee;
USE ieee.std_logic_1164.ALL;
ARCHITECTURE behavioral OF inverter IS
BEGIN
    PROCESS(clk)
    BEGIN
        IF (clk'EVENT AND clk = '1') THEN
            sout <= NOT sin;
        END IF;
    END PROCESS;
END behavioral;
```

5 Save the file to `inverter.vhd`.

### Compiling the VHDL File

This section explains how to set up a design library and compile `inverter.vhd`, as follows:

- 1 Verify that the file `inverter.vhd` is in the current directory by entering the `ls` command at the ModelSim command prompt.
- 2 Create a design library to hold your compilation results. To create the library and required `_info` file, enter the `vlib` and `vmap` commands as follows:

```
ModelSim> vlib work
```

```
ModelSim> vmap work work
```

If the design library `work` already exists, ModelSim *does not* overwrite the current library, but displays the following warning:



```
# ** Warning: (vlib-34) Library already exists at "work".
```

---

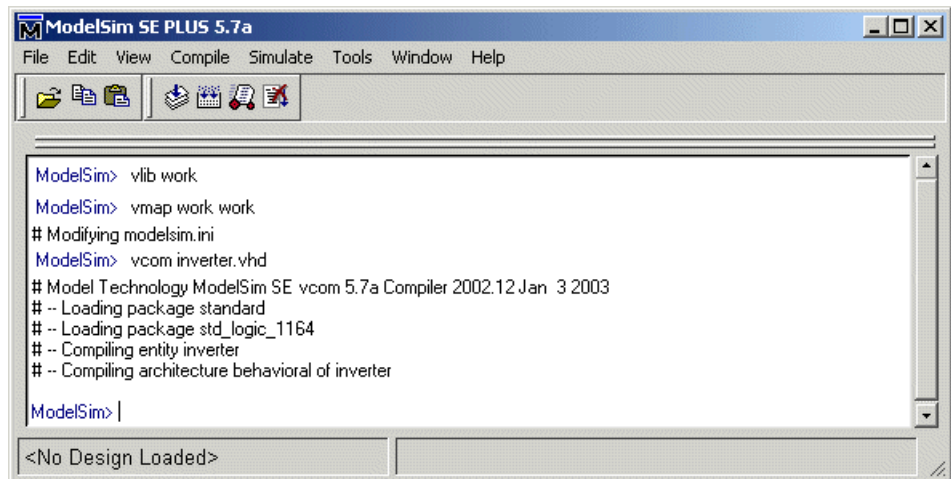
**Note** You must use the ModelSim **File** menu or `vlib` command to create the library directory to ensure that the required `_info` file is created. Do not create the library with operating system commands.

---

- 3** Compile the VHDL file. One way of compiling the file is to click the file name in the project workspace and select **Compile > Compile All**. Another alternative is to specify the name of the VHDL file with the `vcom` command, as follows:

```
ModelSim> vcom inverter.vhd
```

If the compilations succeed, informational messages appear in the command window and the compiler populates the work library with the compilation results.



Instead of compiling manually, you may choose to use the `invertercmds.m` file. See “Using the `invertercmds.m` File” on page 4-46.

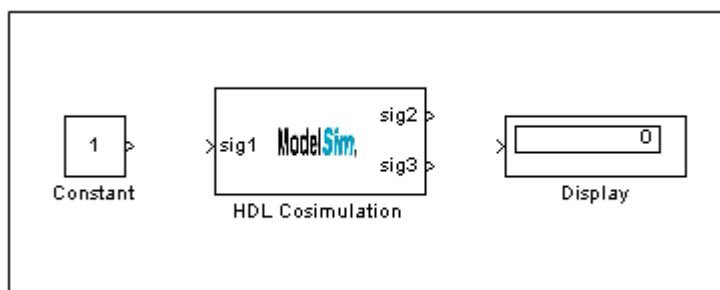
### Creating the Simulink Model

Now create your Simulink model. For this tutorial, you create a simple Simulink model that drives input into a block representing the VHDL inverter you coded in “Developing the VHDL Code” on page 4-47 and displays the inverted output.

Start by creating a model, as follows:

- 1 Start MATLAB, if it is not already running. Open a new model window. Then, open the Simulink Library Browser.
- 2 Drag the following blocks from the Simulink Library Browser to your model window:
  - Constant block from the Simulink Source library
  - HDL Cosimulation block from the EDA Simulator Link MQ block library
  - Display block from the Simulink Sink library

Arrange the three blocks in the order shown in the following figure.

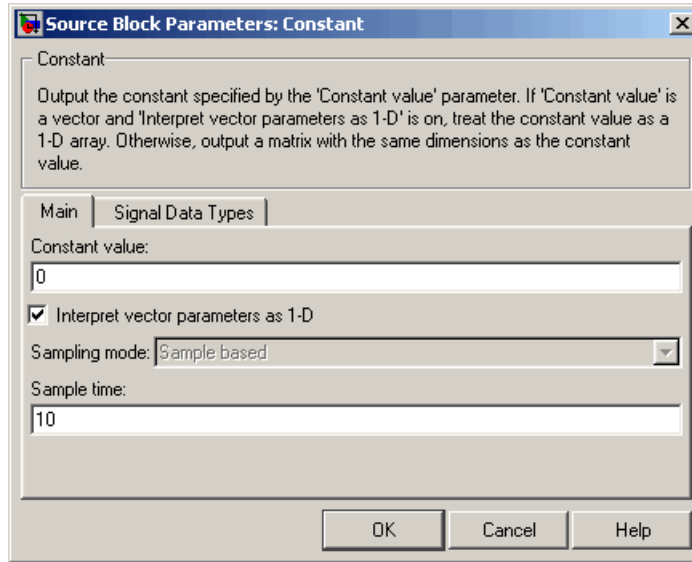


Next, configure the Constant block, which is the model’s input source, by performing the following actions:

- 1 Double-click the Constant block icon to open the Constant block parameters dialog box. Enter the following parameter values in the **Main** pane:
  - **Constant value:** 0
  - **Sample time:** 10

Later you can change these initial values to see the effect various sample times have on different simulation runs.

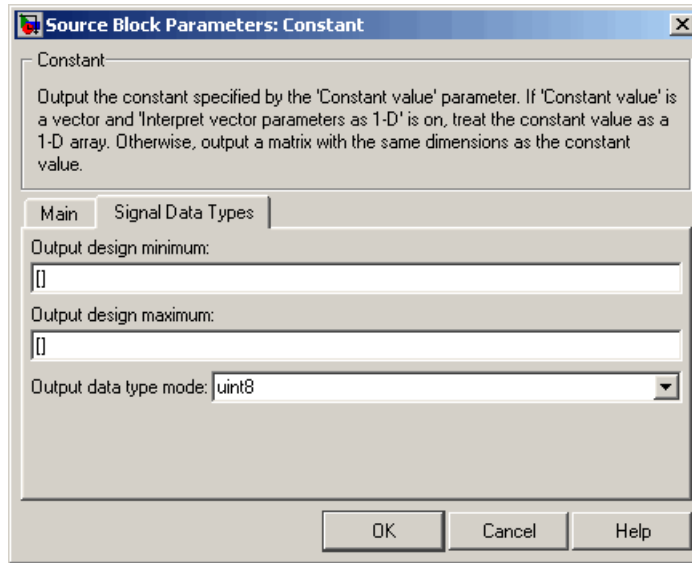
The dialog box should now appear as follows.



- 2 Click the **Signal data types** tab. The dialog box now displays the **Output data type mode** menu.

Select `uint8` from the **Output data type mode** menu. This data type specification is supported by EDA Simulator Link MQ software without the need for a type conversion. It maps directly to the VHDL type for the VHDL port `sin`, `STD_LOGIC_VECTOR(7 DOWNTO 0)`.

The dialog box should now appear as follows.



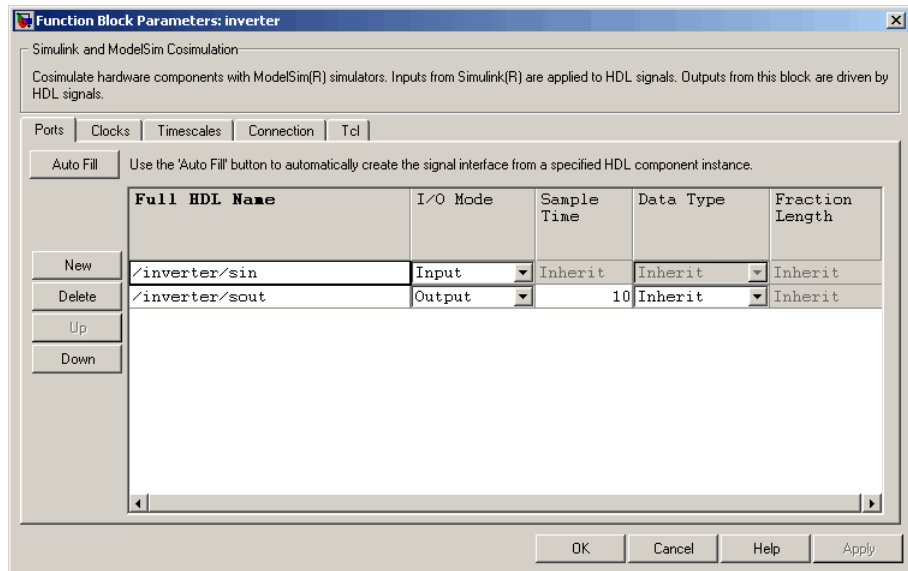
- 3 Click **OK**. The Constant block parameters dialog box closes and the value in the Constant block icon changes to 0.

Next, configure the HDL Cosimulation block, which represents the inverter model written in VHDL. Start with the **Ports** pane, by performing the following actions:

- 1 Double-click the HDL Cosimulation block icon. The Block Parameters dialog box for the HDL Cosimulation block appears. Click the **Ports** tab.
- 2 In the **Ports** pane, select the sample signal `/top/sig1` from the signal list in the center of the pane by double-clicking on it.
- 3 Replace the sample signal path name `/top/sig1` with `/inverter/sin`. Then click **Apply**. The signal name on the HDL Cosimulation block changes.
- 4 Similarly, select the sample signal `/top/sig2`. Change the **Full HDL Name** to `/inverter/sout`. Select Output from the **I/O Mode** list. Change the **Sample Time** parameter to 10. Then click **Apply** to update the list.

- 5 Select the sample signal `/top/sig3`. Click the **Delete** button. The signal is now removed from the list.

The **Ports** pane should appear as follows.



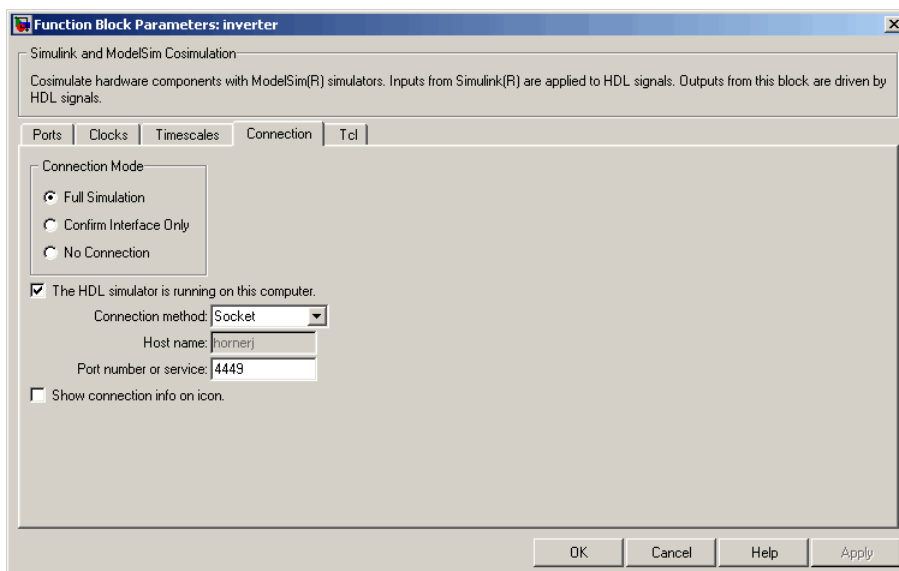
Now configure the parameters of the **Connection** pane by performing the following actions:

- 1 Click the **Connection** tab.
- 2 Leave **Connection Mode** as **Full Simulation**.
- 3 Select socket from the **Connection method** list. This option specifies that Simulink and ModelSim will communicate via a designated TCP/IP socket port. Observe that two additional fields, **Port number or service** and **Host name**, are now visible.

Note that, because the **The HDL simulator is running on this computer option** is selected by default, the **Host name** field is disabled. In this configuration, both Simulink and ModelSim execute on the same computer, so you do not need to enter a remote host system name.

- 4 In the **Port number or service** text box, enter socket port number 4449 or, if this port is not available on your system, another valid port number or service name. The model will use TCP/IP socket communication to link with ModelSim. Note what you enter for this parameter. You will specify the same socket port information when you set up ModelSim for linking with Simulink.

The **Connection** pane should appear as follows.

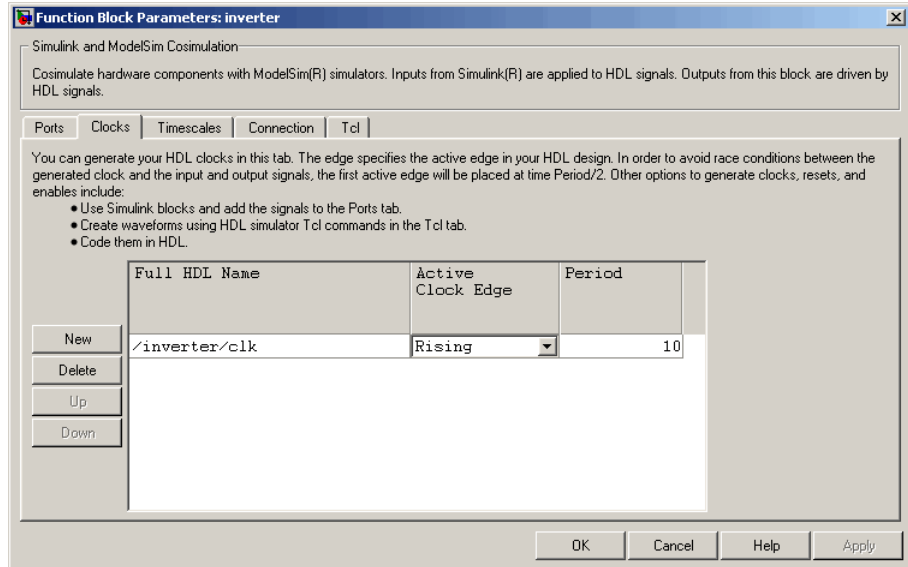


- 5 Click **Apply**.

Now configure the **Clocks** pane by performing the following actions:

- 1 Click the **Clocks** tab.
- 2 Click the **New** button. A new clock signal with an empty signal name is added to the signal list.
- 3 Double-click on the new signal name to edit. Enter the signal path `/inverter/clock`. Then select **Rising** from the **Edge** list. Set the **Period** parameter to 10.

**4** The **Clocks** pane should appear as follows.



**5** Click **Apply**.

Next, enter some simple Tcl commands to be executed before and after simulation, as follows:

**1** Click the **Tcl** tab.

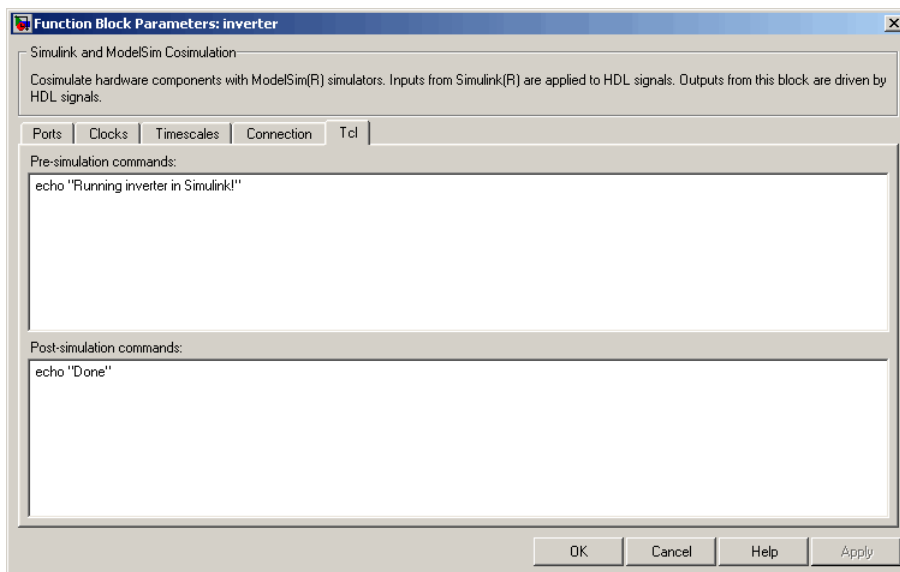
**2** In the **Pre-simulation commands** text box, enter the following Tcl command:

```
echo "Running inverter in Simulink!"
```

**3** In the **Post-simulation commands** text box, enter

```
echo "Done"
```

The **Tcl** pane should appear as follows.

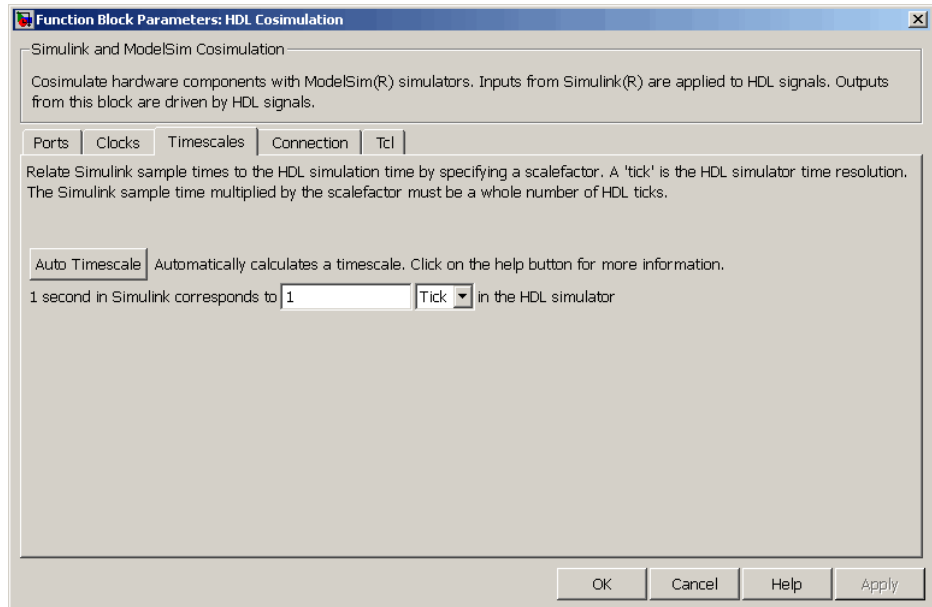


### 4 Click **Apply**.

Next, view the **Timescales** pane to make sure it is set to its default parameters, as follows:

- 1 Click the **Timescales** tab.
- 2 The default settings of the **Timescales** pane are shown in the following figure. These settings are required for correct operation of this example. See “Understanding the Representation of Simulation Time” on page 8-15 for further information.

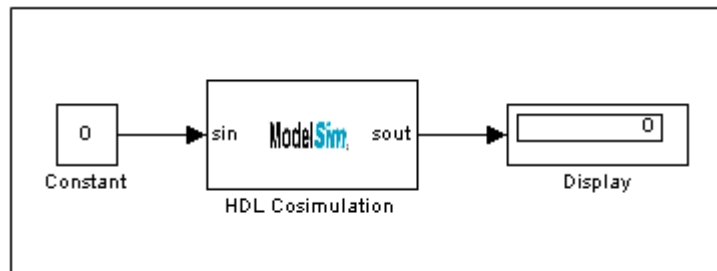




**3** Click **OK** to close the Function Block Parameters dialog box.

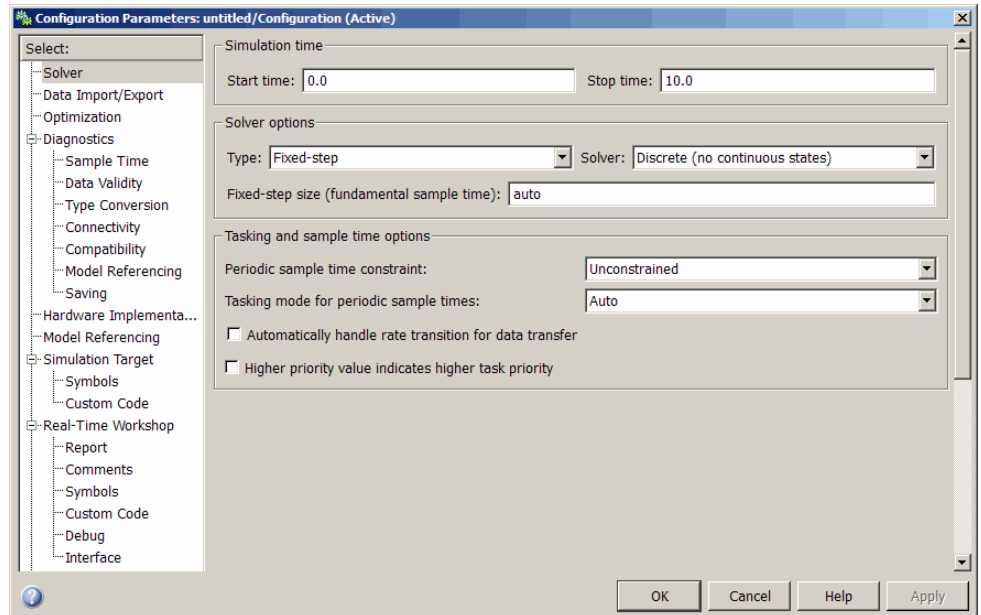
The final step is to connect the blocks, configure model-wide parameters, and save the model. Perform the following actions:

**1** Connect the blocks as shown in the following figure.



At this point, you might also want to consider adjusting block annotations.

- 2 Configure the Simulink solver options for a fixed-step, discrete simulation; this is required for correct cosimulation operation. Perform the following actions:
  - a Select **Configuration Parameters** from the **Simulation** menu in the model window. The Configuration Parameters dialog box opens, displaying the **Solver options** pane.
  - b Select **Fixed-step** from the **Type** menu.
  - c Select **Discrete (no continuous states)** from the **Solver** menu.
  - d Click **Apply**. The **Solver options** pane should appear as shown in the following figure.



- e Click **OK** to close the Configuration Parameters dialog box.

See “Setting Simulink Software Configuration Parameters” on page 4-42 for further information on Simulink settings that are optimal for use with EDA Simulator Link MQ software.

- 3 Save the model.

## Setting Up ModelSim for Use with Simulink

You now have a VHDL representation of an inverter and a Simulink model that applies the inverter. To start ModelSim such that it is ready for use with Simulink, enter the following command line in the MATLAB Command Window:

```
vsim('socketsimulink', 4449)
```

---

**Note** If you entered a different socket port specification when you configured the HDL Cosimulation block in Simulink, replace the port number 4449 in the preceding command line with the correct socket port information for your model. The `vsim` function informs ModelSim of the TCP/IP socket to use for establishing a communication link with your Simulink model.

---

To launch ModelSim, you may choose instead to use the `invertercmds.m` file. See “Using the `invertercmds.m` File” on page 4-46.

## Loading Instances of the VHDL Entity for Cosimulation with Simulink

This section explains how to use the `vsimulink` command to load an instance of your VHDL entity for cosimulation with Simulink. The `vsimulink` command is an EDA Simulator Link MQ variant of the ModelSim `vsim` command. It is made available as part of the ModelSim configuration.

To load an instance of the `inverter` entity, perform the following actions:

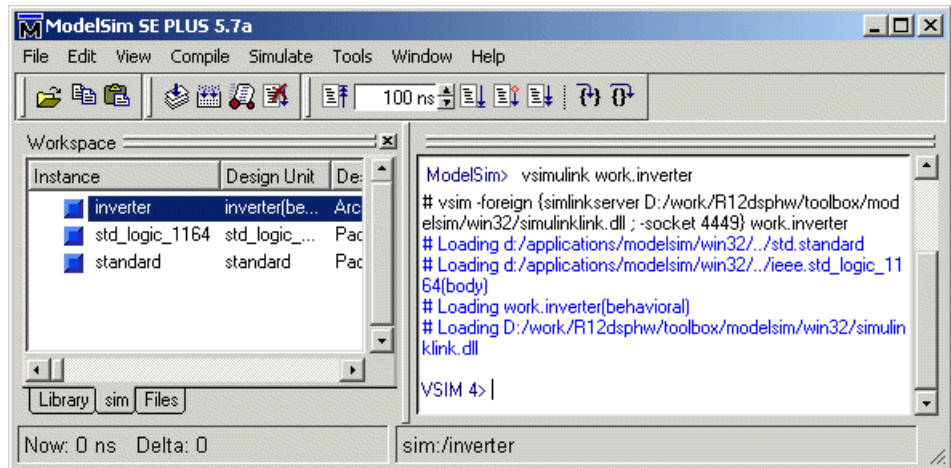
- 1 Change your input focus to the ModelSim window.
- 2 If necessary, change your directory to the location of your `inverter.vhd` file. For example:

```
ModelSim> cd C:/MyPlayArea
```

- 3 Enter the following `vsimulink` command:

```
ModelSim> vsimulink work.inverter
```

ModelSim starts the vsim simulator such that it is ready to simulate entity `inverter` in the context of your Simulink model. The ModelSim command window display should be similar to the following.



Instead of loading the entity manually, you may choose to use the `invertercmds.m` file. See “Using the `invertercmds.m` File” on page 4-46.

### Running the Simulation

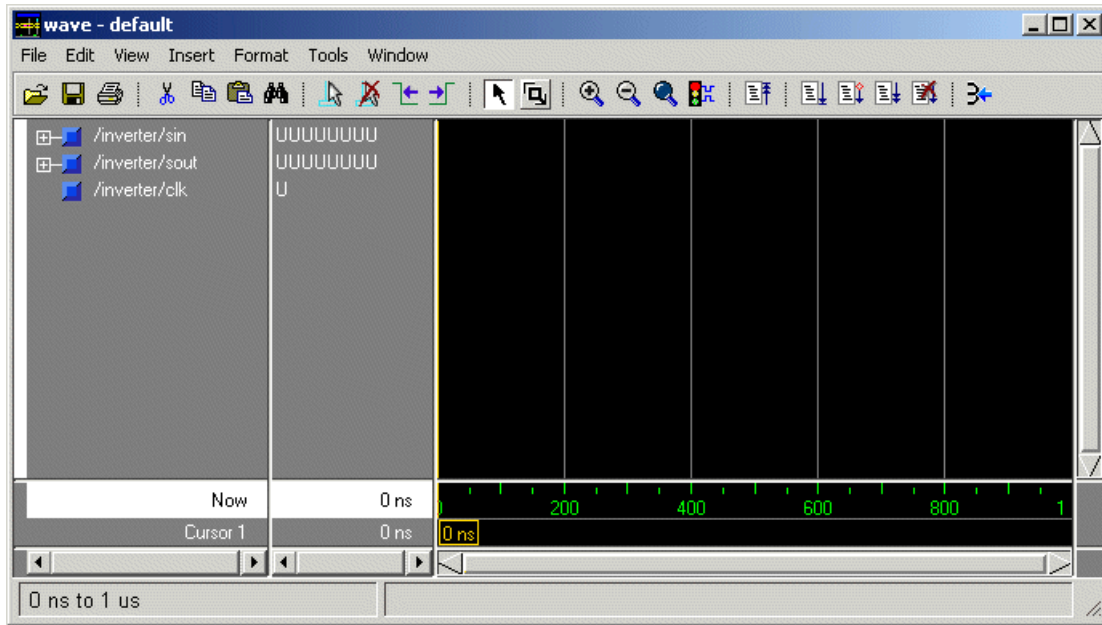
This section guides you through a scenario of running and monitoring a cosimulation session.

Perform the following actions:

- 1 Open and add the inverter signals to a **wave** window by entering the following ModelSim command:

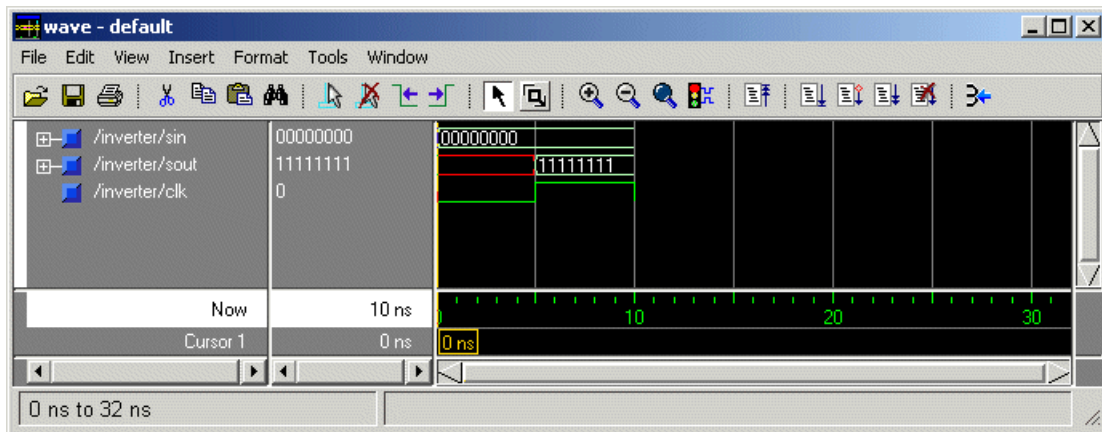
```
VSIM n> add wave /inverter/*
```

The following **wave** window appears.

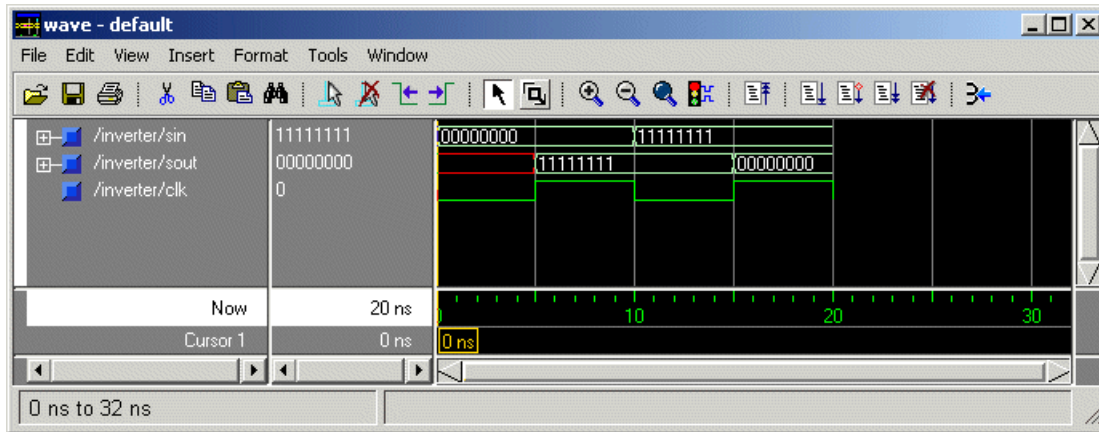


**2** Change your input focus to your Simulink model window.

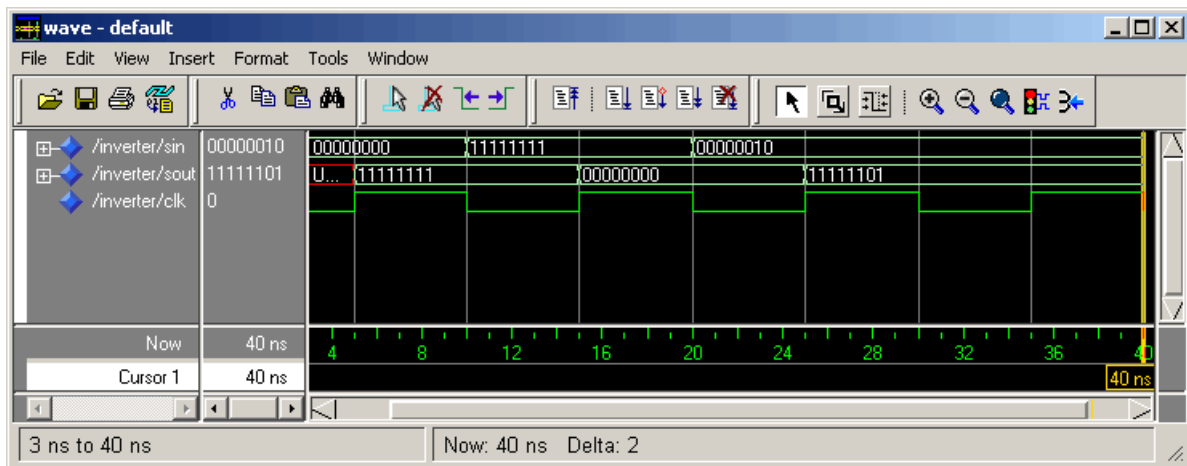
**3** Start a Simulink simulation. The value in the Display block changes to 255. Also note the changes that occur in the ModelSim **wave** window. You might need to zoom in to get a better view of the signal data.



- 4 In the Simulink model, change **Constant value** to 255, save the model, and start another simulation. The value in the Display block changes to 0 and the ModelSim **wave** window is updated as follows.



- 5 In the Simulink Model, change **Constant value** to 2 and **Simulation time** to 20 and start another simulation. This time, the value in the Display block changes to 253 and the ModelSim **wave** window appears as shown in the following figure.



Note the change in the sample time in the **wave** window.

## Shutting Down the Simulation

This section explains how to shut down a simulation in an orderly way, as follows:

- 1** In ModelSim, stop the simulation by selecting **Simulate > End Simulation**.
- 2** Quit ModelSim.
- 3** Close the Simulink model window.





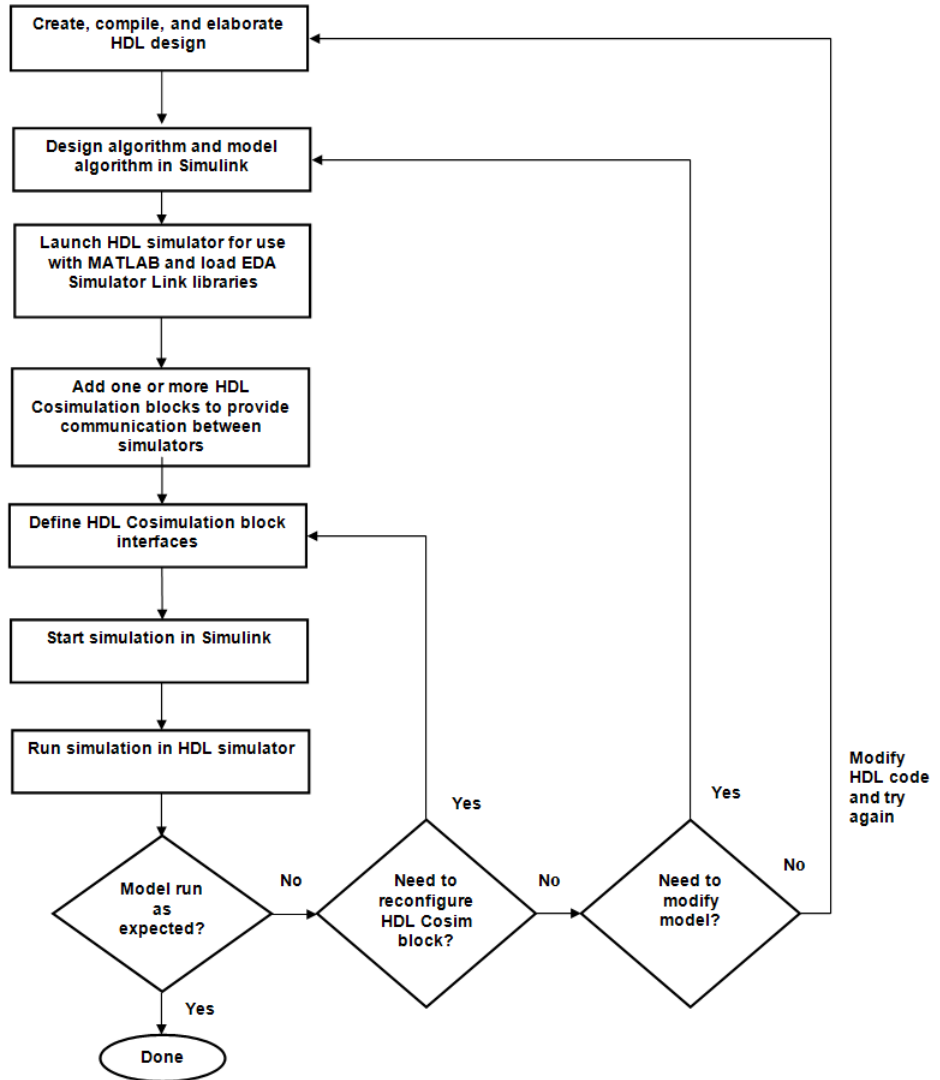
# Replacing an HDL Component with a Simulink Algorithm

---

- “Workflow for Using Simulink as HDL Component” on page 5-2
- “Overview to Component Simulation with Simulink” on page 5-4
- “Code an HDL Component for Use with Simulink Applications” on page 5-7
- “Create Simulink Model for Component Cosimulation with the HDL Simulator” on page 5-8
- “Launch HDL Simulator for Component Cosimulation with Simulink” on page 5-9
- “Add the HDL Cosimulation Block to the Simulink Component Model” on page 5-10
- “Define the HDL Cosimulation Block Interface” on page 5-11
- “Start the Simulation in Simulink” on page 5-12
- “Run a Component Cosimulation Session” on page 5-13

## Workflow for Using Simulink as HDL Component

The following workflow shows the steps necessary to cosimulate an HDL design that Simulink software



The workflow is as follows:

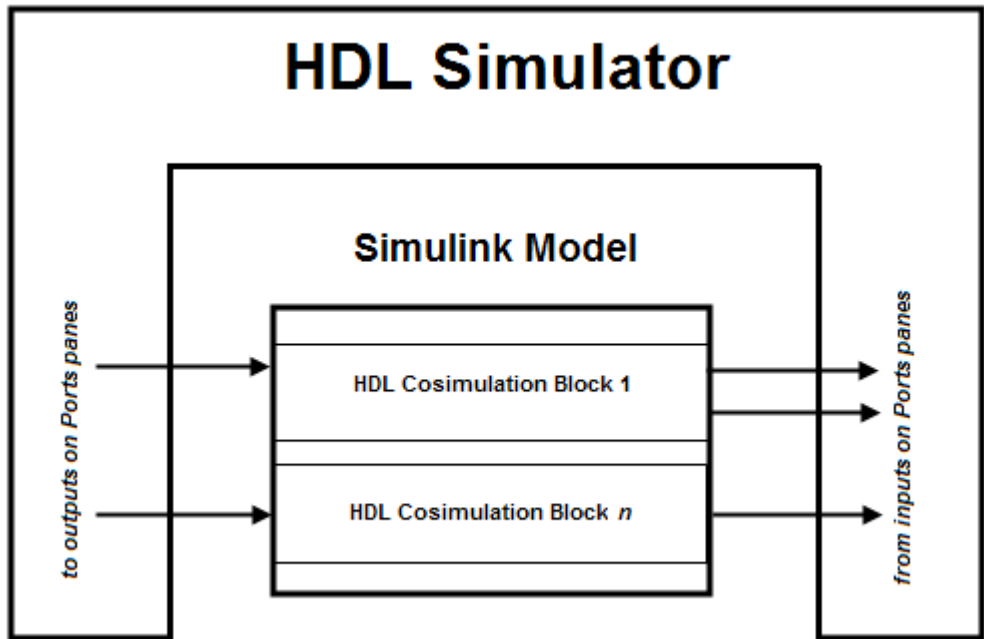
- Create, compile, and elaborate HDL design.
- Design algorithm and model algorithm in Simulink.
- Launch HDL simulator for use with MATLAB and load EDA Simulator Link MQ libraries.
- Add one or more HDL Cosimulation blocks to provide communication between simulators.
- Define HDL Cosimulation block interfaces.
- Start simulation in Simulink.
- Run cosimulation in HDL simulator.

## Overview to Component Simulation with Simulink

In this section...
“How the HDL Simulator and Simulink Software Communicate Using EDA Simulator Link MQ” on page 5-4
“Creating the HDL Module” on page 5-5
“Introduction to the EDA Simulator Link MQ HDL Cosimulation Block (Simulink as Component)” on page 5-6

### How the HDL Simulator and Simulink Software Communicate Using EDA Simulator Link MQ

When you link the HDL simulator with a Simulink application, the simulator functions as the server. As the following diagram shows, the HDL Cosimulation blocks inside the Simulink model accept signals from the HDL module under simulation in the HDL simulator via the output ports on the Ports panes and return data via the input ports on the Ports panes.




---

**Note** The programming and interfacing conventions for using Simulink as a test bench functions (see Chapter 4, “Simulating an HDL Component in a Simulink Test Bench Environment”) and Simulink as a component are essentially the same; therefore, steps in the component workflow map to documentation for steps in the test bench workflow.

---

## Creating the HDL Module

When you code an HDL module that will use Simulink to visualize a particular component, you should consider the types of data to be shared between the two environments and the direction modes.

### Specifying Port Direction Modes in the HDL Module

In your module statement, you must specify each port with a direction mode (input, output, or bidirectional). See “Specifying Port Direction Modes in

HDL Components (MATLAB as Test Bench)” on page 2-8 for descriptions of these port directions.

### **Specifying Port Data Types in the HDL Module**

You must specify data types compatible with Simulink for ports in your HDL modules. See “Specifying Port Data Types in HDL Components (MATLAB as Test Bench)” on page 2-8 for descriptions of supported port data types. For details on how the EDA Simulator Link MQ interface converts data types for the MATLAB and Simulink environments, see “Performing Data Type Conversions” on page 8-5.

### **Introduction to the EDA Simulator Link MQ HDL Cosimulation Block (Simulink as Component)**

The EDA Simulator Link MQ HDL Cosimulation Block links hardware components that are concurrently simulating in the HDL simulator to the rest of a Simulink model.

You can link Simulink and the HDL simulator by using one or more HDL Cosimulation blocks fitted into the framework of a larger Simulink model posing as an HDL component.

For details, see “Add the HDL Cosimulation Block to the Simulink Test Bench Model” on page 4-13.

## **Code an HDL Component for Use with Simulink Applications**

The most basic element of communication in the EDA Simulator Link MQ interface is the HDL module. The interface passes all data between the HDL simulator and Simulink as port data. The EDA Simulator Link MQ software works with any existing HDL module. However, when you code an HDL module that is targeted for Simulink verification, you should consider the types of data to be shared between the two environments and the direction modes. These factors are also ones you need to consider when you code an HDL module for use with Simulink as a component. For details, see “Code an HDL Component for Use with Simulink Test Bench Applications” on page 4-11.

### **Create Simulink Model for Component Cosimulation with the HDL Simulator**

For the most part, there is nothing different about creating a Simulink model to act as an HDL component than there is from creating a Simulink model to use as a test bench. When using Simulink as a component, you may have multiple HDL Cosimulation blocks rather than a single HDL Cosimulation block, though there's no limitation on how many HDL Cosimulation blocks you may use in either situation. For more on how the HDL simulator and Simulink communicate, see "How the HDL Simulator and Simulink Software Communicate Using EDA Simulator Link MQ" on page 5-4.

For more about creating a Simulink model for use in cosimulation with EDA Simulator Link MQ, see "Create a Simulink Model for Test Bench Cosimulation with the HDL Simulator" on page 4-10.



## Launch HDL Simulator for Component Cosimulation with Simulink

In order to be able to take advantage of some of the automatic field population on the HDL Cosimulation block, you must first launch the HDL simulator and have it ready with the EDA Simulator Link MQ libraries loaded and the HDL module loaded and ready to run.

See

- “Starting the HDL Simulator from MATLAB” on page 4-12
- “Loading an Instance of an HDL Module for Cosimulation” on page 4-12

## **Add the HDL Cosimulation Block to the Simulink Component Model**

For instructions on adding the HDL Cosimulation block from the Simulink Library Browser, see “Add the HDL Cosimulation Block to the Simulink Test Bench Model” on page 4-13. You may also want to refer to the HDL CosimulationHDL CosimulationHDL Cosimulation block reference.

## Define the HDL Cosimulation Block Interface

Define input and output ports, clocks, communication settings, and set the timing relationship. See “Define the HDL Cosimulation Block Interface (Simulink as Test Bench)” on page 4-14.

### **Start the Simulation in Simulink**

Set Simulink configuration parameters, check connection, and start and stop the cosimulation. See “Run a Test Bench Cosimulation Session (Simulink as Test Bench)” on page 4-42.

## Run a Component Cosimulation Session

Start the simulation running in the HDL simulator. Observe and control simulation behavior in Simulink. See “Start the Simulation in Simulink” on page 5-12.



# Recording Simulink Signal State Transitions for Post-Processing

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- “Adding a Value Change Dump (VCD) File” on page 6-2
- “To VCD File Block Tutorial” on page 6-6

## Adding a Value Change Dump (VCD) File

A value change dump (VCD) file logs changes to variable values, such as the values of signals, in a file during a simulation session. VCD files can be useful during design verification. Some examples of how you might apply VCD files include the following cases:

- For comparing results of multiple simulation runs, using the same or different simulator environments
- As input to post-simulation analysis tools
- For porting areas of an existing design to a new design

VCD files can provide data that you might not otherwise acquire unless you understood the details of a device's internal logic. In addition, they include data that can be graphically displayed or analyzed with postprocessing tools.

For example, the ModelSim `vcd2wlf` tool converts a VCD file to a Wave Log Format (WLF) file that you can view in a ModelSim **wave** window. Other examples of postprocessing include the extraction of data about a particular section of a design hierarchy or data generated during a specific time interval.

The To VCD File block provided in the EDA Simulator Link MQ block library serves as a VCD file generator during Simulink sessions. The block generates a VCD file that contains information about changes to signals connected to the block's input ports and names the file with a specified file name.

---

**Note** The To VCD File block logs changes to states '1' and '0' only. The block does *not* log changes to states 'X' and 'Z'.

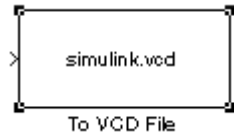
---

To generate a VCD file, perform the following steps:

- 1** Open your Simulink model, if it is not already open.
- 2** Identify where you want to add the To VCD File block. For example, you might temporarily replace a scope with this block.



- 3 In the Simulink Library Browser, click the EDA Simulator Link MQ block library.



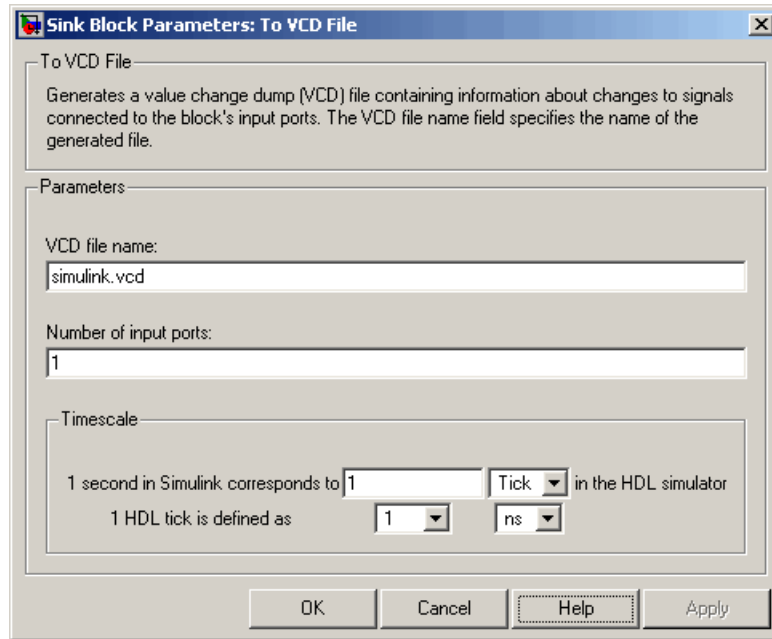
- 4 Copy the To VCD File block from the Library Browser to your model by clicking the block and dragging it from the browser to your model window.
- 5 Connect the block ports to appropriate blocks in your Simulink model.

---

**Note** Because multidimensional signals are not part of the VCD specification, they are flattened to a 1D vector in the file.

---

- 6 Configure the To VCD File block by specifying values for parameters in the Block Parameters dialog box, as follows:
  - a Double-click the block icon. Simulink displays the following dialog box.



- b** Specify a file name for the generated VCD file in the **VCD file name** text box.
- If you specify a file name only, Simulink places the file in your current MATLAB directory.
  - Specify a complete path name to place the generated file in a different location.
  - If you want the generated file to have a .vcd file type extension, you must specify it explicitly.

---

**Note** Do not give the same file name to different VCD blocks. Doing so results in invalid VCD files.

---

- c** Specify an integer in the **Number of input ports** text box that indicates the number of block input ports on which signal data is to be collected. The block can handle up to  $94^3$  (830,584) signals, each of which maps to a unique symbol in the VCD file.

- d** Click **OK**.
- 7** Choose a timing relationship between Simulink and the HDL simulator. The time scale options specify a correspondence between one second of Simulink time and some quantity of HDL simulator time. Choose relative time or absolute time. For more on the To VCD File time scale, see the reference documentation for the To VCD File block.
- 8** Run the simulation. Simulink captures the simulation data in the VCD file as the simulation runs.

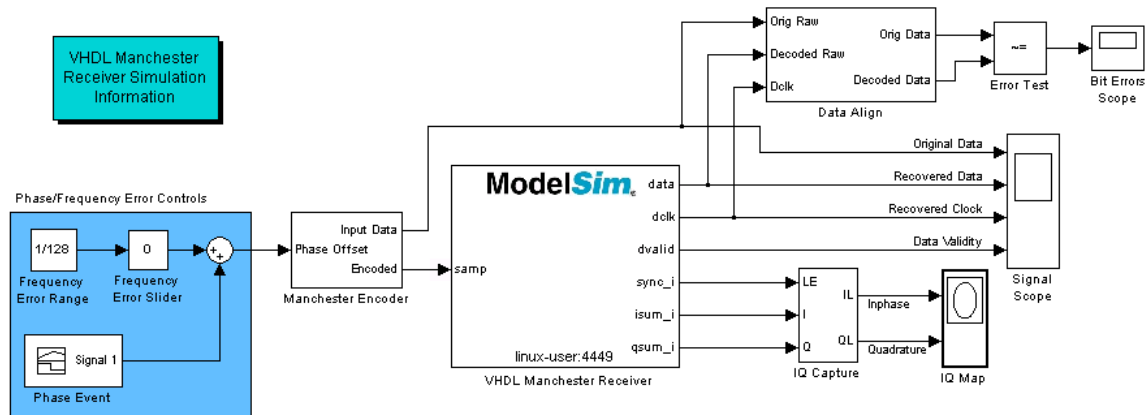
For a description of the VCD file format see “VCD File Format” on page 12-29.

For a sample application of a VCD file, see “To VCD File Block Tutorial” on page 6-6.

## To VCD File Block Tutorial

VCD files include data that can be graphically displayed or analyzed with postprocessing tools. An example of such a tool is the ModelSim `vcd2wlf` tool, which converts a VCD file to a WLF file that you can then view in a ModelSim **wave** window. This section shows how you might apply the `vcd2wlf` tool, as follows:

- 1** Place a copy of the Manchester Receiver Simulink demo `manchestermode1.mdl` in a writable directory.
- 2** Open your writable copy of the Manchester Receiver model. For example, select **File > Open**, select the file `manchestermode1.mdl` and click **Open**. The Simulink model should appear as follows.



Before running this model you must first launch ModelSim.  
You can launch ModelSim on this computer using either a shared memory link or a TCP/IP socket link.

#### Shared memory link:

- 1) Be sure that the 'Connection' tab of the Cosimulation block dialog is set as follows:  
     'ModelSim running on this computer' is checked  
     and 'Shared memory' is selected
- 2) Execute the following MATLAB command:  
     vsim('tclstart',manchestercmds)
- 3) Start the Simulink simulation.

```
vsim('tclstart',manchestercmds)
%Double-click here to launch a new ModelSim
```

ModelSim Startup Command(Shared Memory)

#### TCP/IP socket link:

- 1) Be sure that the 'Connection' tab of the Cosimulation block dialog is set as follows:  
     'ModelSim running on this computer' is checked  
     and 'Socket' is selected  
     'Port number or service' matches the port number used  
     in the command below.
- 2) Execute the following MATLAB command:  
     vsim('tclstart',manchestercmds,'socketsimulink',4442)
- 3) Start the Simulink simulation.

```
vsim('tclstart',manchestercmds,'socketsimulink',4442)
%Double-click here to launch a new ModelSim
```

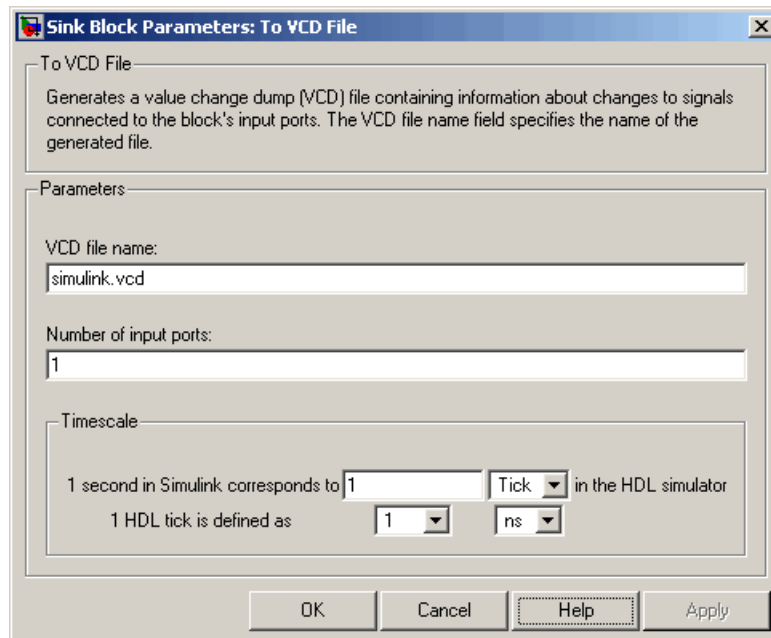
ModelSim Startup Command(TCP/IP Socket)

**3** Open the Library Browser.

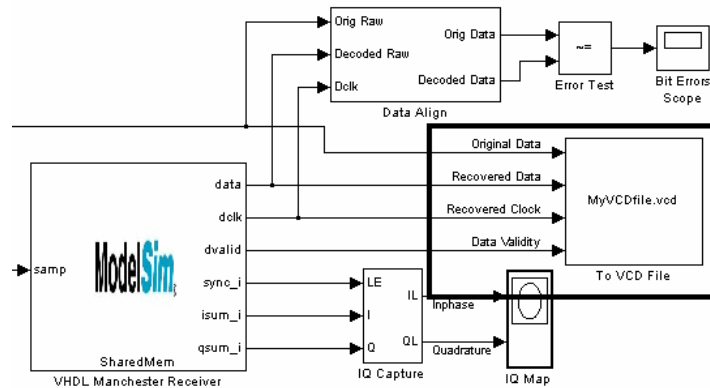
**4** Replace the Signal Scope block with a To VCD File block, as follows:

- a Delete the Signal Scope block. The lines representing the signal connections to that block change to red dashed lines, indicating the disconnection.
- b Find and open the EDA Simulator Link MQ block library.

- c Copy the To VCD File block from the Library Browser to the model by clicking the block and dragging it from the browser to the location in your model window previously occupied by the Signal Scope block.
- d Double-click the To VCD File block icon. The Block Parameters dialog box appears.



- e Type `MyVCDfile.vcd` in the **VCD file name** text box.
  - f Type 4 in the **Number of input ports** text box.
  - g Click **OK**. Simulink applies the new parameters to the block.
- 5 Connect the signals `Original Data`, `Recovered Data`, `Recovered Clock`, and `Data Validity` to the block ports. The following display highlights the modified area of the model.



6 Save the model.

7 Select the following command line from the instructional text that appears in the demonstration model:

```
vsim('tclstart',manchestercmds,'socketsimulink',4442)
```

8 Paste the command in the MATLAB Command Window and execute the command line. This command starts ModelSim and configures it for a Simulink cosimulation session.

---

**Note** You might need to adjust the TCP/IP socket port. The port you specify in the `vsim` command must match the value specified for the HDL Cosimulation block. To check the port setting for that block, double-click the block icon and then select the **Connection** tab in the Block Parameters dialog box.

---

9 Start the simulation from the Simulink model window.

10 When the simulation is complete, locate, open, and browse through the generated VCD file, `MyVCDfile.vcd`.

11 Close the VCD file.

12 Change your input focus to ModelSim and end the simulation.

- 13** Change the current directory to the directory containing the VCD file and enter the following command at the ModelSim command prompt:

```
vcd2wlf MyVCDfile.vcd MyVCDfile.wlf
```

The `vcd2wlf` utility converts the VCD file to a WLF file that you display with the command `vsim -view`.


- 14** In ModelSim, open the wave file `MyVCDfile.wlf` as data set `MyVCDwlf` by entering the following command:

```
vsim -view MyVCDfile.wlf
```

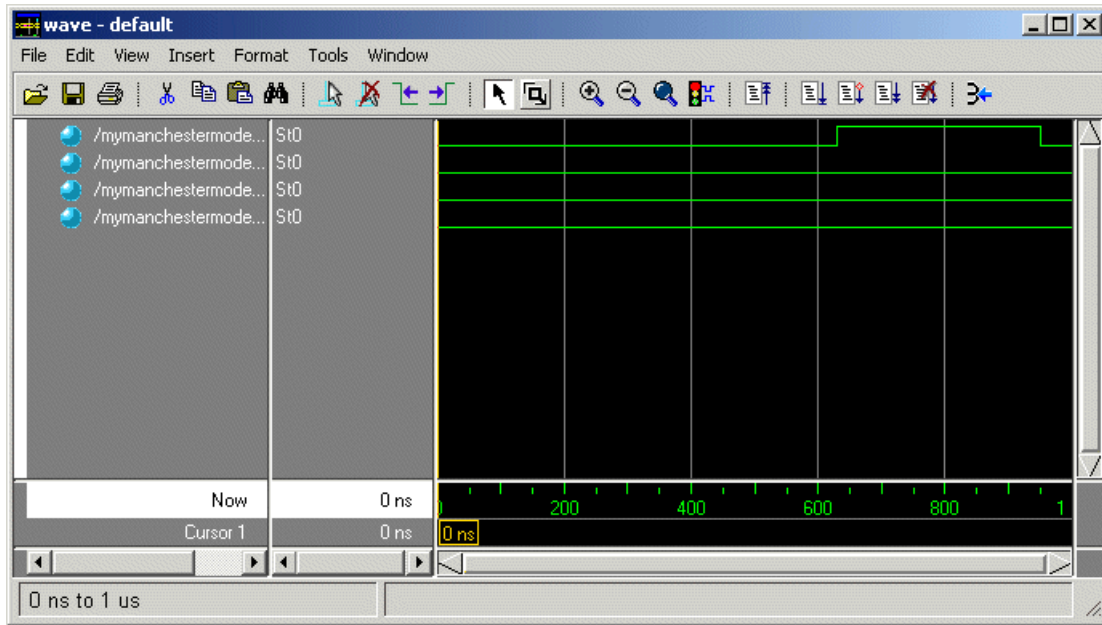
- 15** Open the `MyVCDwlf` data set with the following command:

```
add wave MyVCDfile:/*
```

A **wave** window appears showing the signals logged in the VCD file.

- 16** Click the Zoom Full button  to view the signal data. The **wave** window should appear as follows.





**17** Exit the simulation. One way of exiting is to enter the following command:

```
dataset close MyVCDfile
```

ModelSim closes the data set, clears the **wave** window, and exits the simulation.

For more information on the `vcd2w1f` utility and working with data sets, see the ModelSim documentation.



# Additional Deployment Options

---

- “Adding ADMS Support” on page 7-2
- “Performing Cross-Network Cosimulation” on page 7-5
- “Establishing EDA Simulator Link MQ Machine Configuration Requirements” on page 7-10
- “Specifying TCP/IP Socket Communication” on page 7-13
- “Improving Simulation Speed” on page 7-17

## Adding ADMS Support

In this section...
“Adding Libraries for ADMS Support” on page 7-2
“Linking MATLAB or Simulink Software to ModelSim in ADMS” on page 7-2

### Adding Libraries for ADMS Support

You do not need a special library installation for ADMS support.

If you must add system libraries to the LD\_LIBRARY\_PATH you can add them in a .vams\_setup file. Doing it this way (rather than specifying the path before calling vasm) prevents vasm from overwriting the path addition each time it starts.

This example appends the system shared libraries to LD\_LIBRARY\_PATH:

```
proc fixldpath {args} {
    set pvpair [split [join $args]]
    set pval [lindex $pvpair 1]
    append newpval /directory/of/system/dlls ":" $pval
    append setcmd { array set env [list LD_LIBRARY_PATH ] " " $newpval " " }
    uplevel 1 $setcmd
}

fixldpath [array get env LD_LIBRARY_PATH]
```

### Linking MATLAB or Simulink Software to ModelSim in ADMS

- “Starting ADMS for Use with EDA Simulator Link MQ” on page 7-3
- “Using Tcl Test Bench Commands with ADMS” on page 7-3
- “Constraints” on page 7-4

## Starting ADMS for Use with EDA Simulator Link MQ

Call `vasim` with all parameters manually; the configuration script available for Discovery™ simulators is not available for ADMS.

When you call `vasim`, provide the `-ms` and `-foreign` parameters. For example,

```
vasim -lib ADC12_ELDO_MS -cmd
      /devel/user/work/ams/adc12test.cmd TEST -ms -foreign matlabclient path/matlablibrary
```

where:

<code>-lib ADC12_ELDO_MS</code>	is the model library
<code>/devel/user/work/ams/adc12test.cmd</code>	is the command file
<code>TEST</code>	is the design
<code>path/matlablibrary</code>	is the path to and the name of the MATLAB shared library (see “Using the EDA Simulator Link MQ Libraries” on page 1-17)

A similar example for the Simulink link looks like the following code:

```
vasim -lib ADC12_ELDO_MS -cmd
      /devel/user/work/ams/adc12test.cmd TEST -ms
      -foreign simlinkserver path/simlinklibrary
```

This command sends all line arguments after `"ms"` to the ModelSim process.

See your ModelSim documentation for more about the `-foreign` option.

## Using Tcl Test Bench Commands with ADMS

When you use any of the EDA Simulator Link MQ HDL simulator command extensions (for example, `matlabcp` or `matlabtb`), precede each command with `ms` in the ADMS Tcl interpreter. For example:

```
ms matlabtb myfirfilter 5 ns -repeat 10 ns -socket 4449
```

This command sends all line arguments after 'ms' to the ModelSim process.

### Constraints

**Setting Simulation Running Time.** When running cosimulation sessions in Simulink, make sure that the runtime of the ADMS simulation is greater than or equal to the Simulink runtime.

### Solaris Support.

- EDA Simulator Link MQ supports ADMS on Solaris 8, 9, 10 32-bits but does not support ADMS on Solaris 64-bit.
- glibc errors on glnxa64 when running a cosimulation session with ADMS

If you get the following:

```
*** glibc detected *** free(): invalid pointer: 0x000000001eeb490 ***
```

Then enter the following command:

```
setenv MALLOC_CHECK_ 0
```

Which says, effectively, "Do not generate an error message, and do not kill the program".

## Performing Cross-Network Cosimulation

### In this section...

“Introduction to Cross-Network Cosimulation” on page 7-5

“Before Cross-Network Cosimulation (MATLAB or Simulink)” on page 7-5

“Performing Cross-Network Cosimulation with the HDL Simulator and MATLAB” on page 7-7

“Performing Cross-Network Cosimulation with the HDL Simulator and Simulink” on page 7-8

### Introduction to Cross-Network Cosimulation

You can perform cross-network cosimulation when your setup comprises one machine running MATLAB and Simulink software and another machine running the HDL simulator. Typically, a Windows-platform machine runs the MATLAB and Simulink software, while a Linux or Solaris machine runs the HDL simulator. However, these procedures apply to any combination of platforms that EDA Simulator Link MQ and the HDL simulator support.

### Before Cross-Network Cosimulation (MATLAB or Simulink)

Before you cosimulate between the HDL simulator and MATLAB or Simulink across a network, perform the following steps:

- 1 Go to the system where you installed MATLAB. Then, find the directory in the MATLAB distribution where the EDA Simulator Link MQ libraries reside.

You can usually find the libraries in the default installed directory:

```
matlabroot/toolbox/modelsim/platform/productlibraryname_
compiler_tag.ext
```

where the variable shown in the following table have the values indicated.

<b>Variable</b>	<b>Value</b>
matlabroot	The location where you installed the MATLAB software; default value is "MATLAB/ <i>version</i> " where <i>version</i> is the installed release (for example, R2009a).
platform	The operating system of the machine with the HDL simulator, for example, linux32. (For more information, see “Using the EDA Simulator Link MQ Libraries” on page 1-17.)
productlibraryname	The name of the library files for MATLAB and for Simulink (for example, liblfmhdle, liblfmhdls). See “Using the EDA Simulator Link MQ Libraries” on page 1-17.
compiler_tag	The compiler used to create the library (for example, gcc32 or spro). For more information, see “Using the EDA Simulator Link MQ Libraries” on page 1-17.
ext	dll (dynamic link library—Windows only) or so ( shared library extension)



For a list of all the EDA Simulator Link MQ HDL shared libraries shipped, see “Default Libraries” on page 1-18 in “Using the EDA Simulator Link MQ Libraries” on page 1-17.

- 2 From the MATLAB machine, copy the appropriate EDA Simulator Link MQ libraries (found in step 1) to the machine where you installed the HDL simulator. Make note of the location you copied the link library to. For purposes of this example, the example refers to the destination directory as "HDLSERVER\_LIB\_LOCATION".

Before you create the link between the two machines needed to run a cosimulation session, create and compile your HDL design, and create your MATLAB m-function (for MATLAB cosimulation) or Simulink model (for Simulink cosimulation).

If you now want to cosimulate with MATLAB, see “Performing Cross-Network Cosimulation with the HDL Simulator and MATLAB” on page 7-7. If you want to cosimulate with Simulink, see “Performing Cross-Network Cosimulation with the HDL Simulator and Simulink” on page 7-8.

## Performing Cross-Network Cosimulation with the HDL Simulator and MATLAB

When you want to perform an HDL-simulator-to-MATLAB cosimulation session across a network, follow these steps:

- 1 In MATLAB, get an available socket using `hdldaemon`:

```
hdldaemon('socket',0)
```

Or assign one:

```
hdldaemon('socket',4449)
```

- 2 Launch the HDL simulator with the following command:

```
vsim -foreign "matlabclient /HDLSERVER_LIB_LOCATION/library_name;  
-socket yyyy" design_name
```

where the arguments shown in the following table have the values indicated.

Argument	Value
<i>library_name</i>	The name of the library you copied to the machine with the HDL simulator (in “Before Cross-Network Cosimulation (MATLAB or Simulink)” on page 7-5).
<i>yyyy</i>	The socket number you have chosen for this connection
<i>design_name</i>	The VHDL or Verilog design you want to load

- In the HDL simulator, schedule the test bench or component (`matlabcp` or `matlabtb`). Specify the socket port number from step 1 and the name of the host where `hdldaemon` is running.

## Performing Cross-Network Cosimulation with the HDL Simulator and Simulink

When you want to perform an HDL-simulator-to-Simulink cosimulation session across a network, follow these steps:

- Launch the HDL simulator with the following command:

```
vsim -foreign "simlinkserver /HDLSERVER_LIB_LOCATION/library_name;  
-socket yyyy" design_name
```

where the arguments shown in the following table have the values indicated.

Argument	Value
<i>library_name</i>	The name of the library you copied to the machine with the HDL simulator (in “Before Cross-Network Cosimulation (MATLAB or Simulink)” on page 7-5).

<b>Argument</b>	<b>Value</b>
<i>yyyy</i>	The socket number you have chosen for this connection
<i>design_name</i>	The VHDL or Verilog design you want to load

- 2** On the machine with MATLAB and Simulink, start Simulink and open your Simulink model.
- 3** Double-click on the HDL Cosimulation block to open the Function Block Parameters dialog box.
- 4** Click on the **Connections** tab.
  - a** Clear “The HDL simulator is running on this computer.” The Connection method is automatically changed to Socket.
  - b** In the text box labeled **Host name**, enter the host name of the machine where the HDL simulator is located.
  - c** In the text box labeled **Port number or service**, enter the socket number from step 1.
  - d** Click **OK** to exit block dialog box, and save your changes.

Next, run your simulation, add more blocks, or make other desired changes.

## Establishing EDA Simulator Link MQ Machine Configuration Requirements

<b>In this section...</b>
“Valid Configurations For Using the EDA Simulator Link MQ Software with MATLAB Applications” on page 7-10
“Valid Configurations For Using the EDA Simulator Link MQ Software with Simulink Software” on page 7-11

### Valid Configurations For Using the EDA Simulator Link MQ Software with MATLAB Applications

The following list provides samples of valid configurations for using the ModelSim HDL simulator and the EDA Simulator Link MQ software with MATLAB software. The scenarios apply whether the HDL simulator is running on the same or different computing system as the MATLAB software. In a network configuration, you use an Internet address in addition to a TCP/IP socket port to identify the servers in an application environment.

- An HDL simulator session linked to a MATLAB function `foo` through a single instance of the MATLAB server
- An HDL simulator session linked to multiple MATLAB functions (for example, `foo` and `bar`) through a single instance of the MATLAB server
- An HDL simulator session linked to a MATLAB function `foo` through multiple instances of the MATLAB server (each running within the scope of a unique MATLAB session)
- Multiple HDL simulator sessions each linked to a MATLAB function `foo` through multiple instances of the MATLAB server (each running within the scope of a unique MATLAB session)
- Multiple HDL simulator sessions each linked to a different MATLAB function (for example, `foo` and `bar`) through the same instance of the MATLAB server
- Multiple HDL simulator sessions each linked to MATLAB function `foo` through a single instance of the MATLAB server

Although multiple HDL simulator sessions can link to the same MATLAB function in the same instance of the MATLAB server, as this configuration scenario suggests, such links are not recommended. If the MATLAB function maintains state (for example, maintains global or persistent variables), you may experience unexpected results because the MATLAB function does not distinguish between callers when handling input and output data. If you must apply this configuration scenario, consider deriving unique instances of the MATLAB function to handle requests for each HDL entity.

---

**Notes**

- Shared memory communication is an option for configurations that require only one communication link on a single computing system.
  - TCP/IP socket communication is required for configurations that use multiple communication links on one or more computing systems. Unique TCP/IP socket ports distinguish the communication links.
  - In any configuration, an instance of MATLAB can run only one instance of the EDA Simulator Link MQ MATLAB server (hdldaemon) at a time.
  - In a TCP/IP configuration, the MATLAB server can handle multiple client connections to one or more HDL simulator sessions.
- 

**Valid Configurations For Using the EDA Simulator Link MQ Software with Simulink Software**

The following list provides samples of valid configurations for using the ModelSim HDL simulator and the EDA Simulator Link MQ software with Simulink software. The scenarios apply whether the HDL simulator is running on the same or different computing system as the MATLAB or Simulink products. In a network configuration, you use an Internet address in addition to a TCP/IP socket port to identify the servers in an application environment.

- An HDL Cosimulation block in a Simulink model linked to a single HDL simulator session

- Multiple HDL Cosimulation blocks in a Simulink model linked to the same HDL simulator session
- An HDL Cosimulation block in a Simulink model linked to multiple HDL simulator sessions
- Multiple HDL Cosimulation blocks in a Simulink model linked to different HDL simulator sessions

---

### **Notes**

- HDL Cosimulation blocks in a Simulink model can connect to the same or different HDL simulator sessions.
  - TCP/IP socket communication is required for configurations that use multiple communication links on one or more computing systems. Unique TCP/IP socket ports distinguish the communication links.
  - Shared memory communication is an option for configurations that require only one communication link on a single computing system.
-

## Specifying TCP/IP Socket Communication

### In this section...

“Choosing TCP/IP Socket Ports” on page 7-13

“Specifying TCP/IP Values” on page 7-15

“TCP/IP Services” on page 7-16

### Choosing TCP/IP Socket Ports

Depending on your particular configuration (for example, when the MATLAB software and the HDL simulator reside on separate machines), when creating an EDA Simulator Link MQ MATLAB application or defining the block parameters of an HDL Cosimulation block, you may need to identify the TCP/IP socket port number or service name (alias) to be used for EDA Simulator Link MQ connections.

To use the TCP/IP socket communication, you must choose a TCP/IP socket port number for the server component to listen on that is available in your computing environment. Client components can connect to a specific server by specifying the port number on which the server is listening. For remote network configurations, the Internet address helps distinguish multiple connections.

The socket port resource is associated with the server component of an EDA Simulator Link MQ configuration. That is, if you use MATLAB in a test bench configuration, the socket port is a resource of the system running MATLAB. If you use a Simulink design in a cosimulation configuration, the socket port is a resource of the system running the HDL simulator.

A TCP/IP socket port number (or alias) is a shared resource. To avoid potential collisions, particularly on servers, you should use caution when choosing a port number for your application. Consider the following guidelines:

- If you are setting up a link for MATLAB, consider the EDA Simulator Link MQ option that directs the operating system to choose an available port number for you. To use this option, specify 0 for the socket port number.

- Choose a port number that is registered for general use. Registered ports range from 1024 to 49151.
- If you do not have a registered port to use, review the list of assigned registered ports and choose a port in the range 5001 to 49151 that is not in use. Ports 1024 to 5000 are also registered, however operating systems use ports in this range for client programs.

Consider registering a port you choose to use.

- Choose a port number that does not contain patterns or have a known meaning. That is, avoid port numbers that more likely to be used by others because they are easier to remember.
- Do not use ports 1 to 1023. These ports are reserved for use by the Internet Assigned Numbers Authority (IANA).
- Avoid using ports 49152 through 65535. These are dynamic ports that operating systems use randomly. If you choose one of these ports, you risk a potential port conflict.
- TCP/IP port filtering on either the client or server side can cause the EDA Simulator Link MQ interface to fail to make a connection.

In such cases the error messages displayed by the EDA Simulator Link MQ interface indicate the lack of a connection, but do not explicitly indicate the cause. A typical scenario caused by port filtering would be a failure to start a simulation in the HDL simulator, with the following warning displayed in the HDL simulator if the simulation is restarted:

```
#MLWarn - MATLAB server not available (yet),  
The entity 'entityname' will not be active
```

In MATLAB, checking the server status at this point indicates that the server is running with no connections:

```
x=hdldaemon('status')  
HLDaemon server is running with 0 connections  
x=  
4449
```



---

**Windows Users** If you suspect that your chosen socket port is filtered, you can check it as follows:

- 1** From the Windows **Start** menu, select **Settings > Network Connections**.
  - 2** Select **Local Area Connection** from the **Network and Dialup Connections** window.
  - 3** From the **Local Area Connection** dialog box, select **Properties > Internet Protocol (TCP/IP > Properties > Advanced > Options > TCP/IP filtering > Properties**.
  - 4** If your port is listed in the **TCP/IP filtering Properties** dialog, you should select an unfiltered port. The easiest way to do this is to specify 0 for the socket port number to let the EDA Simulator Link MQ software choose an available port number for you.
- 

## Specifying TCP/IP Values

Specifies TCP/IP socket communication for links between the HDL simulator and Simulink software. For TCP/IP socket communication on a single computing system, the `<tcp_spec>` parameter of `matlabcp` or `matlabtb` can consist of just a TCP/IP port number or service name. If you are setting up communication between computing systems, you must also specify the name or Internet address of the remote host.

If the HDL simulator and MATLAB are running on the same system, the TCP/IP specification identifies a unique TCP/IP socket port to be used for the link. If the two applications are running on different systems, you must specify a remote host name or Internet address in addition to the socket port. See “Specifying TCP/IP Socket Communication” on page 7-13 for more detail in specifying TCP/IP values.

The following table lists different ways of specifying `tcp_spec`.

Format	Example
<port-num>	4449
<port-alias>	matlabservice
<port-num>@<host>	4449@compa
<host>:<port-num>	compa:4449
<port-alias>@<host-ia>	matlabservice@123.34.55.23

An example of a matlabcp call using port 4449 might look like this:

```
> matlabcp u_osc_filter -mfunc oscfilter -socket 4449
```

A remote connection might look like this:

```
> matlabcp u_osc_filter -mfunc oscfilter -socket computer93:4449
```

### TCP/IP Services

By setting up the MATLAB server as a service, you can run the service in the background, allowing it to handle different HDL simulator client requests over time without you having to start and stop the service manually each time. Although it makes less sense to set up a service for the Simulink software as you cannot really automate the starting of an HDL simulator service, you might want to use a service with Simulink to reserve a TCP/IP socket port.

Services are defined in the `etc/services` file located on each computer; consult the User's Guide for your particular operating system for instructions and more information on setting up TCP/IP services.

For remote connections, the service name must be set up on both the client and server side. For example, if the service name is "matlabservice" and you are performing a Windows-Linux cross-platform simulation, the service name must appear in the service file on both the Windows machine and the Linux machine.

## Improving Simulation Speed

### In this section...

“Obtaining Baseline Performance Numbers” on page 7-17

“Analyzing Simulation Performance” on page 7-17

“Cosimulating Frame-Based Signals with Simulink” on page 7-19

### Obtaining Baseline Performance Numbers

You can baseline the performance numbers by timing the execution of the HDL and the Simulink model separately and adding them together; you may not expect better performance than that. Make sure that the separate simulations are representative: running an HDL-only simulator with unrealistic input stimulus could be much faster than when proper input stimulus is provided.

### Analyzing Simulation Performance

While cosimulation entails a certain amount of overhead, sometimes the HDL simulation itself also slows performance. Ask yourself these questions when trying to analyze and improve performance:

Consideration	Suggestions for Improving Speed
Are you are using NFS or other remote file systems?	How fast is the file system? Consider using a different type or expect that the file system you're using will impact performance.
Are you using separate machines for Simulink and the HDL simulator?	How fast is the network? Wait until the network is quieter or contact your system administrator for advice on improving the connection.

Consideration	Suggestions for Improving Speed
<p>Are you using the same machine for Simulink and the HDL simulator?</p>	<ul style="list-style-type: none"> <li>• Are you using shared pipes instead of sockets? Shared memory is faster.</li> <li>• Are the Simulink and HDL processes large enough to cause swaps to disk? Consider adding more memory; otherwise be aware that you're running a huge process and expect it to impact performance.</li> </ul>
<p>Are you using <i>optimal</i> (that is, as large as possible) Simulink sample rates on the HDL Cosimulation block?</p>	<p>For example, if you set the output sample rate to 1 but only use every 10th sample, you could make the rate 10 and reduce the traffic between Simulink and the HDL simulator.</p> <p>Another example is if you place a very fast clock as an input to the HDL Cosimulation block, but have none of the other inputs need such a fast rate. In that case, you should generate the clock in HDL or via the <b>Clocks</b> or <b>Tcl</b> pane on the HDL Cosimulation block.</p>
<p>Are you compiling/elaborating the HDL using the vopt flow?</p>	<p>Use vopt to optimize your design for maximum (HDL) simulator speed.</p>
<p>Are you using Simulink Accelerator™ mode?</p>	<p>Acceleration mode can speed up the execution of your model. See "Accelerating Models" in the <i>Simulink User's Guide</i>.</p>
<p>If you have the Communications Blockset software, have you considered using Framed signals?</p>	<p>Framed signals reduce the number of Simulink/HDL interactions.</p>

## Cosimulating Frame-Based Signals with Simulink

### Overview to Cosimulation with Frame-Based Signals

Frame-based processing can improve the computational time of your Simulink models, because multiple samples can be processed at once. Use of frame-based signals also lets you simulate the behavior of frame-based systems more accurately. The HDL Cosimulation block supports processing of single-channel frame-based signals.

A *frame* of data is a collection of sequential samples from a single channel or multiple channels. One frame of a single-channel signal is represented by a M-by-1 column vector. A signal is *frame based* if it is propagated through a model one frame at a time.

Frame-based processing requires the Signal Processing Blockset software. Source blocks from the Signal Processing Sources library let you specify a frame-based signal by setting the **Samples per frame** block parameter. Most other signal processing blocks preserve the frame status of an input signal. You can use the Buffer block to buffer a sequence of samples into frames.

See “Working with Signals” in the Signal Processing Blockset documentation for detailed information about frame-based processing.

### Using Frame-Based Processing

You do not need to configure the HDL Cosimulation block in any special way for frame-based processing. To use frame-based processing in a cosimulation, connect one or more single-channel frame-based signals to one or more input ports of the HDL Cosimulation block. All such signals must meet the requirements described in “Frame-Based Processing Requirements and Restrictions” on page 7-20. The HDL Cosimulation block automatically configures any outputs for frame-based operation at the appropriate frame size.

Use of frame-based signals affects only the Simulink side of the cosimulation. The behavior of the HDL code under simulation in the HDL simulator does not change in any way. Simulink assumes that HDL simulator processing is sample based. Simulink assembles samples acquired from the HDL simulator into frames as required. Conversely, Simulink transmits output data to the

HDL simulator in frames, which are unpacked and processed by the HDL simulator one sample at a time.

### **Frame-Based Processing Requirements and Restrictions**

Observe the following restrictions and requirements when connecting frame-based signals in to an HDL Cosimulation block:

- Connection of mixed frame-based and sample-based signals to the same HDL Cosimulation block is not supported.
- Only single-channel frame-based signals can be connected to the HDL Cosimulation block. Use of multichannel (matrix) frame-based signals is not supported in this release.
- All frame-based signals connected to the HDL Cosimulation block must have the same frame size.

Frame-based processing in the Simulink model is transparent to the operation of the HDL model under simulation in the HDL simulator. The HDL model is presumed to be sample-based. The following constraint also applies to the HDL model under simulation in the HDL simulator:

Specify VHDL signals as scalars values, not vectors or arrays (with the exception of bit vectors, as VHDL and Verilog bit vectors are converted to the appropriately sized fixed-point scalar data type by the HDL Cosimulation block).

### **Frame-Based Cosimulation Example**

This example shows the use of the HDL Cosimulation block to cosimulate a VHDL implementation of a simple lowpass filter. In the example, you will compare the performance of the simulation using frame-based and sample-based signals.

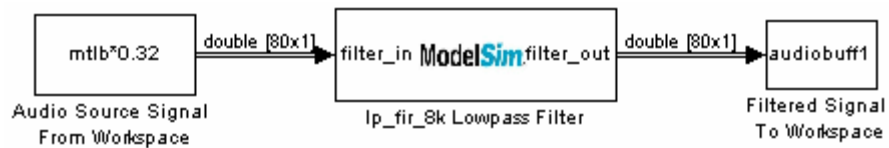
The example files are:

- `matlabroot\toolbox\modelsim\modelsimdemos\frame_filter_cosim.mdl`: the example model.
- `matlabroot\toolbox\modelsim\modelsimdemos\VHDL\frame_demos\lp_fir_8k.vhd`:

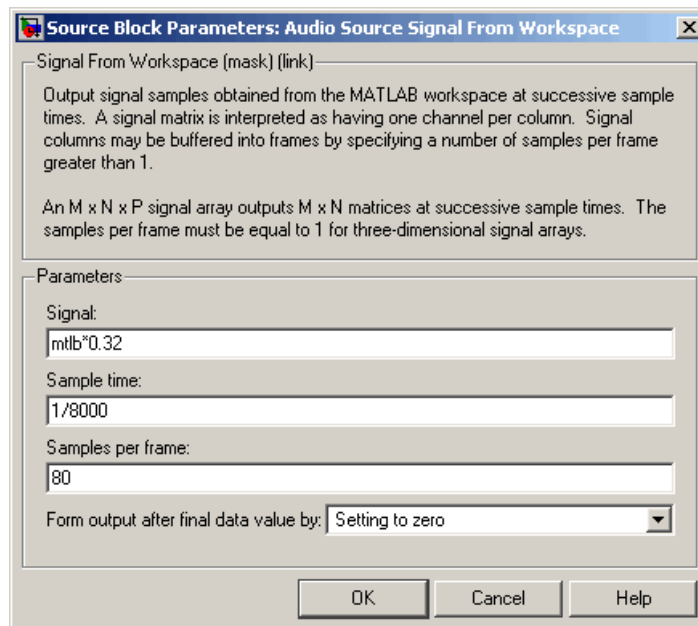
VHDL code for the filter to be cosimulated. The filter was designed with FDATool and the code was generated by the Filter Design HDL Coder.

The example uses the data file `matlabroot\toolbox\signal\signal\mtlb.mat` as an input signal. This file contains a speech signal. The sample data is of data type double, sampled at a rate of 8 kHz.

The next figure shows the `frame_filter_cosim.mdl` model.



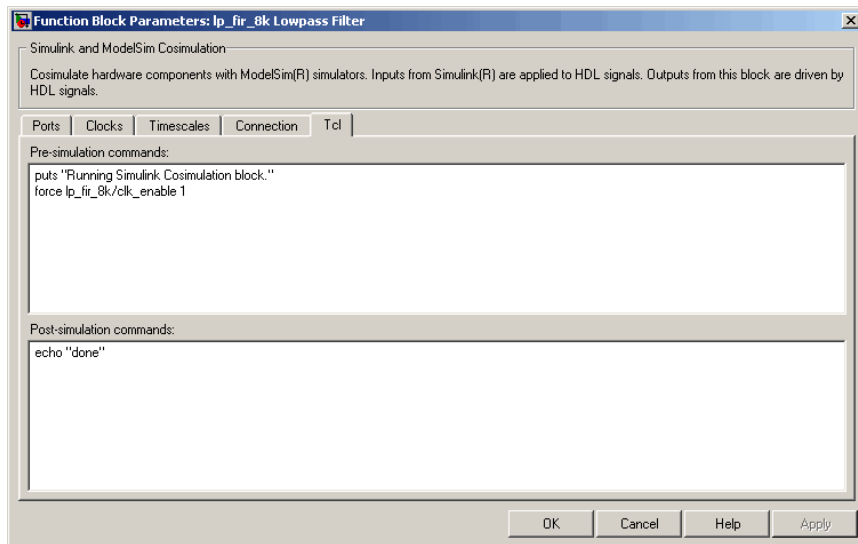
The Audio Source Signal From Workspace block provides an input signal from the workspace variable `mtlb`. The block is configured for an 8 kHz sample rate, with a frame size of 80, as shown in this figure.



The sample rate and frame size of the input signal propagate throughout the model.

The VHDL code file `lp_fir_8k.vhd` implements a simple lowpass FIR filter with a cutoff frequency of 1500 Hz. The HDL Cosimulation block simulates this HDL module. The HDL Cosimulation block ports and clock signal are configured to match the corresponding signals on the VHDL entity.

For the ModelSim simulation to execute correctly, the `clk_enable` signal of the `lp_fir_8k` entity must be forced high. The signal is forced by a pre-simulation command transmitted by the HDL Cosimulation block. The command has been entered into the **Tcl** pane of the HDL Cosimulation block, as shown in the following figure.



The HDL Cosimulation block returns output in the workspace variable `audiobuff1` via the Filtered Signal To Workspace block.

To run the cosimulation, perform the following steps:

- 1 Start MATLAB and make it your active window.



- 2** Set up and change to a writable working directory that is outside the context of your MATLAB installation directory.
- 3** Add the demo directory (`matlabroot\toolbox\modelsim\modelsimdemos\frame_cosim`) to the MATLAB path.
- 4** Copy the demo VHDL file `lp_fir_8k.vhd` to your working directory.

- 5** Open the example model.

```
open frame_filter_cosim.mdl
```

- 6** Load the source speech signal, which will be filtered, into the MATLAB workspace.

```
load mtlb
```

If you have a compatible sound card, you can play back the source signal by typing the following commands at the MATLAB command prompt:

```
a = audioplayer(mtlb,8000);  
play(a);
```

- 7** Start ModelSim by typing the following command at the MATLAB command prompt:

```
vsim
```

The ModelSim window should now be active. If not, start it.

- 8** At the ModelSim prompt, create a design library, and compile the VHDL filter code from the source file `lp_fir_8k.vhd`, by typing the following commands:

```
vlib work  
vmap work work  
vcom lp_fir_8k.vhd
```

- 9** The lowpass filter to be simulated is defined as the entity `lp_fir_8k`. At the ModelSim prompt, load the instantiated entity `lp_fir_8k` for cosimulation:

```
vsimulink lp_fir_8k
```

ModelSim is now set up for cosimulation.

- 10 Start MATLAB. Run a simulation and measure elapsed time as follows:

```
t = clock; sim(gcs); etime(clock,t)
```

```
ans =
```

```
2.7190
```

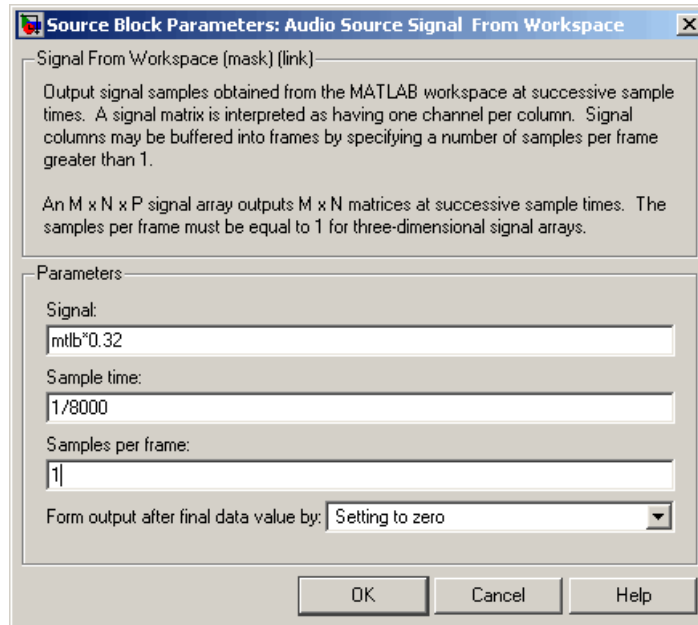
The timing in this code excerpt is typical for a run of this model given a simulation **Stop time** of 1 second and a frame size of 80 samples. Timings are system-dependent and will vary slightly from one simulation run to the next.

Take note of the timing you obtained. For the next simulation run, you will change the model to sample-based operation and obtain a comparative timing.

- 11 MATLAB stores the filtered audio signal returned from ModelSim in the workspace variable `audiobuff1`. If you have a compatible sound card, you can play back the filtered signal to hear the effect of the lowpass filter. Play the signal by typing the following commands at the MATLAB command prompt:

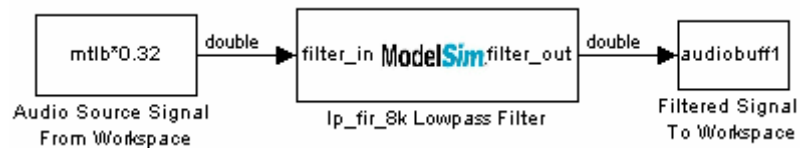
```
b = audioplayer(audiobuff1,8000);  
play(b);
```

- 12 Open the block parameters dialog box of the Audio Source Signal From Workspace block and set the **Samples per frame** property to 1, as shown in this figure.



- 13** Close the dialog box, and select the Simulink window. Select **Update diagram** from the **Edit** menu.

The block diagram now indicates that the source signal (and all signals inheriting from it) is a scalar, as shown in the following figure.



- 14** Start ModelSim. At the ModelSim prompt, type

```
restart
```

- 15** Start MATLAB. Run a simulation and measure elapsed time as follows:

```
t = clock; sim(gcs); etime(clock,t)
```

```
ans =
```

```
3.8440
```

Observe that the elapsed time has increased significantly with a sample-based input signal. The timing in this code excerpt is typical for a sample-based run of this model given a simulation **Stop time** of 1 second. Timings are system-dependent and will vary slightly from one simulation run to the next.

- 16** Close down the simulation in an orderly way. In ModelSim, stop the simulation by selecting **Simulate > End Simulation**, and quit ModelSim. Then, close the Simulink model window.

# Advanced Operational Topics

---

- “Avoiding Race Conditions in HDL Simulators” on page 8-2
- “Performing Data Type Conversions” on page 8-5
- “Understanding How Simulink Software Drives Cosimulation Signals” on page 8-14
- “Understanding the Representation of Simulation Time” on page 8-15
- “Handling Multirate Signals” on page 8-27
- “Understanding Block Simulation Latency” on page 8-28
- “Interfacing with Continuous Time Signals” on page 8-34

## Avoiding Race Conditions in HDL Simulators

### In this section...

“Overview to Avoiding Race Conditions” on page 8-2

“Potential Race Conditions in Simulink Link Sessions” on page 8-2

“Potential Race Conditions in MATLAB Link Sessions” on page 8-3

“Further Reading” on page 8-4

### Overview to Avoiding Race Conditions

A well-known issue in hardware simulation is the potential for nondeterministic results when race conditions are present. Because the HDL simulator is a highly parallel execution environment, you must write the HDL such that the results do not depend on the ordering of process execution.

Although there are well-known coding idioms for ensuring successful simulation of a design under test, you must always take special care at the testbench/DUT interfaces for applying stimulus and reading results, even in pure HDL environments. For an HDL/foreign language interface, such as with a Simulink or MATLAB link session, the problem is compounded if there is no common synchronization signal, such as a clock coordinating the flow of data.

### Potential Race Conditions in Simulink Link Sessions

All the signals on the interface of an HDL Cosimulation block in the Simulink library have an intrinsic sample rate associated with them. This sample rate can be thought of as an implicit clock that controls the simulation time at which a value change can occur. Because this implicit clock is completely unknown to the HDL engine (that is, it is not an HDL signal), the times at which input values are driven into the HDL or output values are sampled from the HDL are asynchronous to any clocks coded in HDL directly, even if they are nominally at the same frequency.

For Simulink value changes scheduled to occur at a specific simulation time, the HDL simulator does not make any guarantees as to the order that value change occurs versus some other blocking signal assignment. Thus, if the

Simulink values are driven/sampled at the same time as an active clock edge in the HDL, there is a race condition.

For cases where your active HDL clock edge and your intrinsic Simulink active clock edges are at the same frequency, you can ensure proper data propagation by offsetting one of those edges. Because the Simulink sample rates are always aligned with time 0, you can accomplish this offset by shifting the active clock edge in the HDL off of time 0. If you are coding the clock stimulus in HDL, use a delay operator ("after" or "#") to accomplish this offset.

When using a Tcl "force" command to describe the clock waveform, you can simply put the first active edge at some nonzero time. Using a nonzero value allows a Simulink sample rate that is the same as the fundamental clock rate in your HDL. This example shows a 20 ns clock (so the Simulink sample rates will also be every 20 ns) with an active positive edge that is offset from time 0 by 2 ns:

```
Mentor> force top.clk 1 {2 ns}, 0 { 12 ns} -repeat 20 ns
```

For HDL Cosimulation Blocks with Clock panes, you can define the clock period and active edge in that pane. The waveform definition places the **non-active** edge at time 0 and the **active** edge at time T/2. This placement ensures the maximum setup and hold times for a clock with a 50% duty cycle.

If the Simulink sample rates are at a different frequency than the HDL clocks, then you must synchronize the signals between the HDL and Simulink as you would do with any multiple time-domain design, even one in pure HDL. For example, you can place two synchronizing flip-flops at the interface.

If your cosimulation does not include clocks, then you must also treat the interfacing of Simulink and the HDL code as being between asynchronous time domains. You may need to over-sample outputs to ensure that all data transitions are captured.

## Potential Race Conditions in MATLAB Link Sessions

When you use the `-sensitivity`, `-rising_edge`, or `-falling_edge` scheduling options to `matlabtb` or `matlabcp` to trigger MATLAB function calls, the propagation of values follow the same semantics as a pure HDL design; you are guaranteed that the triggers must occur before the results can be

calculated. You still can have race conditions, but they can be analyzed within the HDL alone.

However, when you use the `-time` scheduling option to `matlabtb` or `matlabcp`, or use `"tnext"` within the MATLAB function itself, the driving of signal values or sampling of signal values cannot be guaranteed in relation to any HDL signal changes. It is as if the potential race conditions in that time-based scheduling are like an implicit clock that is unknown to the HDL engine and not visible by just looking at the HDL code.

The remedies are the same as for the Simulink signal interfacing: ensure the sampling and driving of signals does not occur at the same simulation times as the MATLAB function calls.

### Further Reading

Problems interfacing designs from testbenches and foreign languages, including race conditions in pure HDL environments, are well-known and extensively documented. Some texts that describe these issues include:

- The documentation for each vendor's HDL simulator product
- The HDL standards specifications
- *Writing Testbenches: Functional Verification of HDL Models*, Janick Bergeron, 2nd edition, © 2003
- *Verilog and SystemVerilog Gotchas*, Stuart Sutherland and Don Mills, © 2007
- *SystemVerilog for Verification: A Guide to Learning the Testbench Language Features*, Chris Spear, © 2007
- *Principles of Verifiable RTL Design*, Lionel Bening and Harry D. Foster, © 2001



## Performing Data Type Conversions

### In this section...

“Converting HDL Data to Send to MATLAB” on page 8-5

“Array Indexing Differences Between MATLAB and HDL” on page 8-7

“Converting Data for Manipulation” on page 8-9

“Converting Data for Return to the HDL Simulator” on page 8-10

### Converting HDL Data to Send to MATLAB

If your HDL application needs to send HDL data to a MATLAB function, you may first need to convert the data to a type supported by MATLAB and the EDA Simulator Link MQ software.

To program a MATLAB function for an HDL model, you must understand the type conversions required by your application. You may also need to handle differences between the array indexing conventions used by the HDL you are using and MATLAB (see following section).

The data types of arguments passed in to the function determine the following:

- The types of conversions required before data is manipulated
- The types of conversions required to return data to the HDL simulator

The following table summarizes how the EDA Simulator Link MQ software converts supported VHDL data types to MATLAB types based on whether the type is scalar or array.

### VHDL-to-MATLAB Data Type Conversions

VHDL Types...	As Scalar Converts to...	As Array Converts to...
STD_LOGIC, STD_ULOGIC, and BIT	A character that matches the character literal for the desired logic state.	

**VHDL-to-MATLAB Data Type Conversions (Continued)**

<b>VHDL Types...</b>	<b>As Scalar Converts to...</b>	<b>As Array Converts to...</b>
STD_LOGIC_VECTOR, STD_ULOGIC_VECTOR, BIT_VECTOR, SIGNED, and UNSIGNED		A column vector of characters (as defined in VHDL Conversions for the HDL Simulator on page 8-11) with one bit per character.
Arrays of STD_LOGIC_VECTOR, STD_ULOGIC_VECTOR, BIT_VECTOR, SIGNED, and UNSIGNED		An array of characters (as defined above) with a size that is equivalent to the VHDL port size.
INTEGER and NATURAL	Type int32.	Arrays of type int32 with a size that is equivalent to the VHDL port size.
REAL	Type double.	Arrays of type double with a size that is equivalent to the VHDL port size.
TIME	Type double for time values in seconds and type int64 for values representing simulator time increments (see the description of the 'time' option in hdldaemon).	Arrays of type double or int64 with a size that is equivalent to the VHDL port size.
Enumerated types	Character array (string) that contains the MATLAB representation of a VHDL label or character literal. For example, the label high converts to 'high' and the character literal 'c' converts to ''c''.	Cell array of strings with each element equal to a label for the defined enumerated type. Each element is the MATLAB representation of a VHDL label or character literal. For example, the vector (one, '2', three) converts to the column vector ['one'; ''2''; 'three']. A user-defined enumerated type that contains only character literals, and then converts to a vector or array of

## VHDL-to-MATLAB Data Type Conversions (Continued)

VHDL Types...	As Scalar Converts to...	As Array Converts to...
		characters as indicated for the types <code>STD_LOGIC_VECTOR</code> , <code>STD_ULONGIC_VECTOR</code> , <code>BIT_VECTOR</code> , <code>SIGNED</code> , and <code>UNSIGNED</code> .

The following table summarizes how the EDA Simulator Link MQ software converts supported Verilog data types to MATLAB types. The software supports only scalar data types for Verilog.

## Verilog-to-MATLAB Data Type Conversions

Verilog Types...	Converts to...
wire, reg	A character or a column vector of characters that matches the character literal for the desired logic states (bits).
integer	A 32-element column vector of characters that matches the character literal for the desired logic states (bits).

## Array Indexing Differences Between MATLAB and HDL

In multidimensional arrays, the same underlying OS memory buffer maps to different elements in MATLAB and the HDL simulator (this mapping only reflects different ways the different languages offer for naming the elements of the same array). When you use both `matlabtb` and `matlabcp` functions, be careful to assign and interpret values consistently in both applications.

In HDL, a multidimensional array declared as:

```
type matrix_2x3x4 is array (0 to 1, 4 downto 2) of std_logic_vector(8 downto 5);
```

has a memory layout as follows:

bit	01	02	03	04	05	06	07	08	09	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24
-																								
dim1	0	0	0	0	0	0	0	0	0	0	0	0	1	1	1	1	1	1	1	1	1	1	1	1
dim2	4	4	4	4	3	3	3	3	2	2	2	2	4	4	4	4	3	3	3	3	2	2	2	2
dim3	8	7	6	5	8	7	6	5	8	7	6	5	8	7	6	5	8	7	6	5	8	7	6	5

This same layout corresponds to the following MATLAB 4x3x2 matrix:

bit	01	02	03	04	05	06	07	08	09	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24
-																								
dim1	1	2	3	4	1	2	3	4	1	2	3	4	1	2	3	4	1	2	3	4	1	2	3	4
dim2	1	1	1	1	2	2	2	2	3	3	3	3	1	1	1	1	2	2	2	2	3	3	3	3
dim3	1	1	1	1	1	1	1	1	1	1	1	1	2	2	2	2	2	2	2	2	2	2	2	2

Therefore, if H is the HDL array and M is the MATLAB matrix, the following indexed values are the same:

- b1 H(0,4,8) = M(1,1,1)
- b2 H(0,4,7) = M(2,1,1)
- b3 H(0,4,6) = M(3,1,1)
- b4 H(0,4,5) = M(4,1,1)
- b5 H(0,3,8) = M(1,2,1)
- b6 H(0,3,7) = M(2,2,1)
- ...
- b19 H(1,3,6) = M(3,2,2)
- b20 H(1,3,5) = M(4,2,2)
- b21 H(1,2,8) = M(1,3,2)
- b22 H(1,2,7) = M(2,3,2)
- b23 H(1,2,6) = M(3,3,2)
- b24 H(1,2,5) = M(4,3,2)

You can extend this indexing to N-dimensions. In general, the dimensions—if numbered from left to right—are reversed. The right-most dimension in HDL corresponds to the left-most dimension in MATLAB.

## Converting Data for Manipulation

Depending on how your simulation MATLAB function uses the data it receives from the HDL simulator, you may need to code the function to convert data to a different type before manipulating it. The following table lists circumstances under which you would require such conversions.

### Required Data Conversions

If You Need the Function to...	Then...
<p>Compute numeric data that is received as a type other than <code>double</code></p>	<p>Use the <code>double</code> function to convert the data to type <code>double</code> before performing the computation. For example:</p> <pre data-bbox="768 718 1196 748">datas(inc+1) = double(idata);</pre>
<p>Convert a standard logic or bit vector to an unsigned integer or positive decimal</p>	<p>Use the <code>mv12dec</code> function to convert the data to an unsigned decimal value. For example:</p> <pre data-bbox="768 890 1151 920">uval = mv12dec(oport.val')</pre> <p>This example assumes the standard logic or bit vector is composed of the character literals '1' and '0' only. These are the only two values that can be converted to an integer equivalent.</p> <p>The <code>mv12dec</code> function converts the binary data that the MATLAB function receives from the entity's <code>osc_in</code> port to unsigned decimal values that MATLAB can compute.</p> <p>See <code>mv12dec</code> for more information on this function.</p>
<p>Convert a standard logic or bit vector to a negative decimal</p>	<p>Use the following application of the <code>mv12dec</code> function to convert the data to a signed decimal value. For example:</p> <pre data-bbox="768 1449 1173 1479">suval = mv12dec(oport.val'), true);</pre>

### Required Data Conversions (Continued)

If You Need the Function to...	Then...
	This example assumes the standard logic or bit vector is composed of the character literals '1' and '0' only. These are the only two values that can be converted to an integer equivalent.

### Examples

The following code excerpt illustrates data type conversion of data passed in to a callback:

```
InDelayLine(1) = InputScale * mvl2dec(iport.osc_in',true);
```

This example tests port values of VHDL type `STD_LOGIC` and `STD_LOGIC_VECTOR` by using the `all` function as follows:

```
all(oport.val == '1' | oport.val  
== '0')
```

This example returns `True` if all elements are '1' or '0'.

### Converting Data for Return to the HDL Simulator

If your simulation MATLAB function needs to return data to the HDL simulator, you may first need to convert the data to a type supported by the EDA Simulator Link MQ software. The following tables list circumstances under which such conversions are required for VHDL and Verilog.

**Note** When data values are returned to the HDL simulator, the char array size must match the HDL type, including leading zeroes, if needed. For example:

```
oport.signal = dec2mv1(2)
```

will only work if `signal` is a 2-bit type in HDL. If the HDL type is anything else, you *must* specify the second argument:

```
oport.signal = dec2mv1(2, N)
```

where `N` is the number of bits in the HDL data type.

## VHDL Conversions for the HDL Simulator

To Return Data to an IN Port of Type...	Then...
STD_LOGIC, STD_ULOGIC, or BIT	<p>Declare the data as a character that matches the character literal for the desired logic state. For <code>STD_LOGIC</code> and <code>STD_ULOGIC</code>, the character can be 'U', 'X', '0', '1', 'Z', 'W', 'L', 'H', or '-'. For <code>BIT</code>, the character can be '0' or '1'. For example:</p> <pre>iport.s1 = 'X'; %STD_LOGIC iport.bit = '1'; %BIT</pre>
STD_LOGIC_VECTOR, STD_ULOGIC_VECTOR, BIT_VECTOR, SIGNED, or UNSIGNED	<p>Declare the data as a column vector or row vector of characters (as defined above) with one bit per character. For example:</p> <pre>iport.s1v = 'X10ZZ'; %STD_LOGIC_VECTOR iport.bitv = '10100'; %BIT_VECTOR iport.uns = dec2mv1(10,8); %UNSIGNED, 8 bits</pre>
Array of STD_LOGIC_VECTOR, STD_ULOGIC_VECTOR, BIT_VECTOR, SIGNED, or UNSIGNED	<p>Declare the data as an array of type character with a size that is equivalent to the VHDL port size. See “Array Indexing Differences Between MATLAB and HDL” on page 8-7.</p>

**VHDL Conversions for the HDL Simulator (Continued)**

<b>To Return Data to an IN Port of Type...</b>	<b>Then...</b>
INTEGER or NATURAL	<p>Declare the data as an array of type <code>int32</code> with a size that is equivalent to the VHDL array size. Alternatively, convert the data to an array of type <code>int32</code> with the MATLAB <code>int32</code> function before returning it. Be sure to limit the data to values with the range of the VHDL type. If necessary, check the <code>right</code> and <code>left</code> fields of the <code>portinfo</code> structure. For example:</p> <pre>iport.int = int32(1:10)';</pre>
REAL	<p>Declare the data as an array of type <code>double</code> with a size that is equivalent to the VHDL port size. For example:</p> <pre>iport.dbl = ones(2,2);</pre>
TIME	<p>Declare a VHDL <code>TIME</code> value as time in seconds, using type <code>double</code>, or as an integer of simulator time increments, using type <code>int64</code>. You can use the two formats interchangeably and what you specify does not depend on the <code>hdldaemon 'time'</code> option (see <code>hdldaemon</code>), which applies to IN ports only. Declare an array of <code>TIME</code> values by using a MATLAB array of identical size and shape. All elements of a given port are restricted to time in seconds (type <code>double</code>) or simulator increments (type <code>int64</code>), but otherwise you can mix the formats. For example:</p> <pre>iport.t1 = int64(1:10)'; %Simulator time                     %increments iport.t2 = 1e-9; %1 nsec</pre>



**VHDL Conversions for the HDL Simulator (Continued)**

<b>To Return Data to an IN Port of Type...</b>	<b>Then...</b>
Enumerated types	<p>Declare the data as a string for scalar ports or a cell array of strings for array ports with each element equal to a label for the defined enumerated type. The 'label' field of the portinfo structure lists all valid labels (see “Gaining Access to and Applying Port Information” on page 9-5). Except for character literals, labels are not case sensitive. In general, you should specify character literals completely, including the single quotes, as in the first example shown here. .</p> <pre data-bbox="556 690 1053 777"> iport.char = {'A', 'B'}; %Character               %literal iport.undef = 'mylabel'; %User-defined label </pre>
Character array for standard logic or bit representation	<p>Use the dec2mv1 function to convert the integer. For example:</p> <pre data-bbox="556 888 1023 916"> oport.slva =dec2mv1([23 99],8)'; </pre> <p>This example converts two integers to a 2-element array of standard logic vectors consisting of 8 bits.</p>

**Verilog Conversions for the HDL Simulator**

<b>To Return Data to an input Port of Type...</b>	<b>Then...</b>
reg, wire	<p>Declare the data as a character or a column vector of characters that matches the character literal for the desired logic state. For example:</p> <pre data-bbox="556 1333 793 1361"> iport.bit = '1'; </pre>
integer	<p>Declare the data as a 32-element column vector of characters (as defined above) with one bit per character.</p>

## Understanding How Simulink Software Drives Cosimulation Signals

Although you can bind the output ports of an HDL Cosimulation block to any signal in an HDL model hierarchy, you must use some caution when connecting signals to input ports. Ensure that the signal you are binding to does not have other drivers. If it does, use resolved logic types; otherwise you may get unpredictable results.

If you need to use a signal that has multiple drivers and it is resolved (for example, it is of VHDL type `STD_LOGIC`), Simulink applies the resolution function at each time step defined by the signal's Simulink sample rate. Depending on the other drivers, the Simulink value may or may not get applied. Furthermore, Simulink has no control over signal changes that occur between its sample times.

---

**Note** Verify that signals used in cosimulation have read/write access. You can check read/write access through the HDL simulator—see HDL simulator documentation for details. This rule applies to all signals on the **Ports**, **Clocks**, and **Tcl** panes.

---

## Understanding the Representation of Simulation Time

### In this section...

“Overview to the Representation of Simulation Time” on page 8-15

“Defining the Simulink and HDL Simulator Timing Relationship” on page 8-16

“Setting the Timing Mode with EDA Simulator Link MQ” on page 8-16

“Relative Timing Mode” on page 8-18

“Absolute Timing Mode” on page 8-21

“Timing Mode Usage Considerations” on page 8-23

“Setting HDL Cosimulation Port Sample Times” on page 8-25

### Overview to the Representation of Simulation Time

The representation of simulation time differs significantly between the HDL simulator and Simulink. Each application has its own timing engine and the link software must synchronize the simulation times between the two.

In the HDL simulator, the unit of simulation time is referred to as a *tick*. The duration of a tick is defined by the HDL simulator *resolution limit*. The default resolution limit is 1 ns, but may vary depending on the simulator.

To determine the current ModelSim resolution limit, enter `echo $resolution` or `report simulator state` at the ModelSim prompt. You can override the default resolution limit by specifying the `-t` option on the ModelSim command line, or by selecting a different Simulator Resolution in the ModelSim Simulate dialog box. Available resolutions in ModelSim are 1x, 10x, or 100x in units of fs, ps, ns, us, ms, or sec. See the ModelSim documentation for further information.

Simulink maintains simulation time as a double-precision value scaled to seconds. This representation accommodates modeling of both continuous and discrete systems.

The relationship between Simulink and the HDL simulator timing affects the following aspects of simulation:

- Total simulation time
- Input port sample times
- Output port sample times
- Clock periods

During a simulation run, Simulink communicates the current simulation time to the HDL simulator at each intermediate step. (An intermediate step corresponds to a Simulink sample time hit. Upon each intermediate step, new values are applied at input ports, or output ports are sampled.)

To bring the HDL simulator up-to-date with Simulink during cosimulation, you must convert sampled Simulink time to HDL simulator time (ticks) and allow the HDL simulator to run for the computed number of ticks.

### Defining the Simulink and HDL Simulator Timing Relationship

The differences in the representation of simulation time can be reconciled in one of two ways using the EDA Simulator Link MQ interface:

- By defining the timing relationship manually (with **Timescales** pane)

When you define the relationship manually, you determine how many femtoseconds, picoseconds, nanoseconds, microseconds, milliseconds, seconds, or ticks in the HDL simulator represent 1 second in Simulink.

- By allowing EDA Simulator Link MQ to define the timescale automatically (with **Auto Timescale** on the **Timescales** pane)

When you allow the link software to define the timing relationship, it attempts to set the timescale factor between the HDL simulator and Simulink to be as close as possible to 1 second in the HDL simulator = 1 second in Simulink. If this setting is not possible, the link product attempts to set the signal rate on the Simulink model port to the lowest possible number of HDL simulator ticks.

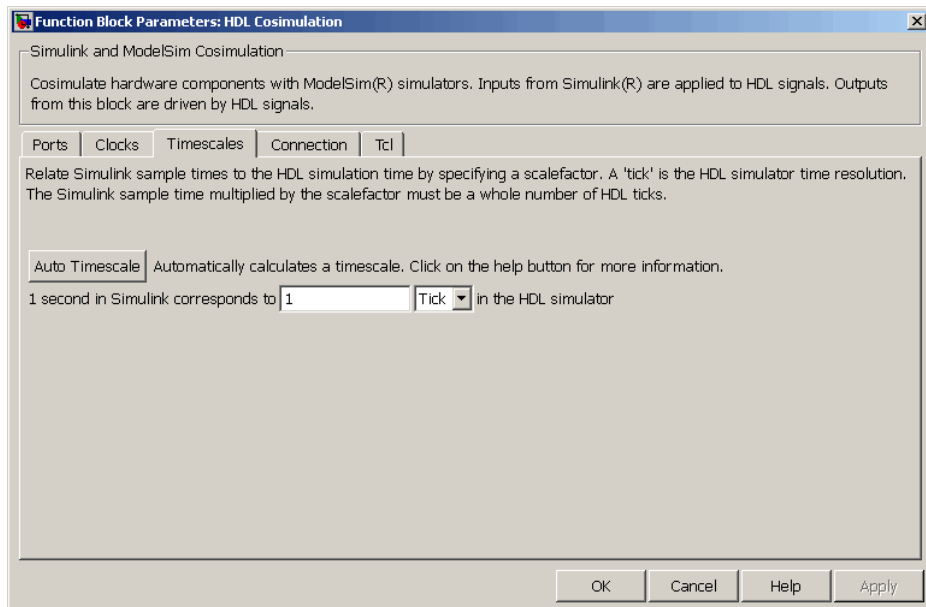
### Setting the Timing Mode with EDA Simulator Link MQ

The **Timescales** pane of the HDL Cosimulation block parameters dialog box defines a correspondence between one second of Simulink time and some

quantity of HDL simulator time. This quantity of HDL simulator time can be expressed in one of the following ways:

- In *relative* terms (i.e., as some number of HDL simulator ticks). In this case, the cosimulation is said to operate in *relative timing mode*. The HDL Cosimulation block defaults to relative timing mode for cosimulation. For more on relative timing mode, see “Relative Timing Mode” on page 8-18.
- In *absolute* units (such as milliseconds or nanoseconds). In this case, the cosimulation is said to operate in *absolute timing mode*. For more on absolute timing mode, see “Absolute Timing Mode” on page 8-21.

The **Timescales** pane lets you choose an optimal timing relationship between Simulink and the HDL simulator, either by entering the HDL simulator equivalent or by clicking on **Auto Timescale**. The next figure shows the default settings of the **Timescales** pane.



For instructions on setting the timing mode either automatically or manually, see “Timescales Pane” on page 12-14 in the HDL Cosimulation block reference.

## Relative Timing Mode

Relative timing mode defines the following one-to-one correspondence between simulation time in Simulink and the HDL simulator:

*One second* in Simulink corresponds to *N ticks* in the HDL simulator, where *N* is a scale factor.

This correspondence holds regardless of the HDL simulator timing resolution.

The following pseudocode shows how Simulink time units are converted to HDL simulator ticks:

$$\text{InTicks} = N * \text{tInSecs}$$

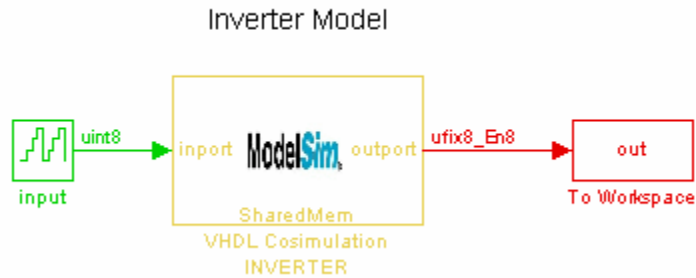
where *InTicks* is the HDL simulator time in ticks, *tInSecs* is the Simulink time in seconds, and *N* is a scale factor.

## Operation of Relative Timing Mode

The HDL Cosimulation block defaults to relative timing mode, with a scale factor of 1. Thus, 1 Simulink second corresponds to 1 tick in the HDL simulator. In the default case:

- If the total simulation time in Simulink is specified as *N* seconds, then the HDL simulation will run for exactly *N* ticks (i.e., *N* ns at the default resolution limit).
- Similarly, if Simulink computes the sample time of an HDL Cosimulation block input port as *T<sub>si</sub>* seconds, new values will be deposited on the HDL input port at exact multiples of *T<sub>si</sub>* ticks. If an output port has an explicitly specified sample time of *T<sub>so</sub>* seconds, values will be read from the HDL simulator at multiples of *T<sub>so</sub>* ticks.

**Relative Timing Mode Example.** To understand how relative timing mode operates, review cosimulation results from the following example model.



The model contains an HDL Cosimulation block (labeled VHDL Cosimulation INVERTER) simulating an 8-bit inverter that is enabled by an explicit clock. The inverter has a single input and a single output. The following sample shows VHDL code for the inverter:

```

LIBRARY ieee;
USE ieee.std_logic_1164.ALL;
ENTITY inverter IS PORT (

    inport : IN  std_logic_vector := "11111111";
    outport: OUT std_logic_vector := "00000000";
    clk:IN  std_logic
);
END inverter;

LIBRARY ieee;
USE ieee.std_logic_1164.ALL;

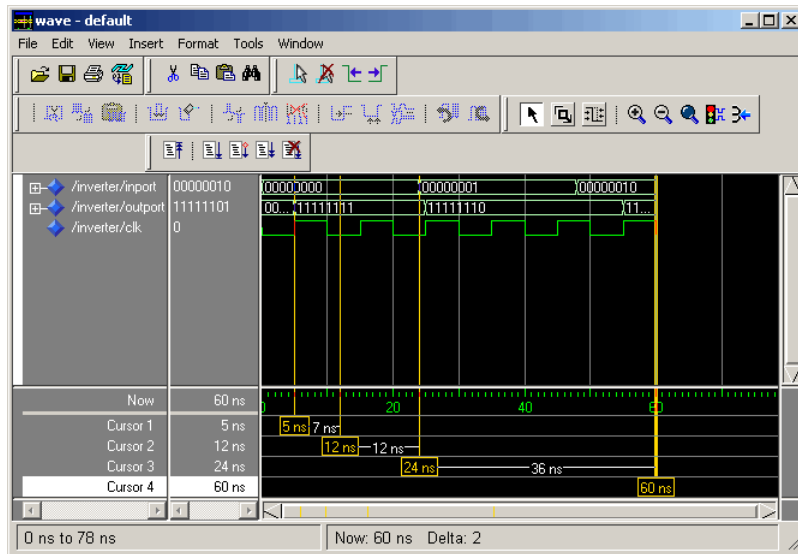
ARCHITECTURE behavioral OF inverter IS
BEGIN
    PROCESS(clk)
    BEGIN
        IF (clk'EVENT AND clk = '1') THEN
            output <= NOT inport;
        END IF;
    END PROCESS;
END behavioral;

```

A cosimulation of this model might have the following settings:

- Simulation parameters in Simulink:
  - **Timescales** parameters: default (relative timing with a scale factor of 1)
  - Total simulation time: 60 s
  - Input port (/inverter/inport) sample time: 24 s
  - Output port (/inverter/outport) sample time: 12 s
  - Clock (inverter/clock) period: 10 s
- ModelSim resolution limit: 1 ns

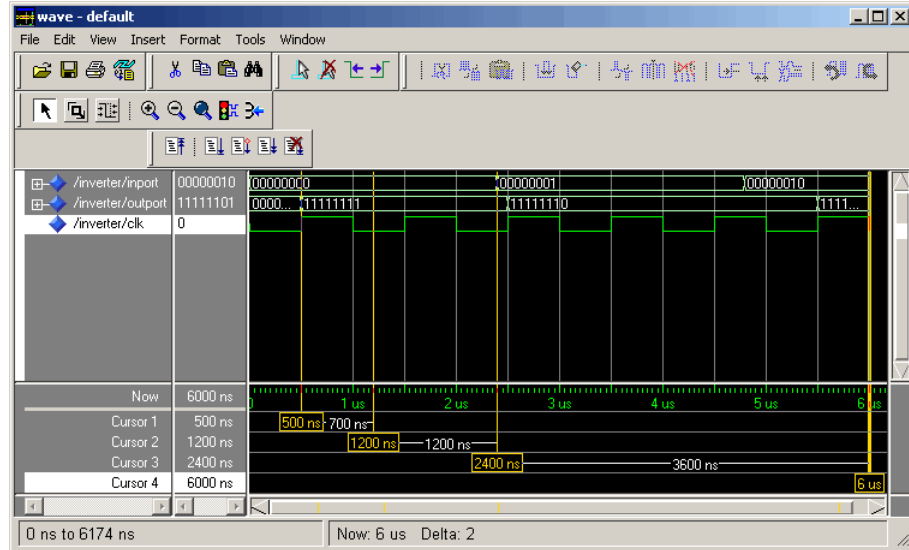
The next figure shows the ModelSim **wave** window after a cosimulation run of the example Simulink model for 60 ns. The **wave** window shows that ModelSim simulated for 60 ticks (60 ns). The inputs change at multiples of 24 ns and the outputs are read from ModelSim at multiples of 12 ns. The clock is driven low and high at intervals of 5 ns.



Now consider a cosimulation of the same model, this time configured with a scale factor of 100 in the **Timescales** pane.



The ModelSim **wave** window in the next figure shows that Simulink port and clock times were scaled by a factor of 100 during simulation. ModelSim simulated for 6 microseconds (60 \* 100 ns). The inputs change at multiples of 24 \* 100 ns and outputs are read from ModelSim at multiples of 12 \* 100 ns. The clock is driven low and high at intervals of 500 ns.



## Absolute Timing Mode

Absolute timing mode lets you define the timing relationship between Simulink and the HDL simulator in terms of absolute time units and a scale factor:

*One second in Simulink corresponds to  $(N * Tu)$  seconds in the HDL simulator, where  $Tu$  is an absolute time unit (e.g., ms, ns, etc.) and  $N$  is a scale factor.*

In absolute timing mode, all sample times and clock periods in Simulink are quantized to HDL simulator ticks. The following pseudocode illustrates the conversion:

$$tInTicks = tInSecs * (tScale / tRL)$$

where:

- `tInTicks` is the HDL simulator time in ticks.
- `tInSecs` is the Simulink time in seconds.
- `tScale` is the timescale setting (unit and scale factor) chosen in the **Timescales** pane of the HDL Cosimulation block.
- `tRL` is the HDL simulator resolution limit.

For example, given a **Timescales** pane setting of 1 s and an HDL simulator resolution limit of 1 ns, an output port sample time of 12 ns would be converted to ticks as follows:

$$tInTicks = 12ns * (1s / 1ns) = 12$$

### Operation of Absolute Timing Mode

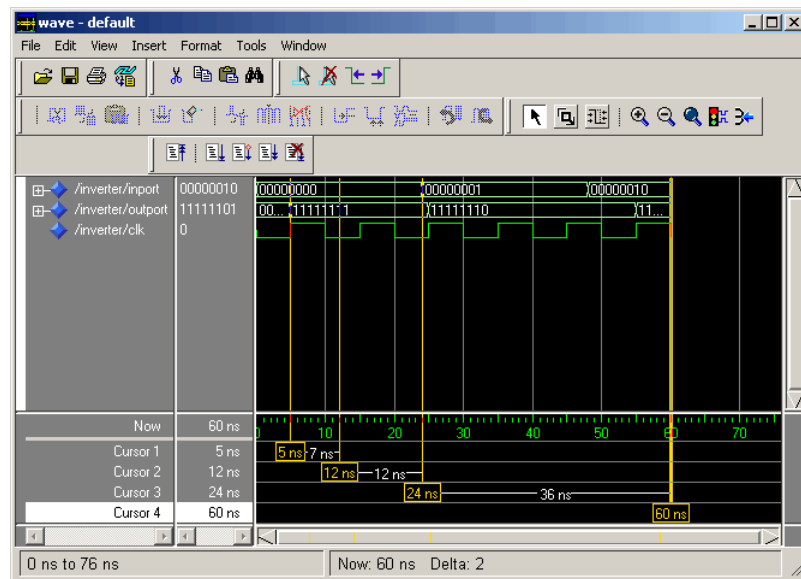
To configure the Timescales parameters for absolute timing mode, you select a unit of absolute time that corresponds to a Simulink second, rather than selecting Tick.

**Absolute Timing Mode Example.** To understand the operation of absolute timing mode, you will again consider the example model discussed in “Operation of Relative Timing Mode” on page 8-18. Suppose that the model is reconfigured as follows:

- Simulation parameters in Simulink:
  - **Timescale** parameters: 1 s of Simulink time corresponds to 1 s of HDL simulator time.
  - Total simulation time: 60e-9 s (60ns)
  - Input port (/inverter/inport) sample time: 24e-9 s (24 ns)
  - Output port (/inverter/outport) sample time: 12e-9 s (12 ns)
  - Clock (inverter/clock) period: 10e-9 s (10 ns)
- HDL simulator resolution limit: 1 ns

Given these simulation parameters, the Simulink software will cosimulate with the HDL simulator for 60 ns, during which Simulink will sample inputs at intervals of 24 ns, update outputs at intervals of 12 ns, and drive clocks at intervals of 10 ns.

The following figure shows the ModelSim **wave** window after a cosimulation run.



## Timing Mode Usage Considerations

When setting a timescale mode, you may need to choose your setting based on the following considerations.

- “Timing Mode Usage Restrictions” on page 8-23
- “Non-Integer Time Periods” on page 8-24

## Timing Mode Usage Restrictions

The following restrictions apply to the use of absolute and relative timing modes:

- When multiple HDL Cosimulation blocks in a model are communicating with a single instance of the HDL simulator, all HDL Cosimulation blocks must have the same **Timescales** pane settings.
- If you change the **Timescales** pane settings in an HDL Cosimulation block between consecutive cosimulation runs, you must restart the simulation in the HDL simulator.
- If you specify a Simulink sample time that cannot be expressed as a whole number of HDL ticks, you will get an error.

### Non-Integer Time Periods

When using non-integer time periods, the HDL simulator cannot represent such an infinitely repeating value. So the simulator truncates the time period, but it does so differently than how Simulink truncates the value, and the two time periods no longer match up.

The following example demonstrates how to set the timing relationship in the following scenario: you want to use a sample period of  $\frac{1}{3\text{Hz}}$  in Simulink, which corresponds to a non-integer time period.

The key idea here is that you must always be able to relate a Simulink time with an HDL tick. The HDL tick is the finest time slice the HDL simulator recognizes.; for ModelSim, the default tick is 1 ns, but it can be made as precise as 1 fs.

However, a 3 Hz signal actually has a period of 333.3333333333... ms, which is not a valid tick period for the HDL simulator. The HDL simulator will truncate such numbers. But Simulink does not make the same decision; thus, for cosimulation where you are trying to keep two independent simulators in synchronization, you should not assume anything. Instead you have to decide whether it is convenient to truncate or round the number.

Therefore, the solution is to "snap" either the Simulink sample time or the HDL sample time (via the timescale) to valid numbers. There are infinite possibilities, but here are some possible ways to perform a snap:

- Change Simulink sample times from 1/3 sec to 0.33333 sec 1 second in Simulink = 1 second in the HDL simulator If you are specifying a clock in the HDL Cosimulation block **Clocks** pane, its period should be 0.33333 sec.
- Keep Simulink sample times at 1/3 sec. 1 second in Simulink = 6 ticks in the HDL simulator If you are specifying a clock in the HDL Cosimulation block **Clocks** pane, its period should be 1/3. Briefly, this specification tells Simulink to make each Simulink sample time correspond to every  $(1/3 \cdot 6) = 2$  ticks, regardless of the HDL time resolution. If your default HDL simulator resolution is 1 ns, that means your HDL sample times are every 2 ns. This sample time will work in a way so that for every Simulink sample time there is a corresponding HDL sample time; however, , Simulink thinks in terms of 1/3 sec periods and the HDL in terms of 2 ns periods. Thus, you could get confused during debug. If you want this to match the real period (such as to 5 places, i.e. 333.33ms), you can follow the next option listed.
- Keep Simulink sample times at 1/3 sec. 1 second in Simulink = 0.99999e9 ticks in the HDL simulator. If you are specifying a clock in the HDL Cosimulation block **Clocks** pane, its period should be 1/3.

## Setting HDL Cosimulation Port Sample Times

In general, Simulink handles the sample time for the ports of an HDL Cosimulation block as follows:

- If an input port is connected to a signal that has an explicit sample time, based on forward propagation, Simulink applies that rate to that input port.
- If an input port is connected to a signal that *does not have* an explicit sample time, Simulink assigns a sample time that is equal to the least common multiple (LCM) of all identified input port sample times for the model.
- After Simulink sets the input port sample periods, it applies user-specified output sample times to all output ports. Sample times must be explicitly defined for all output ports.

If you are developing a model for cosimulation in *relative* timing mode, consider the following sample time guideline:

Specify the output sample time for an HDL Cosimulation block as an integer multiple of the resolution limit defined in the HDL simulator. Use the HDL simulator command `report simulator state` to check the resolution limit of the loaded model. If the HDL simulator resolution

limit is 1 ns and you specify a block's output sample time as 20, Simulink interacts with the HDL simulator every 20 ns.

## Handling Multirate Signals

EDA Simulator Link MQ software supports the use of multirate signals, signals that are sampled or updated at different rates, in a single HDL Cosimulation block. An HDL Cosimulation block exchanges data for each signal at the Simulink sample rate for that signal. For input signals, an HDL Cosimulation block accepts and honors all signal rates.

The HDL Cosimulation block also lets you specify an independent sample time for each output port. You must explicitly set the sample time for each output port, or accept the default. Using this setting lets you control the rate at which Simulink updates an output port by reading the corresponding signal from the HDL simulator.

## Understanding Block Simulation Latency

### In this section...

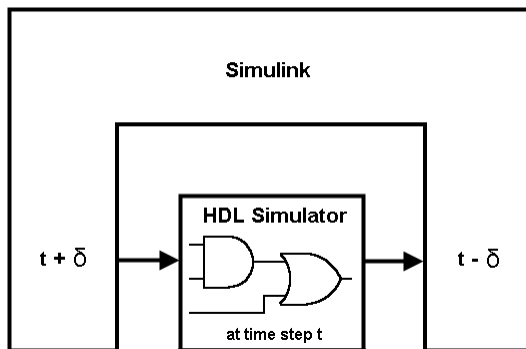
“Overview to Block Simulation Latency” on page 8-28

“Block Latency Example” on page 8-29

### Overview to Block Simulation Latency

Simulink and the EDA Simulator Link MQ Cosimulation blocks supplement the hardware simulator environment, rather than operate as part of it. During cosimulation, Simulink does not participate in the HDL simulator delta-time iteration. From the Simulink perspective, all signal drives (reads) occur during a single delta-time cycle. For this reason, and due to fundamental differences between the HDL simulator and Simulink with regard to use and treatment of simulation time, some degree of latency is introduced when you use EDA Simulator Link MQ Cosimulation blocks. The latency is a time lag that occurs between when Simulink begins the deposit of a signal and when the effect of the deposit is visible on cosimulation block output.

As the following figure shows, Simulink cosimulation block input affects signal values just after the current HDL simulator time step ( $t + \delta$ ) and block output reflects signal values just before the current HDL simulator step time ( $t - \delta$ ).



Regardless of whether you specify your HDL code with latency, the cosimulation block has a minimum latency that is equivalent to the cosimulation block's output sample time. For large sample times, the delay



can appear to be quite long, but this length occurs as an artifact of the cosimulation block, which exchanges data with the HDL simulator at the block's output sample time only. Such length may be reasonable for a cosimulation block that models a device that operates on a clock edge only, such as a register-based device.

For cosimulation blocks that model combinatorial circuits, you may want to experiment with a faster sampling frequency for output ports in order to reduce this latency.

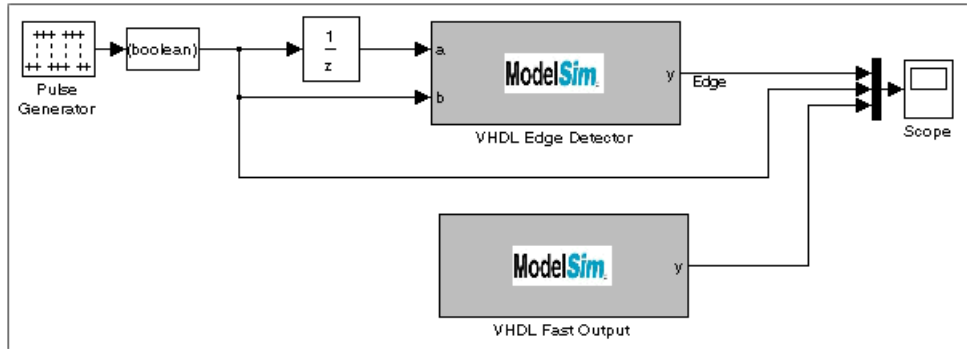
## Block Latency Example

To visualize cosimulation block latency, consider the following VHDL code and Simulink model. The VHDL code represents an XOR gate:

```
-- edgedet.vhd

LIBRARY IEEE;
USE IEEE.std_logic_1164.all;
ENTITY edgedet IS
END edgedet;

ARCHITECTURE behavioral OF edgedet IS
SIGNAL a : std_logic;
SIGNAL b : std_logic;
SIGNAL y : std_logic;
BEGIN
    y <= a XOR b;
END behavioral;
```



In the Simulink model, the cosimulation block VHDL Edge Detector contains an XOR circuit. The second cosimulation block, VHDL Fast Output, simply reads the same XOR output. The first block is driven by a signal generated by the Pulse Generator block. The Data Type Conversion block converts the signal to a boolean value. The signal is then treated three different ways:

- A Unit Delay block applies a sample and hold to the signal and drives block input port a. The delay is equal to one period of the signal's Simulink sample time. When the delay is applied to the XOR, the pulse equals the period specified by the delay block after any edges.
- The signal without a delay drives block input port b.
- The third signal bypasses the cosimulation block and goes directly to the Scope block for display.

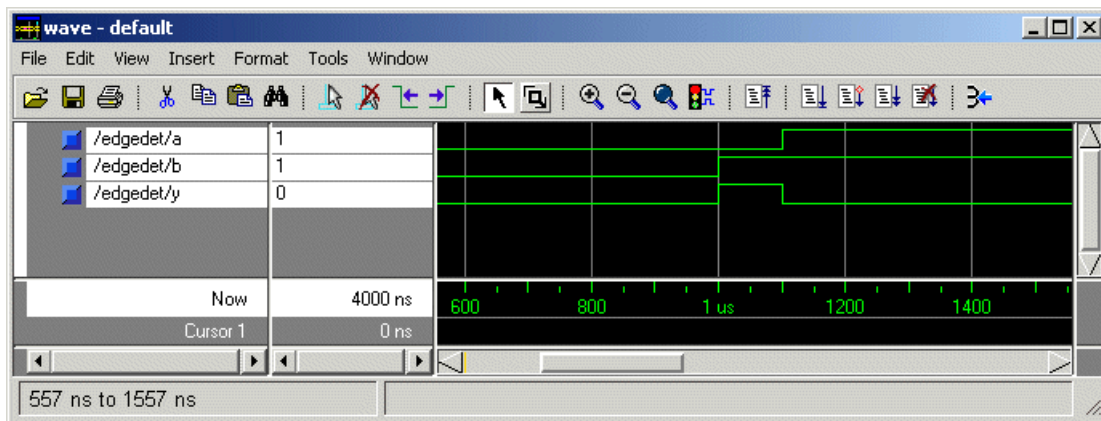
The second cosimulation block, VHDL Fast Output, is a source block that reads the output of the XOR circuit and passes it on to the Scope block for display.

Now, assume that ModelSim is set up with a resolution limit of 100 ns and an iteration limit of 5000, and that the sample times for the blocks in the Simulink model are as follows:

Block	Sample Time	Value
Pulse Generator	Sample time	100

Block	Sample Time	Value
Data Type Conversion block	Sample time	Inherited from Pulse Generator block
Unit Delay block	Sample time	Inherited from Data Type Conversion block
HDL Cosimulation block—Edge Detector	Input sample time	Inherited from Unit Delay block
	Output sample time	100
HDL Cosimulation block—Fast Output (source)	Output sample time	100

After the simulation runs, the ModelSim **wave** window appears as follows.

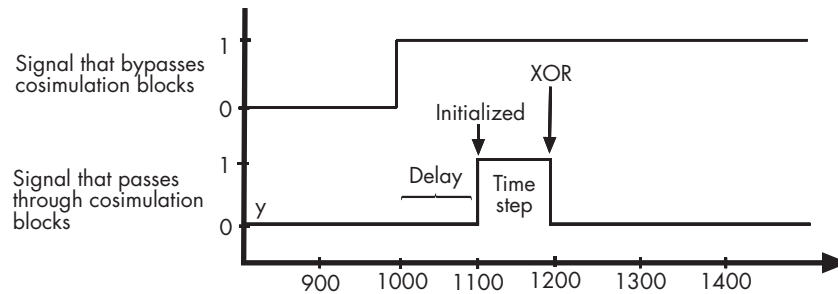


Note the following:

- Signal a gets asserted high after a 100 ns delay. This is due to the unit delay applied by the Simulink model.

- Signal **b** gets asserted high immediately.
- Signal **y** experiences a falling edge as a result of the XOR computation.

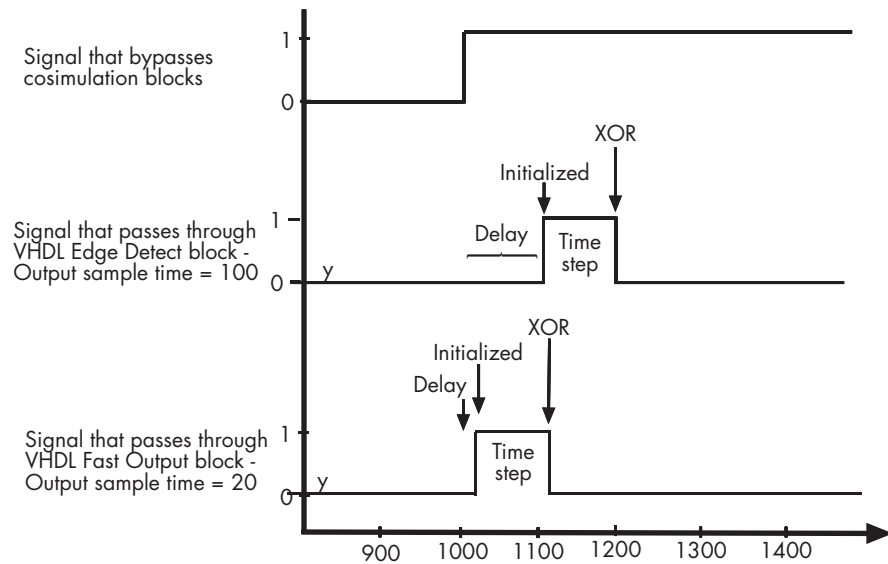
The following figure highlights the individual signal paths that get appear in the Simulink Scope window.



The signal that bypasses the cosimulation blocks rises at  $t=1000$ . That signal stays high for the duration of the sample period. However, the signals that are read from output port **y** of the two cosimulation blocks, display in the Scope window as follows:

- After a one time step delay, the signals rise in response to step generator. The delay occurs because the values that the step generator deposit on the cosimulation block's signal paths do not propagate to the block's output until the next Simulink cycle.
- After the next time step, the signal value falls due to the VHDL XOR operation.

For cosimulation blocks that model combinatorial circuits, such as the one in the preceding example, you may want to experiment with a faster sample frequency for output ports. For example, suppose you change the **Output sample time** for the VHDL Fast Output cosimulation block from 100 to 20. The following figure highlights the individual signal paths that appear in the Scope window for this scenario.



In this case, the signal that bypasses the cosimulation blocks and the output signal read from the VHDL Edge Detect block remain the same. However, the delay for the signal read from the VHDL Fast Output block is 20 ticks instead of 100. Although the size of the time step is still tied to the ModelSim resolution limit, the delay that occurs before the VHDL code is processed is significantly reduced and the time of execution more closely reflects simulation time in ModelSim.

---

**Note** Although this type of parameter tuning can increase simulation performance, it can make a model more difficult to debug. For example, it might be necessary to adjust the output sample time for each cosimulation block.

---

## **Interfacing with Continuous Time Signals**

Use the Simulink Zero-Order Hold block to apply a zero-order hold (ZOH) on continuous signals that are driven into an HDL Cosimulation block.

# M-Function Prototype Reference

---

- “Defining EDA Simulator Link MQ M-Functions and Function Parameters” on page 9-2
- “Scheduling EDA Simulator Link MQ M-Functions Using the tnext Parameter” on page 9-8

## Defining EDA Simulator Link MQ M-Functions and Function Parameters

### In this section...

“M-Function Syntax and Function Argument Definitions” on page 9-2

“Oscfilter Function Example” on page 9-4

“Gaining Access to and Applying Port Information” on page 9-5

### M-Function Syntax and Function Argument Definitions

The syntax of a MATLAB component function is

```
function [oport, tnext] = MyFunctionName(iport, tnow, portinfo)
```

The syntax of a MATLAB test bench function is

```
function [iport, tnext] = MyFunctionName(oport, tnow, portinfo)
```

The input/output arguments (*iport* and *oport*) for a MATLAB component function are the reverse of the port arguments for a MATLAB test bench function. That is, the MATLAB component function returns signal data to the *outputs* and receives data from the *inputs* of the associated HDL module.

For more information on using *tnext* and *tnow* for simulation scheduling, see “Scheduling EDA Simulator Link MQ M-Functions Using the *tnext* Parameter” on page 9-8.

The following table describes each of the test bench and component M-function parameters and the roles they play in each of the functions.



<b>Parameter</b>	<b>Test Bench</b>	<b>Component</b>
<code>input</code>	<i>Output</i> Structure that forces (by deposit) values onto signals connected to input ports of the associated HDL module.	<i>Input</i> Structure that receives signal values from the input ports defined for the associated HDL module at the time specified by <code>tnow</code> .
<code>tnext</code>	<i>Output, optional</i> Specifies the time at which the HDL simulator schedules the next callback to MATLAB. <code>tnext</code> should be initialized to an empty value ( <code>[]</code> ). If <code>tnext</code> is not later updated, no new entries are added to the simulation schedule.	<i>Output, optional</i> Same as test bench.
<code>output</code>	<i>Input</i> Structure that receives signal values from the output ports defined for the associated HDL module at the time specified by <code>tnow</code> .	<i>Output</i> Structure that forces (by deposit) values onto signals connected to output ports of the associated HDL module.
<code>tnow</code>	<i>Input</i> Receives the simulation time at which the MATLAB function is called. By default, time is represented in seconds. For more information see “Scheduling EDA Simulator Link MQ M-Functions Using the <code>tnext</code> Parameter” on page 9-8.	Same as test bench.
<code>portinfo</code>	<i>Input</i> For the first call to the function only (at the start of the simulation), <code>portinfo</code> receives a structure whose	Same as test bench.

Parameter	Test Bench	Component
	fields describe the ports defined for the associated HDL module. For each port, the <code>portinfo</code> structure passes information such as the port's type, direction, and size.	

If you are using `matlabcp`, initialize the function outputs to empty values at the beginning of the function as in the following example:

```
tnext = [];
oport = struct();
```

---

**Note** When you import VHDL signals, signal names in `iport`, `oport`, and `portinfo` are returned in all capitals.

You can use the port information to create a generic MATLAB function that operates differently depending on the port information supplied at startup. For more information on port data, see “Gaining Access to and Applying Port Information” on page 9-5.

---

## Oscfilter Function Example

The following code gives the definition of the `oscfilter` MATLAB component function.

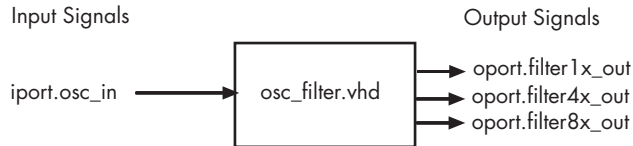
```
function [oport,tnext] = oscfilter(iport, tnow, portinfo)
```

The function name `oscfilter`, differs from the entity name `u_osc_filter`. Therefore, the component function name must be passed in explicitly to the `matlabcp` command that connects the function to the associated HDL instance using the `-mfunc` parameter.

The function definition specifies all required input and output parameters, as listed here:

<code>oport</code>	Forces (by deposit) values onto the signals connected to the entity's output ports, <code>filter1x_out</code> , <code>filter4x_out</code> and <code>filter8x_out</code> .
<code>tnext</code>	Specifies a time value that indicates when the HDL simulator will execute the next callback to the MATLAB function.
<code>iport</code>	Receives HDL signal values from the entity's input port, <code>osc_in</code> .
<code>tnow</code>	Receives the current simulation time.
<code>portinfo</code>	For the first call to the function, receives a structure that describes the ports defined for the entity.

The following figure shows the relationship between the HDL entity's ports and the MATLAB function's `iport` and `oport` parameters.



## Gaining Access to and Applying Port Information

EDA Simulator Link MQ software passes information about the entity or module under test in the `portinfo` structure. The `portinfo` structure is passed as the third argument to the function. It is passed only in the first call to your MATLAB function. You can use the information passed in the `portinfo` structure to validate the entity or module under simulation. Three fields supply the information, as indicated in the next sample. . The content of these fields depends on the type of ports defined for the VHDL entity or Verilog module.

```
portinfo.field1.field2.field3
```

The following table lists possible values for each field and identifies the port types for which the values apply.

**HDL Port Information**

<b>Field...</b>	<b>Can Contain...</b>	<b>Which...</b>	<b>And Applies to...</b>
<i>field1</i>	in	Indicates the port is an input port	All port types
	out	Indicates the port is an output port	All port types
	inout	Indicates the port is a bidirectional port	All port types
	tscale	Indicates the simulator resolution limit in seconds as specified in the HDL simulator	All types
<i>field2</i>	<i>portname</i>	Is the name of the port	All port types
<i>field3</i>	type	Identifies the port type For VHDL: integer, real, time, or enum For Verilog: 'verilog_logic' identifies port types reg, wire, integer	All port types
	right ( <i>VHDL only</i> )	The VHDL RIGHT attribute	VHDL integer, natural, or positive port types
	left ( <i>VHDL only</i> )	The VHDL LEFT attribute	VHDL integer, natural, or positive port types
	size	VHDL: The size of the matrix containing the data Verilog: The size of the bit vector containing the data	All port types
	label	VHDL: A character literal or label Verilog: the string '01ZX'	VHDL: Enumerated types, including predefined types BIT, STD_LOGIC, STD_ULOGIC, BIT_VECTOR, and STD_LOGIC_VECTOR Verilog: All port types

The first call to the MATLAB function has three arguments including the `portinfo` structure. Checking the number of arguments is one way that you can ensure that `portinfo` was passed. For example:

```
if(nargin ==3)
    tscale = portinfo.tscale;
end
```

## Scheduling EDA Simulator Link MQ M-Functions Using the `tnext` Parameter

You can control the callback timing of a MATLAB test bench function by using that function's `tnext` parameter. This parameter passes a time value to the HDL simulator, which gets added to the MATLAB function's simulation schedule. If the function returns a null value (`[]`), no new entries are added to the schedule.

You can set the value of `tnext` to a value of type `double` or `int64`. The following table explains how the interface converts each type of data for use in the HDL simulator environment.

### Time Representations for `tnext` Parameter

If You Specify a...	The Interface...
double value	Converts the value to seconds. For example, the following value converts to the simulation time nearest to 1 nanosecond as a multiple of the current HDL simulator time resolution.  <pre>tnext = 1e-9</pre>
int64 value	Converts to an integer multiple of the current HDL simulator time resolution limit. For example, the following value converts to 100 ticks of the current time resolution.  <pre>tnext=int64(100)</pre>

---

**Note** The `tnext` parameter represents time from the start of the simulation. Therefore, `tnext` should always be greater than `tnow`. If it is less, nothing is scheduled.

---

**Example:** In the Oscillator demo, the `oscfilter` function calculates a time interval at which callbacks should be executed. This interval is calculated on the first call to `oscfilter` and is stored in the variable `fastestrate`. The variable `fastestrate` represents the sample period of the fastest oversampling rate supported by the filter, derived from a base sampling period of 80 ns.

The following assignment statement sets the timing parameter `tnext`, which schedules the next callback to the MATLAB component function, relative to the current simulation time (`tnow`).

```
tnext = tnow + fastestrate;
```

A new value for `tnext` is returned each time the function is called.





# Functions — Alphabetical List

---

# configuremodelsim

---

**Purpose** Configure ModelSim for use with EDA Simulator Link MQ

**Syntax**  
`configuremodelsim`  
`configuremodelsim('PropertyName', 'PropertyValue'...)`

## Description

---

**Note** `configuremodelsim` has been replaced by the guided setup script (`syscheckmq`) for configuring your simulator setup. Although `configuremodelsim` supported for backward compatibility, you should consider using the setup script instead. See “Setting Up the HDL Simulator for Use with the Link Software” on page 1-11.

---

`configuremodelsim` configures ModelSim for use with the MATLAB and Simulink features of EDA Simulator Link MQ. There are two uses for this function:

- To configure ModelSim so that it may access EDA Simulator Link MQ when invoked from outside of MATLAB
- To add Tcl commands to the Tcl startup script that runs every time you invoke ModelSim

When you use `configuremodelsim` without any arguments, the function prompts you to either allow it to find the installed ModelSim executable or have you provide the path to the ModelSim installation you want to use. If you had not configured the software previously (no Tcl DO file exists), `configuremodelsim` creates a new `ModelSimTclFunctionsForMATLAB.tcl` script in the `tcl` directory under the ModelSim installation. If a previous configuration exists, `configuremodelsim` prompts you to decide if you want to replace the existing configuration.

`configuremodelsim('PropertyName', 'PropertyValue'...)` starts an interactive or programmatic script (depending on which property name/value pairs you select) that allows you to customize the ModelSim configuration. See `configuremodelsim` Property Name/Property Value pairs.

After you call this function, ModelSim is ready to use EDA Simulator Link MQ when you invoke ModelSim from outside of MATLAB. You can use Chapter 11, “HDL Simulator Command Extensions — Alphabetical List” from the ModelSim environment to perform the following actions:

- Load instances of VHDL entities or Verilog modules for simulations that use MATLAB or Simulink for verification or cosimulation
- Begin MATLAB test bench or component sessions for loaded instances
- End MATLAB test bench or component sessions

If you have specified Tcl commands to add to the Tcl startup DO file, those commands are now added to the `ModelSimTclFunctionsForMATLAB.tcl` script.

## Usage Considerations

- `configuremodelsim` is intended to be used for setting up ModelSim and MATLAB when you plan to start ModelSim from outside of MATLAB.

If you intend to invoke `vsim` from the MATLAB prompt, then you do not need to use `configuremodelsim`. (MATLAB will find `vsim` if it already appears in the system path, and, if it does not, you can set the `vsimdir` property value of `vsim` in MATLAB to provide the path information.)

In addition, if you are starting ModelSim from outside of MATLAB, you should define your environment with the path to the ModelSim executable before running `configuremodelsim`.

# configuremodelsim

---

---

**Note** The property name/property value options for `vsim` may have been set previously with a call to `configuremodelsim`. To check on current settings, search for and browse through the contents of the file `\tcl\ModelSimTclFunctionsForMATLAB.tcl` in your ModelSim installation path. The `vsim` function overrides any options previously defined by the `configuremodelsim` function.

To start ModelSim from MATLAB with a default configuration previously defined by `configuremodelsim`, issue the command `!vsim` at the MATLAB command prompt.

---

- The `vsimdir` property value of `configuremodelsim` only instructs `configuremodelsim` where to put the Tcl DO file. It does not set up MATLAB workspace for MATLAB invocation of ModelSim (instead, you can perform this setup with the `vsimdir` property value of `vsim`).
- If you are using `configuremodelsim` to add Tcl commands to the Tcl startup DO file, to change the location of the Tcl startup DO file, or to remove the Tcl startup DO file, you can run `configuremodelsim` as many times as you wish. You need to run `configuremodelsim` only once to set the location of the Tcl DO file.

## Property Name/Property Value Pairs

`'action', 'install'`

Instructs `configuremodelsim` to create a new `ModelSimTclFunctionsForMATLAB.tcl` script.

This script is programmatic if you use `'vsimdir'` to specify the ModelSim installation you want to use; otherwise, `configuremodelsim` prompts you for the desired directory.

If a previous configuration exists, `configuremodelsim` prompts you to decide if you want to replace the existing configuration. If you respond yes, the old Tcl DO file is overwritten with a new one.

'action', 'uninstall'

Removes the EDA Simulator Link MQ configuration from the ModelSim startup DO file. The property replaces the contents of ModelSimTclFunctionsForMATLAB.tcl with this single line of text: “# MATLAB and Simulink option was deconfigured.”

This script is programmatic if you use 'vsimdir' to specify the ModelSim installation you want to use; otherwise, configuremodelsim prompts you for the desired directory.

'tclstart', 'tcl\_commands'

Adds one or more Tcl commands to the Tcl DO file that executes during ModelSim startup. Specify a command string or a cell array of command strings that configuremodelsim will append to ModelSimTclFunctionsForMATLAB.tcl.

This script is programmatic only; if you do not also use 'vsimdir' with this property, configuremodelsim uses the first vsim it encounters on the system path and modifies the Tcl DO file (ModelSimTclFunctionsForMATLAB.tcl) in the \tcl directory under this ModelSim installation.

'vsimdir', 'pathname'

Specifies where to put the Tcl script containing EDA Simulator Link MQ Tcl commands. This script is programmatic only; if you do not specify a directory with this property, configuremodelsim uses the first vsim it encounters on the system path and installs the Tcl DO file (ModelSimTclFunctionsForMATLAB.tcl) in the \tcl directory under this ModelSim installation.

## Examples

The following function call starts the interactive installation script that installs EDA Simulator Link MQ commands for use with ModelSim:

```
configuremodelsim
```

Because the property name vsimdir was not supplied, configuremodelsim prompts you for the directory:

# configuremodelsim

---

```
Identify the ModelSim installation to be configured for MATLAB and Simulink

Do you want configuremodelsim to locate installed ModelSim executables [y]/n? n

Please enter the path to your ModelSim executable file (modelsim.exe or vsim.exe):
D:\Applications\Modeltech_6.0e\win32

Modelsim successfully configured to be used with MATLAB and Simulink
```

When `configuremodelsim` is run on an existing configuration, the dialog looks similar to the following sample:

```
Identify the ModelSim installation to be configured for MATLAB and Simulink

Do you want configuremodelsim to locate installed ModelSim executables [y]/n? n

Please enter the path to your ModelSim executable file (modelsim.exe or vsim.exe):
D:\Applications\Modeltech_6.0e\win32

Previous MATLAB startup file found in this installation of ModelSim:
D:\Applications\Modeltech_6.0e\win32\..\tcl\ModelSimTclFunctionsForMATLAB.tcl
Do you want to replace this file [y]/n? y

Modelsim successfully configured to be used with MATLAB and Simulink
```

If you answer no to the prompt for replacing the file, you receive this message instead:

```
Modelsim configuration not updated for MATLAB and Simulink
```

This next example shows adding a Tcl command to the ModelSim configuration, for a customized Tcl DO file:

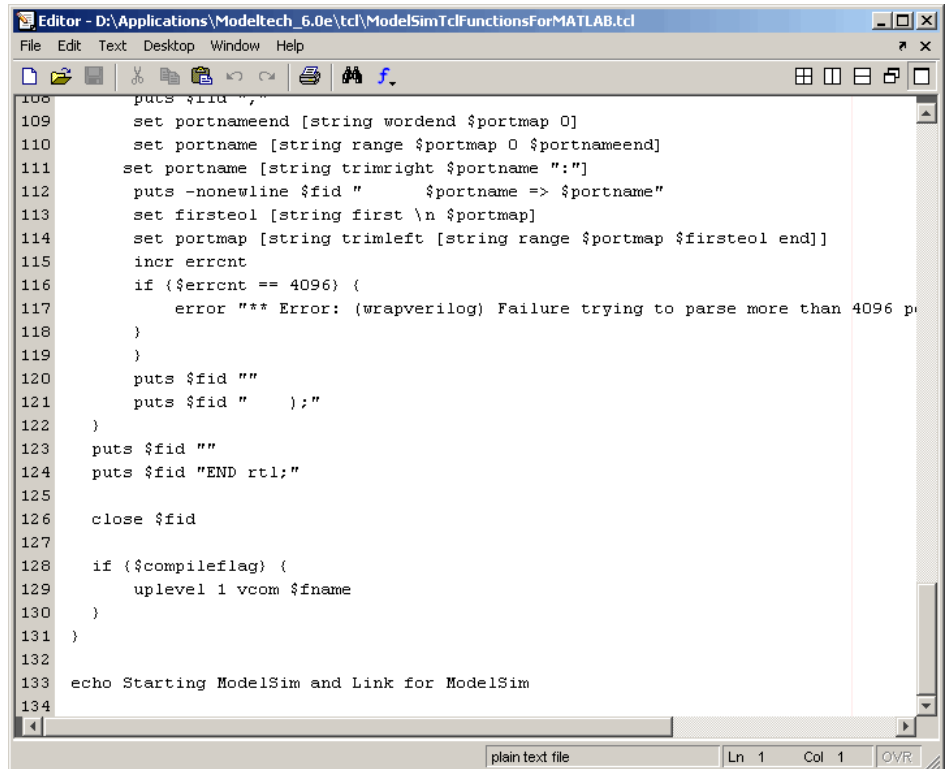
```
configuremodelsim('tclstart','echo Starting ModelSim and EDA Simulator Link MQ')

vsimoptions =

echo Starting ModelSim and EDA Simulator Link MQ
```

Modelsim successfully configured to be used with MATLAB and Simulink

If you now inspect ModelSimTclFunctionsForMATLAB.tcl you will find this last Tcl command appended to the file, as shown in the following graphic.



```
Editor - D:\Applications\Modeltech_6.0e\tcl\ModelSimTclFunctionsForMATLAB.tcl
File Edit Text Desktop Window Help
108 puts $fid ","
109 set portnameend [string wordend $portmap 0]
110 set portname [string range $portmap 0 $portnameend]
111 set portname [string trimright $portname ":"]
112 puts -nonewline $fid "      $portname => $portname"
113 set firsteol [string first \n $portmap]
114 set portmap [string trimleft [string range $portmap $firsteol end]]
115 incr errcnt
116 if {$errcnt == 4096} {
117     error "*** Error: (wrapverilog) Failure trying to parse more than 4096 p
118 }
119 }
120 puts $fid ""
121 puts $fid "    );"
122 }
123 puts $fid ""
124 puts $fid "END rtl;"
125
126 close $fid
127
128 if {$compileflag} {
129     uplevel 1 vcom $fname
130 }
131 }
132
133 echo Starting ModelSim and Link for ModelSim
134
```

The following example shows removing the EDA Simulator Link MQ configuration from ModelSim:

```
configuremodelsim ('action', 'uninstall')
```

Identify the Modelsim installation to be deconfigured for MATLAB and Simulink

# configuremodelsim

---

Do you want configuremodelsim to locate installed Modelsim executables [y]/n? n

Please enter the path to your Modelsim executable file (modelsim.exe or vsim.exe):

D:\Applications\Modeltech\_6.0e\win32

Previous MATLAB startup file found in this installation of Modelsim:

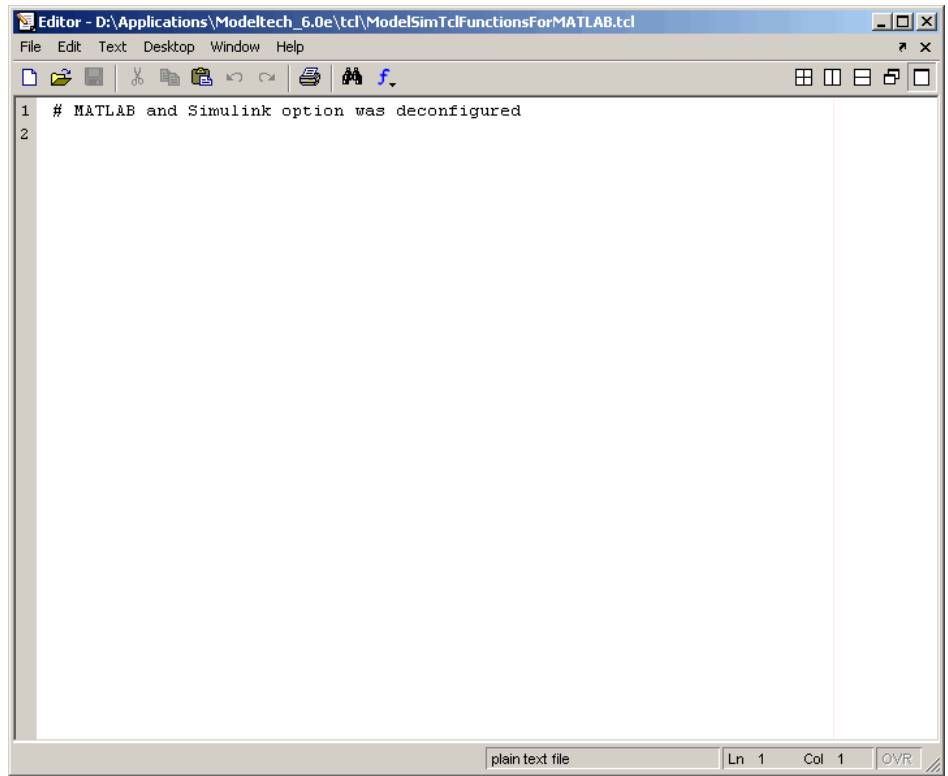
D:\Applications\Modeltech\_6.0e\win32...\tcl\ModelSimTclFunctionsForMATLAB.tcl

Do you want to replace this file (required for deconfiguration) [y]/n? y

Modelsim successfully deconfigured

If you now inspect ModelSimTclFunctionsForMATLAB.tcl you will find that the contents of the file have been removed.





The image shows a screenshot of a text editor window. The title bar reads "Editor - D:\Applications\Modeltech\_6.0e\tcl\ModelSimTclFunctionsForMATLAB.tcl". The menu bar includes "File", "Edit", "Text", "Desktop", "Window", and "Help". The toolbar contains icons for file operations and editing. The main text area contains two lines of code:

```
1 # MATLAB and Simulink option was deconfigured  
2
```

The status bar at the bottom indicates "plain text file", "Ln 1", "Col 1", and "OVR".

# dec2mvl

---

**Purpose** Convert decimal integer to binary string

**Syntax** `dec2mvl(d)`  
`dec2mvl(d,n)`

**Description** `dec2mvl(d)` returns the binary representation of `d` as a multivalued logic string. `d` must be an integer smaller than  $2^{52}$ .  
`dec2mvl(d,n)` produces a binary representation with at least `n` bits.

**Examples** The following function call returns the string '10111':

```
dec2mvl(23)
```

The following function call returns the string '01001':

```
dec2mvl(-23)
```

The following function call returns the string '11101001':

```
dec2mvl(-23,8)
```

**See Also** `mvl2dec`

**Purpose** Control the MATLAB server that supports interactions with HDL simulators

**Syntax**

```
hdldaemon
hdldaemon('PropertyName', 'PropertyValue'...)
hdldaemon('status')
hdldaemon('kill')
```

**Description** Use hdldaemon to activate servers, check link status, and shutdown servers.

### **Server Activation**

hdldaemon starts the MATLAB server component of the EDA Simulator Link MQ software with the following default settings:

- Shared memory communication enabled
- Time resolution for the MATLAB simulation function output ports set to scaled (type double)

You can use TCP/IP on a single system (one that runs both MATLAB and the HDL simulator). However, consider using shared memory communication when your application configuration consists of a single system. This approach can result in increased performance.

Only one hdldaemon per MATLAB session can be running at any given time.

### **Matching Communication Modes and Socket Ports**

The communication mode that you specify (shared memory or TCP/IP sockets) must match what you specify for the communication mode when you issue the matlabcp, matlabbt, or matlabbtbeval command in the HDL simulator.

In addition, if you specify TCP/IP socket mode, you must also identify a socket port to be used for establishing links. You can choose and then specify a socket port yourself, or you can use an option that instructs the operating system to identify an available socket port for you. Regardless

of how you identify the socket port, the socket you specify with the HDL simulator must match the socket being used by the server.

For more information on modes of communication, see “Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8.

For more information on establishing the HDL simulator end of the communication link, see “Start hdldaemon to Provide Connection to HDL Simulator” on page 2-23.

`hdldaemon('PropertyName', 'PropertyValue'...)` starts the EDA Simulator Link MQ MATLAB server component with property-value pair settings that specify the communication mode for the link between MATLAB and the HDL simulator, the resolution of `now` (the current time argument passed by the associated M-function), and, optionally, a Tcl command to be executed immediately in the HDL simulator. See `hdldaemon` Property Name/Property Value pairs for details.

## Link Status

`hdldaemon('status')` returns the following message indicating that a link (connection) exists between MATLAB and the HDL simulator:

```
HLDaemon socket server is running on port 4449 with 0 connections
```

You can also use this function to check on the communication mode being used, the number of existing connections, and the interprocess communication identifier (`ipc_id`) being used for a link by assigning the return value of `hdldaemon` to a variable. The `ipc_id` identifies a port number for TCP/IP socket links or the file system name for a shared memory communication channel. For example:

```
x=hdldaemon('status')
x =
    comm: 'sockets'
connections: 0
ipc_id: '4449'
```

This function call indicates that the server is using TCP/IP socket communication with socket port 4449 and is running with no active

HDL simulator clients. If you are using a shared memory link, set the value of `comm` to 'shared memory' and make the value of `ipc_id` a file system name for the shared memory communication channel. For example:

```
x=hdldaemon('status')
HDLDaemon shared memory server is running with 0 connections
x =
    comm: 'shared memory'
 connections: 0
 ipc_id: [1x45 char]
```

## Server Shutdown

`hdldaemon('kill')` shuts down the MATLAB server without shutting down MATLAB.

`hdldaemon` accepts the following valid property name/property value pairs:

'socket', `tcp_spec`  
Specifies the TCP/IP socket mode of communication for the link between MATLAB and the HDL simulator. If you omit this argument, the server uses the shared memory mode of communication.

---

**Note** You *must* use TCP/IP socket communication when your application configuration consists of multiple computing systems.

---

The `tcp_spec` can be a TCP/IP port number, TCP/IP port alias or service name, or the value zero, indicating that the port is to be assigned by the operating system. See “Specifying TCP/IP Values” on page 7-15 for some valid `tcp_spec` examples.

## Property Name/ Property Value Pairs

For more information on choosing TCP/IP socket ports, see “Choosing TCP/IP Socket Ports” on page 7-13.

---

**Note** If you specify the operating system option ('0' or 0), use `hdldaemon('status')` to acquire the assigned socket port number. You must specify this port number when you issue a link request with the `matlabtb` or `matlabtbeval` command in the HDL simulator.

---

`'time', 'sec' | 'time', 'int64'`

Specifies the time resolution for MATLAB function ports and simulation times (tnow).

Specify...	For...
<code>'time' 'sec'</code> (default)	A double value that is scaled to seconds based on the current HDL simulation resolution
<code>'time' 'int64'</code>	64-bit integer representing the number of simulation steps

If you omit this argument, the server uses scaled resolution time.

`'tclcmd', 'command'`

Passes a TCL command string, to be executed in the HDL simulator, from MATLAB to the HDL simulator. You may use a compound command and separate the commands with semicolons.

---

**Note** The Tcl command string you specify cannot include commands that load an HDL simulator project or modify simulator state. For example, the string cannot include commands such as `run`, `stop`, or `reset`.

---

**Caution** Do not call `hdldaemon(tclcmd, 'tclcmd')` inside of a `matlabtb` or `matlabcp` function. You will get a race condition and the simulator will hang.

`'quiet', 'true'`

Suppresses printing messages to the standard queue. Errors still appear.

The following table provides guidelines on when and how to specify property name/property value pairs.

If Your Application Is to...	Do the Following...
Operate in shared memory mode	Omit the <code>'socket'</code> , <code>tcp_spec</code> property name/property value pair. The interface operates in shared memory mode by default. You should use shared memory mode if your application configuration consists of a single system and uses a single communication channel.
Operate in TCP/IP socket mode, using a specific TCP/IP socket port	Specify the <code>'socket'</code> , <code>tcp_spec</code> property name and value pair. The <code>tcp_spec</code> can be a socket port number or service name. Examples of valid port specifications include <code>'4449'</code> , <code>4449</code> , and <code>MATLAB Service</code> . For information on choosing a TCP/IP socket port, see “Choosing TCP/IP Socket Ports” on page 7-13.

# hdldaemon

---

If Your Application Is to...	Do the Following...
Operate in TCP/IP socket mode, using a TCP/IP socket that the operating system identifies as available	Specify 'socket', 0 or 'socket', '0'.
Return time values in seconds (type double)	Specify 'time', 'sec' or omit the parameter. This is the default time value resolution.
Return 64-bit time values (type int64)	Specify 'time', 'int64'.
Execute Tcl command immediately upon simulator connection	Specify the 'tclcmd', 'command' property name and value pair. Command must be a valid Tcl command but cannot include commands that load an HDL simulator project or modify the simulator state.
Suppress server shutdown message when using hdldaemon to get an unused socket number (message can appear confusing)	Specify 'quiet', 'true'.

## Examples

The following function call starts the MATLAB server with shared memory communication enabled and a 64-bit time resolution format for the MATLAB function's `tnow` parameter:

```
hdldaemon('time', 'int64')
```

The following function call starts the MATLAB server with TCP/IP socket communication enabled on socket port 4449. Although you do not need to use TCP/IP socket communication on a single-computer application, you can use that mode of communication locally. Because the function does not specify a time resolution, the HDL simulator



applies the default, scaled simulation time resolution to the MATLAB function's output ports:

```
hdldaemon('socket', 4449)
```

The following function call starts the MATLAB server with TCP/IP socket communication enabled on port 4449. This call also specifies a 64-bit time resolution format:

```
hdldaemon('socket', 4449, 'time', 'int64')
```

You also can start the server from a script. Consider the following function call sequence:

```
dstat = hdldaemon('socket', 0)
portnum = dstat.ipc_id
```

The first call to `hdldaemon` specifies that the server use TCP/IP communication with a port number that the operating system identifies and returns connection status information, including the assigned port number, to `dstat`. The statement on the second line assigns the socket port number to `portnum` for future reference.

The following function call causes the string `This is a test` to be displayed at the HDL simulator prompt:

```
hdldaemon('tclcmd','puts "This is a test"')
```

The following is an example of a compound Tcl command used with `hdldaemon`:

```
hdldaemon('tclcmd','{force filter2d_v.clk_enable 1
-after 0ns;
force filter2d_v.reset 1 -after 0 ns 0 -after 1 ns;
puts {Running Simulink Cosimulation block};
puts [clock format [clock seconds]]}')'
```

# mvl2dec

---

**Purpose** Convert multivalued logic to decimal

**Syntax** `mvl2dec('mv_logic_string')`  
`mvl2dec('mv_logic_string', signed)`

**Description** `mvl2dec('mv_logic_string')` converts a multivalued logic string to a positive decimal. If *mv\_logic\_string* contains any character other than '0' or '1', NaN is returned. *mv\_logic\_string* must be a vector.

`mvl2dec('mv_logic_string', signed)` converts a multivalued logic string to a positive or a negative decimal. If *signed* is true, this function assumes the first character *mv\_logic\_string*(1) to be a signed bit of a 2s complement number. If *signed* is missing or false, the multivalued logic string becomes a positive decimal.

**Examples** The following function call returns the decimal value 23:

```
mvl2dec('010111')
```

The following function call returns NaN:

```
mvl2dec('xxxxxx')
```

The following function call returns the decimal value -9:

```
mvl2dec('10111', true)
```

**See Also** `dec2mvl`

**Purpose** Block cosimulation until HDL simulator is ready for simulation

**Syntax**

```
pingHdlSim(timeout)
pingHdlSim(timeout, 'portnumber')
pingHdlSim(timeout, 'portnumber', 'hostname')
```

**Description** pingHdlSim(timeout) blocks cosimulation by not returning until the HDL server loads or until the specified time-out occurs. pingHdlSim returns the process ID of the HDL simulator or -1 if a time-out occurs. You must enter a time-out value.

You may find this function useful if you are trying to automate a cosimulation and need to know that the HDL server has loaded before your script continues the simulation.

pingHdlSim(timeout, 'portnumber') tries to connect to the local host on port *portnumber* and times out after *timeout* seconds you specify.

pingHdlSim(timeout, 'portnumber', 'hostname') tries to connect to the host *hostname* on port *portname*. It times out after *timeout* seconds you specify.

**Examples** The following function call blocks further cosimulation until the HDL server loads or until 30 seconds have passed:

```
pingHdlSim(30)
```

If the server loads within 30 seconds, pingHdlSim returns the process ID. If it does not, pingHdlSim returns -1.

The following function call blocks further cosimulation on port 5678 until the HDL server loads or until 20 seconds have passed:

```
pingHdlSim(20, '5678')
```

The following function call blocks further cosimulation on port 5678 on host name msuser until the HDL server loads or until 20 seconds pass:

```
pingHdlSim(20, '5678', 'msuser')
```

# tclHdlSim

---

**Purpose** Execute Tcl command in HDL simulator

**Syntax**

```
tclHdlSim(tclCmd)
tclHdlSim(tclCmd, 'portNumber')
tclHdlSim(tclCmd, 'portnumber', 'hostname')
```

**Description**

tclHdlSim(tclCmd) executes a Tcl command on the HDL simulator using a shared connection.

tclHdlSim(tclCmd, 'portNumber') executes a Tcl command on the HDL simulator by connecting to the local host on port *portNumber*.

tclHdlSim(tclCmd, 'portnumber', 'hostname') executes a Tcl command on the HDL simulator by connecting to the host *hostname* on port *portname*.

The HDL simulator must be connected to MATLAB using the EDA Simulator Link MQ software for this function to work (see “Starting the HDL Simulator” on page 1-22. If you start from within MATLAB, you must use vsimmatlab.).

**Examples**

The following function call displays a message in the HDL simulator command window using port 5678 on host name msuser:

```
tclHdlSim('puts "Done"', '5678', 'msuser')
```

**See Also** hdldaemon, vsim

---

<b>Purpose</b>	Start and configure ModelSim for use with EDA Simulator Link MQ
<b>Syntax</b>	<code>vsim('PropertyName', 'PropertyValue'...)</code>
<b>Description</b>	<p><code>vsim('PropertyName', 'PropertyValue'...)</code> starts and configures the ModelSim simulator (<code>vsim</code>) for use with the MATLAB and Simulink features of EDA Simulator Link MQ. The first directory in ModelSim matches your MATLAB current directory.</p> <p>After you call this function, you can use EDA Simulator Link MQ command extensions to perform the following actions:</p> <ul style="list-style-type: none"><li>• Load instances of VHDL entities or Verilog modules for simulations that use MATLAB for verification</li><li>• Load instances of VHDL entities or Verilog modules for simulations that use Simulink for cosimulation</li></ul> <p>The property name/property value pair settings allow you to customize the Tcl commands used to start ModelSim, the <code>vsim</code> executable to be used, the path and name of the DO file that stores the start commands, and for Simulink applications, details about the mode of communication to be used by the applications.</p>
	<hr/> <p><b>Tip</b> Use <code>pingHdlSim</code> to add a pause between the call to <code>vsim</code> and the call to actually run the simulation when you are attempting to automate the cosimulation.</p> <hr/>
<b>Property Name/Property Value Pairs</b>	<p><code>'libdir', 'directory'</code></p> <p>Specifies the directory containing MATLAB library files. This property creates an entry in the startup Tcl file that points to the directory with the libraries needed for ModelSim to communicate with MATLAB when ModelSim runs on a machine that does not have MATLAB.</p>

'libfile', 'library\_file\_name'

Specifies a particular library file. This value defaults to the version of the library file that was built using the same compiler that MATLAB itself uses. If the HDL simulator links other libraries, including SystemC libraries, that were built using a compiler supplied with the HDL simulator, you can specify an alternate library file with this property. See “Using the EDA Simulator Link MQ Libraries” on page 1-17 for versions of the library built using other compilers.

'pingTimeout', 'seconds'

Time to wait, in seconds, for the HDL simulator to start. Specify 0 (the default) to immediately return without waiting.

'rundir', 'dirname'

Specifies where to run ModelSim. By default, the function uses the current working directory.

The following conditions apply to this name/value pair:

- If the value of `dirname` is “TEMPDIR”, the function creates a temporary directory in which it runs ModelSim.
- If you specify `dirname` and the directory does *not* exist, you will get an error.

'socketsimulink', 'tcp\_spec'

Specifies TCP/IP socket communication for links between ModelSim and Simulink. For TCP/IP socket communication on a single computing system, the `tcp_spec` can consist of just a TCP/IP port number or service name. If you are setting up communication between computing systems, you must also specify the name or Internet address of the remote host. See “Specifying TCP/IP Values” on page 7-15 for some valid `tcp_spec` examples.

For more information on choosing TCP/IP socket ports, see “Choosing TCP/IP Socket Ports” on page 7-13

If ModelSim and Simulink run on the same computing system, you have the option of using shared memory for communication. Shared memory is the default mode of communication and takes effect if you do not specify `-socket <tcp-spec>` on the command line.

---

**Note** The function applies the communication mode specified by this property to all invocations of Simulink from ModelSim.

---

`'startms', ['yes' | 'no']`

Determines whether ModelSim will launch from `vsim`. This property defaults to `yes`, which launches ModelSim and creates a startup Tcl file. If `startms` is set to `no`, ModelSim does not launch, but the HDL simulator still creates a startup Tcl file.

This startup Tcl file contains pointers to MATLAB libraries. To run ModelSim on a machine without MATLAB, copy the startup Tcl file and MATLAB library files to the remote machine and start ModelSim manually. See “Using the EDA Simulator Link MQ Libraries” on page 1-17.

`'startupfile', 'pathname'`

Each invocation of `vsim` creates a Tcl script that, when executed, compiles and launches the HDL simulator. By default, this function generates the filename of `compile_and_launch.tcl` in the directory specified by `rundir`. With this property, you can specify the name and location of the generated Tcl script. If the file name already exists, that file’s contents are overwritten. You can edit and use the generated file in a regular shell outside of MATLAB. For example:

```
sh> vsim -gui -do compile_and_launch.tcl
```

'tclstart', 'tcl\_commands'

Specifies one or more Tcl commands to execute after ModelSim launches. Specify a command string or a cell array of command strings.

'vsimdir', 'pathname'

Specifies the path name to the ModelSim simulator executable (`vsim.exe`) to be started. By default, the function uses the first version of `vsim.exe` that it finds on the system path (defined by the `path` variable). Use this option to start different versions of the ModelSim simulator or if the version of the simulator you want to run does not reside on the system path.

## Examples

The following function call sequence changes the directory location to `VHDLproj` and then calls the function `vsim`. Because the call to `vsim` omits the `'vsimdir'` and `'startupfile'` properties, `vsim` uses the default `vsim` executable and creates a temporary DO file in a temporary directory. The `'tclstart'` property specifies a Tcl command that loads an instance of a VHDL entity for MATLAB verification:

- The `vsimmatlab` command loads an instance of the VHDL entity `parse` in the library `work` for MATLAB verification.
- The `matlabtb` command begins the test bench session for an instance of entity `parse`, using TCP/IP socket communication on port 4449 and a test bench timing value of 10 ns.

```
cd VHDLproj % Change directory to ModelSim project directory
vsim('tclstart','vsimmatlab work.parse; matlabtb parse 10 ns -socket 4449')
```

The following function call sequence changes the directory location to `VHDLproj` and then calls the function `vsim`.

- Because the call to `vsim` omits the `'vsimdir'` and `'startupfile'` properties, `vsim` uses the default `vsim` executable and creates a DO file in a temporary directory.



- The 'tclstart' property specifies a Tcl command that loads the VHDL entity parse in the library work for cosimulation between vsim and Simulink.
- The 'socketsimulink' property specifies that TCP/IP socket communication on the same computer is to be used for links between Simulink and ModelSim, using socket port 4449.

```
cd VHDLproj % Change directory to ModelSim project directory
vsim('tclstart','vsimulink work.parse','socketsimulink','4449')
```



# HDL Simulator Command Extensions — Alphabetical List

---

# matlabcp

---

**Purpose** Associate MATLAB component function with instantiated HDL design

**Syntax**

```
matlabcp <instance>  
[<time-specs>]  
[-socket <tcp-spec>]  
[-rising <port>[,<port>...]]  
[-falling <port> [,<port>,...]]  
[-sensitivity <port>[,<port>,...]]  
[-mfunc <name>]  
[-use_instance_obj]  
[-argument]
```

**Arguments** <instance>  
Specifies an instance of an HDL design that is associated with a MATLAB function. By default, `matlabcp` associates the instance to a MATLAB function that has the same name as the instance. For example, if the instance is `myfirfilter`, `matlabcp` associates the instance with the MATLAB function `myfirfilter` (note that hierarchy names are ignored; for example, if your instance name is `top.myfirfilter`, `matlabcp` would associate only `myfirfilter` with the MATLAB function). Alternatively, you can specify a different MATLAB function with `-mfunc`.

---

**Note** Do not specify an instance of an HDL module that has already been associated with a MATLAB M-function (via `matlabcp` or `matlabtb`). If you do, the new association overwrites the existing one.

---

<time-specs>  
Specifies a combination of time specifications consisting of any or all of the following:

<timen>,...

Specifies one or more discrete time values at which the HDL simulator calls the specified MATLAB function. Each time value is relative to the current simulation time. Even if you do not specify a time, the HDL simulator calls the MATLAB function once at the start of the simulation. Separate multiple time values by a space. For example:

```
matlabtb vlogtestbench_top 10 ns, 10 ms, 10 sec
```

The MATLAB function executes when time equals 0 and then 10 nanoseconds, 10 milliseconds, and 10 seconds from time zero.

---

**Note** For time-based parameters, you can specify any standard time units (ns, us, and so on). If you do not specify units, the command treats the time value as a value of HDL simulation ticks.

---

-repeat <time>

Specifies that the HDL simulator calls the MATLAB function repeatedly based on the specified <timen>, ... pattern. The time values are relative to the value of tnow at the time the HDL simulator first calls the MATLAB function.

-cancel <time>

Specifies a time at which the specified MATLAB function stops executing. The time value is relative to the value of tnow at the time the HDL simulator first calls the MATLAB function. If you do not specify a cancel time, the application calls the MATLAB function until you finish the simulation, quit the session, or issue a nomatlabtb call.

---

**Note** The -cancel option works only with the <time-specs> arguments. It does not affect any of the other scheduling arguments for matlabcp.

---

---

**Note** Place time specifications after the `matlabcp` instance and before any additional command arguments; otherwise the time specifications are ignored.

---

All time specifications for the `matlabcp` functions appear as a number and, optionally, a time unit:

- fs (femtoseconds)
- ps (picoseconds)
- ns (nanoseconds)
- us (microseconds)
- ms (milliseconds)
- sec (seconds)
- no units (tick)

`-socket <tcp_spec>`

Specifies TCP/IP socket communication for the link between the HDL simulator and MATLAB. When you provide TCP/IP information for `matlabcp`, you can choose a TCP/IP port number or TCP/IP port alias or service name for the `<tcp_spec>` parameter. If you are setting up communication between computers, you must also specify the name or Internet address of the remote host that is running the MATLAB server (`hdldaemon`). See “Specifying TCP/IP Values” on page 7-15 for some valid `tcp_spec` examples.

For more information on choosing TCP/IP socket ports, see “Choosing TCP/IP Socket Ports” on page 7-13.

If you run the HDL simulator and MATLAB on the same computer, you have the option of using shared memory for communication. Shared memory is the default mode of communication and takes effect if you do not specify `-socket <tcp_spec>` on the command line.

---

**Note** The communication mode that you specify with the `matlabcp` command must match what you specify for the communication mode when you issue the `hdldaemon` command in MATLAB.

---

For more information on modes of communication, see “Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8. For more information on establishing the MATLAB end of the communication link, see “Start `hdldaemon` to Provide Connection to HDL Simulator” on page 2-23.

`-rising <signal>[, <signal>...]`

Indicates that the application calls the specified MATLAB function on the rising edge (transition from '0' to '1') of any of the specified signals. Specify `-rising` with the path names of one or more signals defined as a logic type (`STD_LOGIC`, `BIT`, `X01`, and so on).

For determining signal transition in:

- Verilog: Z and X are read as 0
- VHDL: Z and X will not create a rate transition

Rate transitions are only from 0 -> 1 and 1-> 0. Specify `-rising` with the path names of one or more signals defined as a logic type.

---

**Note** When specifying signals with the `-rising`, `-falling`, and `-sensitivity` options, specify them in full path name format. If you do not specify a full path name, the command applies the HDL simulator rules to resolve signal specifications.

---

`-falling <signal>[, <signal>...]`

Indicates that the application calls the specified MATLAB function whenever any of the specified signals experiences a falling edge—changes from '1' to '0'. Specify `-falling` with the path names of one or more signals defined as a logic type (STD\_LOGIC, BIT, X01, and so on).

---

**Note** When specifying signals with the `-rising`, `-falling`, and `-sensitivity` options, specify them in full path name format. If you do not specify a full path name, the command applies the HDL simulator rules to resolve signal specifications.

---

`-sensitivity <signal>[, <signal>...]`

Indicates that the application calls the specified MATLAB function whenever any of the specified signals changes state. Specify `-sensitivity` with the path names of one or more signals. Signals of any type can appear in the sensitivity list and can be positioned at any level in the HDL model hierarchy.

---

**Note** When specifying signals with the `-rising`, `-falling`, and `-sensitivity` options, specify them in full path name format. If you do not specify a full path name, the command applies the HDL simulator rules to resolve signal specifications.

---

`-mfunc <name>`

The name of the MATLAB function that is associated with the HDL module instance you specify for `instance`. By default, the EDA Simulator Link MQ software invokes a MATLAB function that has the same name as the specified HDL instance. Thus, if the names are the same, you can omit the `-mfunc` option. If the names are not the same, use this argument when you call `matlabcp`. If you omit this argument and `matlabcp` does not find



a MATLAB function with the same name, the command generates an error message.

**-use\_instance\_obj** (*Beta Feature*)

Instructs the function specified with the argument `-mfunc` to use an HDL instance object passed by EDA Simulator Link MQ to the M-function. You include the `-use_instance_obj` argument with `matlabcp` in the following format:

```
matlabcp modelname -mfunc funcname -use_instance_obj
```

When you call `matlabcp` with the `use_instance_obj` argument, the M-function has the following signature:

```
function MyFunctionName(hdl_instance_obj)
```

The HDL instance object (`hdl_instance_obj`) has the fields shown in the following table.

Field	Read/Write Access	Description
<code>tnext</code>	Write only	Used to schedule a callback during the set time value. This field is equivalent to old <code>tnext</code> . For example:  <pre>hdl_instance_obj.tnext = hdl_instance_obj.tnow + 5e-9</pre> will schedule a callback at time equals 5 nanoseconds from <code>tnow</code> .
<code>userdata</code>	Read/Write	Stores state variables of the current <code>matlabcp</code> instance. You can retrieve the variables the next time the callback of this instance is scheduled.

Field	Read/Write Access	Description
simstatus	Read only	<p>Stores the status of the HDL simulator. The EDA Simulator Link MQ software sets this field to 'Init' during the first callback for this particular instance and to 'Running' thereafter. simstatus is a read-only property.</p> <pre>&gt;&gt; hdl_instance_obj.simstatus  ans=     Init</pre>
instance	Read only	<p>Stores the full path of the Verilog/VHDL instance associated with the callback. instance is a read-only property. The value of this field equals that of the module instance specified with the function call. For example:</p> <p>In the HDL simulator:</p> <pre>hdlsim&gt; matlabcp osc_top -mfunc oscfilter use_instance_obj</pre> <p>In MATLAB:</p> <pre>&gt;&gt; hdl_instance_obj.instance  ans=     osc_top</pre>

Field	Read/Write Access	Description
argument	Read only	<p>Stores the argument set by the <code>-argument</code> option of <code>matlabcp</code>. For example:</p> <pre>matlabtb osc_top -mfunc oscfilter -use_instance_obj -argument foo</pre> <p>The link software supports the <code>-argument</code> option only when it is used with <code>-use_instance_obj</code>, otherwise the argument is ignored. <code>argument</code> is a read-only property.</p> <pre>&gt;&gt;hdl_instance_obj.argument  ans=     foo</pre>
portinfo	Read only	<p>Stores information about the VHDL and Verilog ports associated with this instance. <code>portinfo</code> is a read-only property, which has a field structure that describes the ports defined for the associated HDL module. For each port, the <code>portinfo</code> structure passes information such as the port's type, direction, and size. For more information on port data, see "Gaining Access to and Applying Port Information" on page 9-5.</p> <pre>hdl_instance_obj.portinfo.field1.field2.field3</pre> <hr/> <p><b>Note</b> When you use <code>use_instance_obj</code>, you access <code>tscale</code> through the HDL instance object. If you do not use <code>use_instance_obj</code>, you can still access <code>tscale</code> through <code>portinfo</code>.</p> <hr/>

Field	Read/Write Access	Description
tscal	Read only	<p>Stores the resolution limit (tick) in seconds of the HDL simulator. tscal is a read-only property.</p> <pre>&gt;&gt; hdl_instance_obj.tscal</pre> <pre>ans = 1.0000e-009</pre> <hr/> <p><b>Note</b> When you use use_instance_obj, you access tscal through the HDL instance object. If you do not use use_instance_obj, you can still access tscal through portinfo.</p>
tnow	Read only	<p>Stores the current time. tnow is a read-only property.</p> <pre>hdl_instance_obj.tnext = hdl_instance_obj.tnow + faststrate;</pre>
portvalues	Read/Write	<p>Stores the current values of and sets new values for the output and input ports for a matlabcp instance. For example:</p> <pre>&gt;&gt; hdl_instance_obj.portvalues</pre> <pre>ans = Read Only Input ports:   clk_enable: []   clk: []   reset: [] Read/Write Output ports:   sine_out: [22x1 char]</pre>
linkmode	Read only	<p>Stores the status of the callback. The EDA Simulator Link MQ software sets this field to 'testbench' if the callback is</p>

Field	Read/Write Access	Description
		<p>associated with <code>matlabtb</code> and 'component' if the callback is associated with <code>matlabcp</code>. <code>linkmode</code> is a read-only property.</p> <pre>&gt;&gt; hdl_instance_obj.linkmode  ans=     component</pre>

-argument (*Beta Feature*)

Used to pass user-defined arguments from the `matlabcp` invocation on the HDL side to the M-function callbacks. Supported with `-use_instance_obj` only. See the field listing under the `-use_instance_obj` property.

## Description

The `matlabcp` command has the following characteristics:

- Starts the HDL simulator client component of the EDA Simulator Link MQ software.
- Associates a specified instance of an HDL design created in the HDL simulator with a MATLAB function.
- Creates a process that schedules invocations of the specified MATLAB function.
- Cancels any pending events scheduled by a previous `matlabcp` command that specified the same instance. For example, if you issue the command `matlabcp` for instance `foo`, all previously scheduled events initiated by `matlabcp` on `foo` are canceled.

MATLAB component functions simulate the behavior of modules in the HDL model. A stub module (providing port definitions only) in the HDL model passes its input signals to the MATLAB component function. The MATLAB component processes this data and returns the results to the outputs of the stub module. A MATLAB component typically provides

some functionality (such as a filter) that is not yet implemented in the HDL code. See Chapter 3, “Replacing an HDL Component with a MATLAB Component Function”.

---

**Note** For the HDL simulator to establish a communication link with MATLAB, the MATLAB server, `hdldaemon`, must be running with the same communication mode and, if appropriate, the same TCP/IP socket port as you specify with the `matlabcp` command.

---

## Examples

The following examples demonstrate some ways you might use the `matlabcp` function.

### Using `matlabcp` with the `-mfunc` option to Associate an HDL Component with a MATLAB M-Function of a Different Name

This example explicitly associates the Verilog module `vlogtestbench_top.u_matlab_component` with the MATLAB function `vlogmatlabc` using the `-mfunc` option. The `'-socket'` option specifies using socket communication on port 4449.

```
matlabcp vlogtestbench_top.u_matlab_component -mfunc vlogmatlabc -socket 4449
```

### Using `matlabcp` with Explicit Times and the `-cancel` Option

This example implicitly associates the Verilog module, `vtstbench_top`, with the MATLAB function `vlogtestbench_top`, and includes explicit times with the `-cancel` option.

```
matlabcp vlogtestbench_top 1e6 fs 3 2e3 ps -repeat 3 ns -cancel 7ns
```

### Using `matlabcp` with Rising and Falling Edges

This example implicitly associates the Verilog module, `vlogtestbench_top`, with the MATLAB function `vlogtestbench_top`, and also uses rising and falling edges.

```
hdlsim> matlabcp vlogtestbench_top 1 2 3 4 5 6 7 -rising outclk3
```

```
-falling u_matlab_component/inoutclk
```

## Using matlabcp and the HDL Instance Object (*Beta Feature*)

In this example, the HDL simulator makes repeated calls to `matlabcp` to bind multiple HDL instances to the same M-function. Each call contains `-argument` as a constructor parameter to differentiate behavior.

```
hdlsim> matlabcp u1_filter1x -mfunc osc_filter -use_instance_obj -argument oversample=1
hdlsim> matlabcp u1_filter8x -mfunc osc_filter -use_instance_obj -argument oversample=8
hdlsim> matlabcp u2_filter8x -mfunc osc_filter -use_instance_obj -argument oversample=8
```

The M-function callback, `osc_filter.m`, sets up user instance-based state using `obj.userdata`, queries port and simulation context using other `obj` fields, and uses the passed in `obj.argument` to differentiate behavior.

```
function osc_filter(obj)
if (strcmp(obj.simstatus,'Init'))
    ud = struct('Nbits', 22, 'Norder', 31, 'clockperiod', 80e-9, 'phase', 1));
    eval(obj.argument);
    if (~exist('oversample','var'))
        error('HdlLinkDemo:UseInstanceObj:BadCtorArg', ...
            'Bad constructor arg to osc_filter callback. Expecting ''oversample=value''.');
    end
    ud.oversample      = oversample;
    ud.oversampleperiod = ud.clockperiod/ud.oversample;
    ud.InDelayLine     = zeros(1,ud.Norder+1);

    centerfreq = 70/256;
    passband   = [centerfreq-0.01, centerfreq+0.01];
    b          = fir1((ud.Norder+1)*ud.oversample-1, passband./ud.oversample);
    ud.Hresp   = ud.oversample .* b;

    obj.userdata = ud;
end

...
```

**Purpose** Schedule MATLAB test bench session for instantiated HDL module

**Syntax**

```
matlabtb <instance>  
[<time-specs>]  
[-socket <tcp-spec>]  
[-rising <port>[,<port>...]]  
[-falling <port> [,<port>,...]]  
[-sensitivity <port>[,<port>,...]]  
[-mfunc <name>]  
[-use_instance_obj]  
[-argument]
```

**Arguments**

<instance>  
Specifies the instance of an HDL module that the EDA Simulator Link MQ software associates with a MATLAB test bench function. By default, `matlabtb` associates the instance with a MATLAB function that has the same name as the instance. For example, if the instance is `myfirfilter`, `matlabtb` associates the instance with the MATLAB function `myfirfilter` (note that hierarchy names are ignored; for example, if your instance name is `top.myfirfilter`, `matlabtb` would associate only `myfirfilter` with the MATLAB function). Alternatively, you can specify a different MATLAB function with `-mfunc`.

---

**Note** Do not specify an instance of an HDL module that has already been associated with a MATLAB M-function (via `matlabcp` or `matlabtb`). If you do, the new association overwrites the existing one.

---

<time-specs>  
Specifies a combination of time specifications consisting of any or all of the following:



<timen>,...

Specifies one or more discrete time values at which the HDL simulator calls the specified MATLAB function. Each time value is relative to the current simulation time. Even if you do not specify a time, the HDL simulator calls the MATLAB function once at the start of the simulation. Separate multiple time values by a space. For example:

```
matlabtb vlogtestbench_top 10 ns, 10 ms, 10 sec
```

The MATLAB function executes when time equals 0 and then 10 nanoseconds, 10 milliseconds, and 10 seconds from time zero.

---

**Note** For time-based parameters, you can specify any standard time units (ns, us, and so on). If you do not specify units, the command treats the time value as a value of HDL simulation ticks.

---

-repeat <time>

Specifies that the HDL simulator calls the MATLAB function repeatedly based on the specified <timen>, ... pattern. The time values are relative to the value of tnow at the time the HDL simulator first calls the MATLAB function. For example:

```
matlabtb vlogtestbench_top 5 ns -repeat 10 ns
```

The MATLAB function executes at time equals 0 ns, 5 ns, 15 ns, 25 ns, and so on.

-cancel <time>

Specifies a time at which the specified MATLAB function stops executing. The time value is relative to the value of tnow at the time the HDL simulator first calls the MATLAB function. If you do not specify a cancel time, the application calls the MATLAB function until you finish the simulation, quit the session, or issue a nomatlabtb call.

---

**Note** The `-cancel` option works only with the `<time-specs>` arguments. It does not affect any of the other scheduling arguments for `matlabtb`.

---

---

**Note** Place time specifications after the `matlabtb` instance and before any additional command arguments; otherwise the time specifications are ignored.

---

All time specifications for the `matlabtb` functions appear as a number and, optionally, a time unit:

- fs (femtoseconds)
- ps (picoseconds)
- ns (nanoseconds)
- us (microseconds)
- ms (milliseconds)
- sec (seconds)
- no units (tick)

`-socket <tcp_spec>`

Specifies TCP/IP socket communication for the link between the HDL simulator and MATLAB. When you provide TCP/IP information for `matlabtb`, you can choose a TCP/IP port number or TCP/IP port alias or service name for the `<tcp_spec>` parameter. If you are setting up communication between computers, you must also specify the name or Internet address of the remote host that is running the MATLAB server (`hdldaemon`). See “Specifying TCP/IP Values” on page 7-15 for some valid `tcp_spec` examples.

---

For more information on choosing TCP/IP socket ports, see “Choosing TCP/IP Socket Ports” on page 7-13.

If you run the HDL simulator and MATLAB on the same computer, you have the option of using shared memory for communication. Shared memory is the default mode of communication and takes effect if you do not specify `-socket <tcp_spec>` on the command line.

---

**Note** The communication mode that you specify with the `matlabtb` command must match what you specify for the communication mode when you issue the `hdldaemon` command in MATLAB. For more information on modes of communication, see “Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8. For more information on establishing the MATLAB end of the communication link, see “Start `hdldaemon` to Provide Connection to HDL Simulator” on page 2-23.

---

`-rising <signal>[, <signal>...]`

Indicates that the application calls the specified MATLAB function on the rising edge (transition from '0' to '1') of any of the specified signals. Specify `-rising` with the path names of one or more signals defined as a logic type (`STD_LOGIC`, `BIT`, `X01`, and so on).

---

**Note** When specifying signals with the `-rising`, `-falling`, and `-sensitivity` options, specify them in full path name format. If you do not specify a full path name, the command applies the HDL simulator rules to resolve signal specifications.

---

`-falling <signal>[, <signal>...]`

Indicates that the application calls the specified MATLAB function whenever any of the specified signals experiences a

falling edge—changes from '1' to '0'. Specify `-falling` with the path names of one or more signals defined as a logic type (STD\_LOGIC, BIT, X01, and so on).

---

**Note** When specifying signals with the `-rising`, `-falling`, and `-sensitivity` options, specify them in full path name format. If you do not specify a full path name, the command applies the HDL simulator rules to resolve signal specifications.

---

`-sensitivity <signal>[, <signal>...]`

Indicates that the application calls the specified MATLAB function whenever any of the specified signals changes state. Specify `-sensitivity` with the path names of one or more signals. Signals of any type can appear in the sensitivity list and can be positioned at any level of the HDL design.

If you specify the option with no signals, the interface is sensitive to value changes for all signals.

---

**Note** Use of this option for INOUT ports can result in double calls.

---

For example:

```
-sensitivity /randnumgen/dout
```

The MATLAB function executes if the value of `dout` changes.

---

**Note** When specifying signals with the `-rising`, `-falling`, and `-sensitivity` options, specify them in full path name format. If you do not specify a full path name, the command applies the HDL simulator rules to resolve signal specifications.

---

**-mfunc <name>**

The name of the associated MATLAB function. If you omit this argument, `matlabtb` associates the HDL module instance to a MATLAB function that has the same name as the HDL instance. If you omit this argument and `matlabtb` does not find a MATLAB function with the same name, the command generates an error message.

**-use\_instance\_obj** (*Beta Feature*)

Instructs the function specified with the argument `-mfunc` to use an HDL instance object passed by EDA Simulator Link MQ to the M-function. The `-use_instance_obj` argument is called with `matlabtb` in the following format:

```
matlabtb modelname -mfunc funcname -use_instance_obj
```

When you call `matlabcp` with the `use_instance_obj` argument, the M-function has the following signature:

```
function MyFunctionName(hdl_instance_obj)
```

The HDL instance object (`hdl_instance_obj`) has the fields shown in the following table.

Field	Read/Write Access	Description
<code>tnext</code>	Write only	Used to schedule a callback during the set time value. This field is equivalent to old <code>tnext</code> . For example:  <pre>hdl_instance_obj.tnext = hdl_instance_obj.tnow + 5e-9</pre> will schedule a callback at time equals 5 nanoseconds from <code>tnow</code> .
<code>userdata</code>	Read/Write	Stores state variables of the current <code>matlabtb</code> instance. You can retrieve the variables the next time the callback of this instance is scheduled.

Field	Read/Write Access	Description
simstatus	Read only	<p>Stores the status of the HDL simulator. The EDA Simulator Link MQ software sets this parameter to 'Init' during the first callback for this particular instance and to 'Running' thereafter. simstatus is a read-only property.</p> <pre>&gt;&gt; hdl_instance_obj.simstatus  ans=     Init</pre>
instance	Read only	<p>Stores the full path of the Verilog/VHDL instance associated with the callback. instance is a read-only property. The value of this field equals that of the module instance specified with the function call. For example:</p> <p>In the HDL simulator:</p> <pre>hdlsim&gt; matlabtb osc_top -mfunc oscfilter use_instance_obj</pre> <p>In MATLAB:</p> <pre>&gt;&gt; hdl_instance_obj.instance  ans=     osc_top</pre>

Field	Read/Write Access	Description
argument	Read only	<p>Stores the argument set by the <code>-argument</code> option of <code>matlabtb</code>. For example:</p> <pre>matlabtb osc_top -mfunc oscfilter -use_instance_obj -argument foo</pre> <p>The link software supports the <code>-argument</code> option only when it is used with <code>-use_instance_obj</code>, otherwise the argument is ignored. <code>argument</code> is a read-only property.</p> <pre>&gt;&gt; hdl_instance_obj.argument ans=     foo</pre>
portinfo	Read only	<p>Stores information about the VHDL and Verilog ports associated with this instance. <code>portinfo</code> is a read-only property, which has a field structure that describes the ports defined for the associated HDL module. For each port, the <code>portinfo</code> structure passes information such as the port's type, direction, and size. For more information on port data, see “Gaining Access to and Applying Port Information” on page 9-5.</p> <pre>hdl_instance_obj.portinfo.field1.field2.field3</pre> <hr/> <p><b>Note</b> When you use <code>use_instance_obj</code>, you access <code>tscale</code> through the HDL instance object. If you do not use <code>use_instance_obj</code>, you can still access <code>tscale</code> through <code>portinfo</code>.</p> <hr/>

Field	Read/Write Access	Description
tscale	Read only	<p>Stores the resolution limit (tick) in seconds of the HDL simulator. tscale is a read-only property.</p> <pre data-bbox="658 447 1044 569">&gt;&gt; hdl_instance_obj.tscale  ans=  1.0000e-009</pre> <hr/> <p><b>Note</b> When you use use_instance_obj, you access tscale through the HDL instance object. If you do not use use_instance_obj, you can still access tscale through portinfo.</p> <hr/>
tnow	Read only	<p>Stores the current time. tnow is a read-only property.</p> <pre data-bbox="658 1010 1285 1031">hdl_instance_obj.tnext = hld_instance_obj.tnow + fastestrate;</pre>



Field	Read/Write Access	Description
portvalues	Read/Write	<p>Stores the current values of and sets new values for the output and input ports for a matlabtb instance. For example:</p> <pre data-bbox="709 482 1151 765"> &gt;&gt; hdl_instance_obj.portvalues  ans = Read/Write Input ports:   clk_enable: []          clk: []          reset: [] Read Only Output ports:   sine_out: [22x1 char] </pre> <p>For example, you can set the reset port to 1 by calling <code>hdl_instance_obj.portvalues.reset = '1'</code>.</p>
linkmode	Read only	<p>Stores the status of the callback. The EDA Simulator Link MQ software sets this parameter to 'testbench' if the callback is associated with matlabtb and 'component' if the callback is associated with matlabcp. linkmode is a read-only property.</p> <pre data-bbox="709 1199 1121 1321"> &gt;&gt; hdl_instance_obj.linkmode  ans= testbench </pre>

-argument (*Beta Feature*)

Used to pass user-defined arguments from the `matlabtb` instantiation on the HDL side to the M-function callbacks. Supported with `-use_instance_obj` only. See the field listing for argument under the `-use_instance_obj` property.

## Description

The `matlabtb` command has the following characteristics:

- Starts the HDL simulator client component of the EDA Simulator Link MQ software.
- Associates a specified instance of an HDL design created in the HDL simulator with a MATLAB function.
- Creates a process that schedules invocations of the specified MATLAB function.
- Cancels any pending events scheduled by a previous `matlabtb` command that specified the same instance. For example, if you issue the command `matlabtb` for instance `foo`, all previously scheduled events initiated by `matlabtb` on `foo` are canceled.

MATLAB test bench functions mimic stimuli passed to entities in the HDL model. You force stimulus from MATLAB or HDL scheduled with `matlabtb`.

---

**Note** For the HDL simulator to establish a communication link with MATLAB, the MATLAB server, `hdldaemon`, must be running with the same communication mode and, if appropriate, the same TCP/IP socket port as you specify with the `matlabtb` command.

---

## Examples

The following examples demonstrate some ways you might use the `matlabtb` function.

## Using matlabtb with the -socket Argument and Time Parameters

The following command starts the HDL simulator client component of EDA Simulator Link MQ, associates an instance of the entity, `myfirfilter`, with the MATLAB function `myfirfilter`, and begins a local TCP/IP socket-based test bench session using TCP/IP port 4449. Based on the specified test bench stimuli, `myfirfilter.m` executes 5 nanoseconds from the current time, and then repeatedly every 10 nanoseconds:

```
hdlsim> matlabtb myfirfilter 5 ns -repeat 10 ns -socket 4449
```

## Applying Rising Edge Clocks and State Changes with matlabtb

The following command starts the HDL simulator client component of EDA Simulator Link MQ, and begins a remote TCP/IP socket-based session using remote MATLAB host `compb` and TCP/IP port 4449. Based on the specified test bench stimuli, `myfirfilter.m` executes 10 nanoseconds from the current time, each time the signal `/top/fclk` experiences a rising edge, and each time the signal `/top/din` changes state.

```
hdlsim> matlabtb /top/myfirfilter 10 ns -rising /top/fclk -sensitivity /top/din  
-socket 4449@computer123
```

## Specifying a MATLAB M-Function Name and Sensitizing Signals with matlabtb

The following command starts the HDL simulator client component of the EDA Simulator Link MQ software. The `-mfunc` option specifies the M-function to connect to and the `-socket` option specifies the port number for socket connection mode. `-sensitivity` indicates that the test bench session is sensitized to the signal `sine_out`.

```
hdlsim> matlabtb osc_top -sensitivity /osc_top/sine_out  
-socket 4448 -mfunc hosctb
```

# matlabtbeval

---

**Purpose** Call specified MATLAB function once and immediately on behalf of instantiated HDL module

**Syntax** `matlabtbeval <instance> [-socket <tcp_spec>]  
[-mfunc <name>]`

**Arguments** `<instance>`  
Specifies the instance of an HDL module that is associated with a MATLAB function. By default, `matlabtbeval` associates the HDL module instance with a MATLAB function that has the same name as the HDL module instance. For example, if the HDL module instance is `myfirfilter`, `matlabtbeval` associates the HDL module instance with the MATLAB function `myfirfilter`. Alternatively, you can specify a different MATLAB function with the `-mfunc` property.

`-socket <tcp_spec>`  
Specifies TCP/IP socket communication for the link between the HDL simulator and MATLAB. For TCP/IP socket communication on a single computer, the `<tcp_spec>` can consist of just a TCP/IP port number or service name (alias). If you are setting up communication between computers, you must also specify the name or Internet address of the remote host. See “Specifying TCP/IP Values” on page 7-15 for some valid `tcp_spec` examples.

For more information on choosing TCP/IP socket ports, see “Choosing TCP/IP Socket Ports” on page 7-13.

If you run the HDL simulator and MATLAB on the same computer, you have the option of using shared memory for communication. Shared memory is the default mode of communication and takes effect if you do not specify `-socket <tcp_spec>` on the command line.

---

**Note** The communication mode that you specify with the `matlabtbeval` command must match what you specify for the communication mode when you call the `hdldaemon` command to start the MATLAB server. For more information on communication modes, see “Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8. For more information on establishing the MATLAB end of the communication link, see “Start `hdldaemon` to Provide Connection to HDL Simulator” on page 2-23.

---

`-mfunc <name>`

The name of the associated MATLAB function. If you omit this argument, `matlabtbeval` associates the HDL module instance with a MATLAB function that has the same name as the HDL module instance. If you omit this argument and `matlabtbeval` does not find a MATLAB function with the same name, the command displays an error message.

## Description

The `matlabtbeval` command has the following characteristics:

- Starts the HDL simulator client component of the EDA Simulator Link MQ software.
- Associates a specified instance of an HDL design created in the HDL simulator with a MATLAB function.
- Executes the specified MATLAB function once and immediately on behalf of the specified module instance.

---

**Note** The `matlabtbeval` command executes the MATLAB function immediately, while `matlabtb` provides several options for scheduling MATLAB function execution.

---

---

**Note** For the HDL simulator to establish a communication link with MATLAB, the MATLAB `hdldaemon` must be running with the same communication mode and, if appropriate, the same TCP/IP socket port as you specify with the `matlabtbeval` command.

---

## Examples

This example starts the HDL simulator client component of the link software, associates an instance of the module `myfirfilter` with the function `myfirfilter.m`, and uses a local TCP/IP socket-based communication link to TCP/IP port 4449 to execute the function `myfirfilter.m`:

```
> matlabtbeval myfirfilter -socket 4449:
```

<b>Purpose</b>	End active MATLAB test bench and MATLAB component sessions
<b>Syntax</b>	nomatlabtb
<b>Description</b>	The nomatlabtb command ends all active MATLAB test bench and MATLAB component sessions that were previously initiated by matlabtb or matlabcp commands.
<b>Examples</b>	The following command ends all MATLAB test bench and MATLAB component sessions:  > nomatlabtb
<b>See Also</b>	matlabtb, matlabcp

# vsimmatlab

---

<b>Purpose</b>	Load instantiated HDL module for verification with MATLAB
<b>Syntax</b>	<code>vsimmatlab &lt;instance&gt; [&lt;vsim_args&gt;]</code>
<b>Arguments</b>	<code>&lt;instance&gt;</code> Specifies the instance of an HDL module to load for verification. <code>&lt;vsim_args&gt;</code> Specifies one or more ModelSim <code>vsim</code> command arguments. For details, see the description of <code>vsim</code> in the ModelSim documentation.
<b>Description</b>	<p>The <code>vsimmatlab</code> command loads the specified instance of an HDL module for verification and sets up ModelSim so it can establish a communication link with MATLAB. ModelSim opens a simulation workspace and displays a series of messages in the command window as it loads the HDL module's packages and architectures.</p> <p>This command may be run from the HDL simulator prompt or from a Tcl script shell (<code>tclsh</code>).</p>
<b>Examples</b>	<p>The following command loads the HDL module instance <code>parse</code> from library <code>work</code> for verification and sets up ModelSim so it can establish a communication link with MATLAB:</p> <pre>ModelSim&gt; vsimmatlab work.parse</pre>



---

<b>Purpose</b>	Load instantiated HDL module for cosimulation with Simulink
<b>Syntax</b>	<code>vsimulink &lt;instance&gt;</code> <code>[-socket &lt;tcp_spec&gt;] [&lt;vsim_args&gt;]</code>
<b>Argument</b>	<p><code>&lt;instance&gt;</code> Specifies the instance of an HDL module to load for cosimulation.</p> <p><code>-socket &lt;tcp_spec&gt;</code> Specifies TCP/IP socket communication for the link between ModelSim and MATLAB. This setting overrides the setting specified with the MATLAB <code>vsim</code> function. The <code>&lt;tcp_spec&gt;</code> can consist of a TCP/IP socket port number or service name (alias). For example, you might specify port number 4449 or the service name <code>matlabservice</code>.</p>

For more information on choosing TCP/IP socket ports, see “Specifying TCP/IP Socket Communication” on page 7-13.

If you run the HDL simulator and MATLAB on the same computer, you have the option of using shared memory for communication. Shared memory is the default mode of communication and takes effect if you do not specify `-socket <tcp_spec>` on the command line.

---

**Note** The communication mode that you specify with the `vsimulink` command must match what you specify for the communication mode when you configure EDA Simulator Link MQ blocks in your Simulink model. For more information on modes of communication, see “Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8. For more information on establishing the Simulink end of the communication link, see “Configuring the Communication Link in the HDL Cosimulation Block” on page 4-34.

---

# vsimulink

---

`<vsim_args>`

Specifies one or more ModelSim `vsim` command arguments. For details, see the description of `vsim` in the ModelSim documentation.

## Description

The `vsimulink` command loads the specified instance of an HDL module for cosimulation and sets up ModelSim so it can establish a communication link with Simulink. ModelSim opens a simulation workspace and displays a series of messages in the command window as it loads the HDL module's packages and architectures.

## Examples

The following command loads the HDL module instance `parse` from library `work` for cosimulation and sets up ModelSim so it can establish a communication link with Simulink:

```
ModelSim> vsimulink work.parse
```

**Purpose** Apply VHDL wrapper to Verilog module

**Syntax** wrapverilog [-nocompile] <verilog\_module>

**Arguments**

<verilog\_module>  
Specifies the Verilog module to which a VHDL wrapper is to be applied. The module you specify must be in a valid ModelSim design library when you issue the command.

-nocompile  
Suppresses automatic compilation of the resulting VHDL file, *verilog\_module\_wrap.vhd*.

## Description

---

**Note** EDA Simulator Link MQ now supports Verilog models directly, without requiring a VHDL wrapper. All EDA Simulator Link MQ MATLAB functions, and the HDL Cosimulation block, offer the same language-transparent feature set for both Verilog and VHDL models. The `wrapverilog` function is supported for backward compatibility, and is still in use by many EDA Simulator Link MQ demos.

---

The `wrapverilog` command applies a VHDL wrapper to the specified Verilog module and then automatically compiles the resulting VHDL file. You can then use your wrapped Verilog module with EDA Simulator Link MQ.

Before executing the `wrapverilog` command on a Verilog file, you must compile and load the Verilog module in ModelSim, as in the following example.

```
vlib work
vmap work work
vlog myverilogmod.v
vsim myverilogmod
wrapverilog [-nocompile] myverilogmod
```

# wrapverilog

---

## **Examples**

The following command applies a VHDL wrapper to Verilog module `myverilogmod.v` and writes the output to `myverilogmod_wrap.vhd`. The `-nocompile` option suppresses automatic compilation.

```
ModelSim> wrapverilog -nocompile myverilogmod
```

# Blocks — Alphabetical List

---

# HDL Cosimulation

---

## Purpose

Cosimulate hardware component by communicating with HDL module instance executing in HDL simulator

## Library

EDA Simulator Link MQ

## Description



The HDL Cosimulation block cosimulates a hardware component by applying input signals to and reading output signals from an HDL model under simulation in the HDL simulator. You can use this block to model a source or sink device by configuring the block with input or output ports only.

The tabbed panes on the block's dialog box let you configure:

- Block input and output ports that correspond to signals (including internal signals) of an HDL module. You must specify a sample time for each output port; you can also specify a data type for each output port.
- Type of communication and communication settings used to exchange data between simulators.
- The timing relationship between units of simulation time in Simulink and the HDL simulator.
- Rising-edge or falling-edge clocks to apply to your model. You can specify the period for each clock signal.
- Tcl commands to run before and after the simulation.

The **Ports** pane provides fields for mapping signals of your HDL design to input and output ports in your block. The signals can be at any level of the HDL design hierarchy.

The **Timescales** pane lets you choose an optimal timing relationship between Simulink and the HDL simulator. You can configure either of the following timing relationships:

- *Relative* timing relationship (Simulink seconds correspond to an HDL simulator-defined tick interval)

- *Absolute* timing relationship (Simulink seconds correspond to an absolute unit of HDL simulator time)

The **Connection** pane specifies the communications mode used between Simulink and the HDL simulator. If you use TCP socket communication, this pane provides fields for specifying a socket port and for the host name of a remote computer running the HDL simulator. The **Connection** pane also provides the option for bypassing the cosimulation block during Simulink simulation.

The **Clocks** pane lets you create optional rising-edge and falling-edge clocks that apply stimuli to your cosimulation model.

The **Tcl** pane provides a way of specifying tools command language (Tcl) commands to be executed before and after the HDL simulator simulates the HDL component of your Simulink model. You can use the **Pre-simulation commands** field on this pane for simulation initialization and startup operations, but you cannot use it to change simulation state.

---

**Note** You must make sure that signals being used in cosimulation have read/write access. (Verify such access through the HDL simulator—see product documentation for details). This rule applies to all signals on the **Ports**, **Clocks**, and **Tcl** panes.

---

## Dialog Box

The Block Parameters dialog box consists of the following tabbed panes of configuration options:

- “Ports Pane” on page 12-4
- “Connection Pane” on page 12-10
- “Timescales Pane” on page 12-14
- “Clocks Pane” on page 12-18
- “Tcl Pane” on page 12-22

## Ports Pane

Specify fields for mapping signals of your HDL design to input and output ports in your block. Simulink deposits an input port signal on an HDL simulator signal at the signal's sample rate. Conversely, Simulink reads an output port signal from a specified HDL simulator signal at the specified sample rate.

In general, Simulink handles port sample periods as follows:

- If you connect an input port to a signal that has an explicit sample period, based on forward propagation, Simulink applies that rate to the port.
- If you connect an input port to a signal that does not have an explicit sample period, Simulink assigns a sample period that is equal to the least common multiple (LCM) of all identified input port sample periods for the model.
- After Simulink sets the input port sample periods, it applies user-specified output sample times to all output ports. You must specify an explicit sample time for each output port.

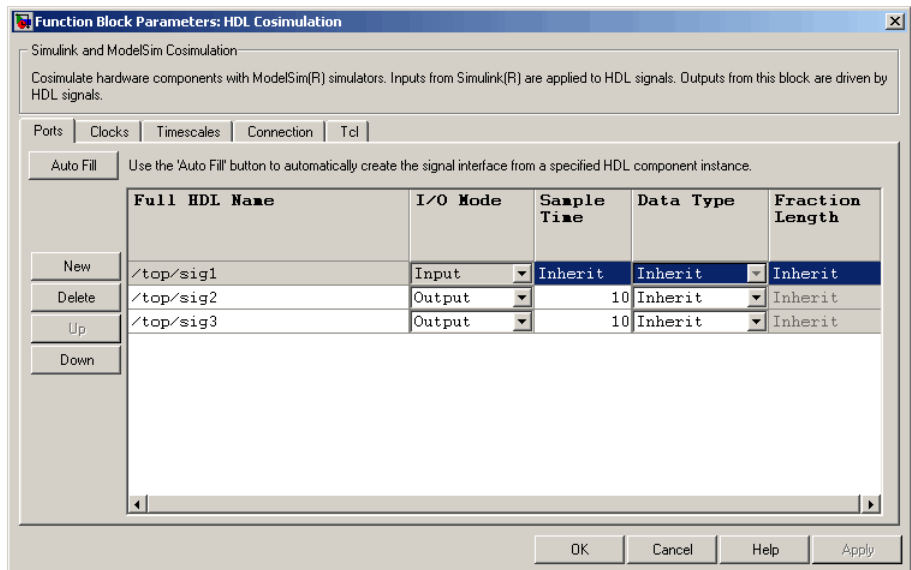
In addition to specifying output port sample times, you can force the fixed-point data types on output ports. For example, setting the **Data Type** property of an 8-bit output port to **Signed** and setting its **Fraction Length** property to 5 would force the data type to `sfixed8_E5`. You can not force width; the width is always inherited from the HDL simulator.



**Note** The **Data Type** and **Fraction Length** properties apply only to the following signals:

- VHDL signals of any logic type, such as STD\_LOGIC or STD\_LOGIC\_VECTOR
- Verilog signals of wire or reg type

You can set input/output ports in the Parts pane also. To do so, specify port as both input and output.



The list at the center of the pane displays HDL signals corresponding to ports on the HDL Cosimulation block.

Maintain this list with the buttons on the left of the pane:

# HDL Cosimulation

---

- **Auto Fill** — Transmit a port information request to the HDL simulator. The port information request returns port names and information from an HDL model (or module) under simulation in the HDL simulator and automatically enters this information into the ports list. See “Obtaining Signal Information Automatically from the HDL Simulator” on page 4-17 for a detailed description of this feature.
- **New** — Add a new signal to the list and select it for editing.
- **Delete** — Remove a signal from the list.
- **Up** — Move the selected signal up one position in the list.
- **Down** — Move the selected signal down one position in the list.

To commit edits to the Simulink model, you must also click **Apply** after selecting parameter values.

---

**Note** When you import VHDL signals from the HDL simulator, EDA Simulator Link MQ returns the signal names in all capitals.

---

To edit a signal name, double-click on the name. Set the signal properties on the same line and in the appropriate columns. The properties of a signal are as follows.

## Full HDL Name

Specifies the signal path name, using the HDL simulator path name syntax. For example, a path name for an input port might be `/manchester/samp`. The signal can be at any level of the HDL design hierarchy. The HDL Cosimulation block port corresponding to the signal is labeled with the **Full HDL Name**.

For rules on specifying signal/port and module path specifications in Simulink, see “Specifying HDL Signal/Port and Module Paths for Cosimulation” on page 4-16.

---

**Note** You can copy signal path names directly from the HDL simulator **wave** window and paste them into the **Full HDL Name** field, using the standard copy and paste commands in the HDL simulator and Simulink. You must use the Path.Name view and not Db::Path.Name view. After pasting a signal path name into the **Full HDL Name** field, you must click the **Apply** button to complete the paste operation and update the signal list.

---

## I/O Mode

Select either Input, Output, or both.

Input designates signals of your HDL module that Simulink will drive. Simulink deposits values on the specified the HDL simulator signal at the signal's sample rate.

---

**Note** When you define a block input port, make sure that only one source is set up to drive input to that signal. For example, you should avoid defining an input port that has multiple instances. If multiple sources drive input to a single signal, your simulation model may produce unexpected results.

---

Output designates signals of your HDL module that Simulink will read. For output signals, you must specify an explicit sample time. You can also specify any data type (except width). For details on specifying a data type, see Data Type and Fraction Length in a following section.

Because Simulink signals do not have the semantic of tri-states (there is no 'Z' value), you will gain no benefit by connecting to a bidirectional HDL signal directly. To interface with bidirectional signals, you can first interface to the input of the output driver, then the enable of the output driver and the output of the input driver. This approach leaves the actual tri-state buffer in HDL

where resolution functions can handle interfacing with other tri-state buffers.

## **Sample Time**

This property becomes available only when you specify an output signal. You must specify an explicit sample time.

**Sample Time** represents the time interval between consecutive samples applied to the output port. The default sample time is 1. The exact interpretation of the output port sample time depends on the settings of the **Timescales** pane of the HDL Cosimulation block (see “Timescales Pane” on page 12-14). See also “Understanding the Representation of Simulation Time” on page 8-15.

## **Data Type**

### **Fraction Length**

These two related parameters apply only to output signals.

The **Data Type** property is enabled only for output signals. You can direct Simulink to determine the data type, or you can assign an explicit data type (with option fraction length). By explicitly assigning a data type, you can force fixed-point data types on output ports of an HDL Cosimulation block.

The **Fraction Length** property specifies the size, in bits, of the fractional part of the signal in fixed-point representation. **Fraction Length** becomes available if you do not set the **Data Type** property to Inherit.

The data type specification for an output port depends on the signal width and by the **Data Type** and **Fraction Length** properties of the signal.

---

**Note** The **Data Type** and **Fraction Length** properties apply only to the following signals:

- VHDL signals of any logic type, such as STD\_LOGIC or STD\_LOGIC\_VECTOR
  - Verilog signals of wire or reg type
- 

To assign a port data type, set the **Data Type** and **Fraction Length** properties as follows:

- Select **Inherit** from the **Data Type** list if you want Simulink to determine the data type.

This property defaults to **Inherit**. When you select **Inherit**, the **Fraction Length** edit field becomes unavailable.

Simulink always double checks that the word-length back propagated by Simulink matches the word length queried from the HDL simulator. If they do not match, Simulink generates an error message. For example, if you connect a Signal Specification block to an output, Simulink will force the data type specified by Signal Specification block on the output port.

If Simulink cannot determine the data type of the signal connected to the output port, it will query the HDL simulator for the data type of the port. As an example, if the HDL simulator returns the VHDL data type STD\_LOGIC\_VECTOR for a signal of size N bits, the data type `ufixN` is forced on the output port. (The implicit fraction length is 0.)

- Select **Signed** from the **Data Type** list if you want to explicitly assign a signed fixed point data type. When you select **Signed**, the **Fraction Length** edit field becomes available. EDA Simulator Link MQ assigns the port a fixed-point type `sfixN_EnF`, where N is the signal width and F is the **Fraction Length**.

# HDL Cosimulation

---

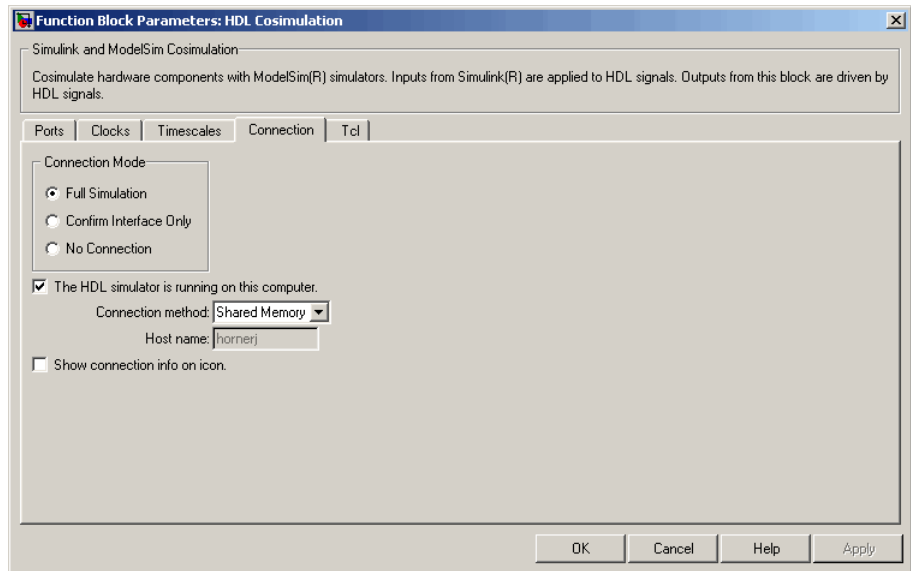
For example, if you specify **Data Type** as Signed and a **Fraction Length** of 5 for a 16-bit signal, Simulink forces the data type to `sfixed16_En5`. For the same signal with a **Data Type** set to Signed and **Fraction Length** of -5, Simulink forces the data type to `sfixed16_E5`.

- Select Unsigned from the **Data Type** list if you want to explicitly assign an unsigned fixed point data type. When you select Unsigned, the **Fraction Length** edit field becomes available. EDA Simulator Link MQ assigns the port a fixed-point type `ufixedN_EnF`, where N is the signal width and F is the **Fraction Length**.

For example, if you specify **Data Type** as Unsigned and a **Fraction Length** of 5 for a 16-bit signal, Simulink forces the data type to `ufixed16_En5`. For the same signal with a **Data Type** set to Unsigned and **Fraction Length** of -5, Simulink forces the data type to `ufixed16_E5`.

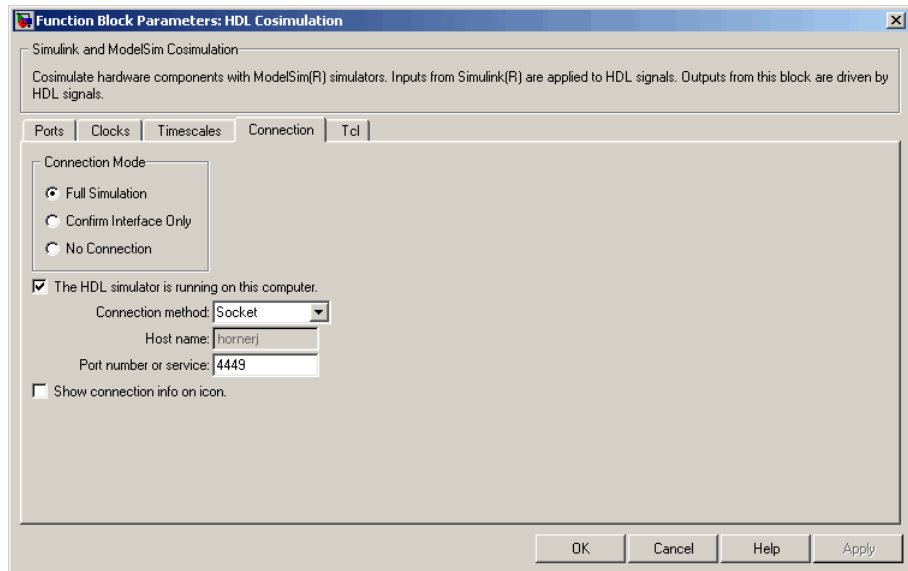
## Connection Pane

This figure shows the default configuration of the **Connection** pane. The block defaults to a shared memory configuration for communication between Simulink and the HDL simulator, when they run on a single computer.



If you select TCP/IP socket mode communication, the pane displays additional properties, as shown in the following figure.

# HDL Cosimulation



## Connection Mode

If you want to bypass the HDL simulator when you run a Simulink simulation, use these options to specify what type of simulation connection you want. Select one of the following options:

- **Full Simulation:** Confirm interface and run HDL simulation (default).
- **Confirm Interface Only:** Connect to the HDL simulator and check for proper signal names, dimensions, and data types, but do not run HDL simulation.
- **No Connection:** Do not communicate with the HDL simulator. The HDL simulator does not need to be started.

With the second and third options, the EDA Simulator Link MQ cosimulation interface does not communicate with the HDL simulator during Simulink simulation.



## **The HDL Simulator is running on this computer**

Select this option if you want to run Simulink and the HDL simulator on the same computer. When both applications run on the same computer, you have the choice of using shared memory or TCP sockets for the communication channel between the two applications. If you do not select this option, only TCP/IP socket mode is available, and the **Connection method** list becomes unavailable.

## **Connection method**

This list becomes available when you select **The HDL Simulator is running on this computer**. Select **Socket** if you want Simulink and the HDL simulator to communicate via a designated TCP/IP socket. Select **Shared memory** if you want Simulink and the HDL simulator to communicate via shared memory. For more information on these connection methods, see “Communicating with MATLAB or Simulink and the HDL Simulator” on page 1-8.

## **Host name**

If you run Simulink and the HDL simulator on different computers, this text field becomes available. The field specifies the host name of the computer that is running your HDL simulation in the HDL simulator.

## **Port number or service**

Indicate a valid TCP socket port number or service for your computer system (if not using shared memory). For information on choosing TCP socket ports, see “Choosing TCP/IP Socket Ports” on page 7-13.

## **Show connection info on icon**

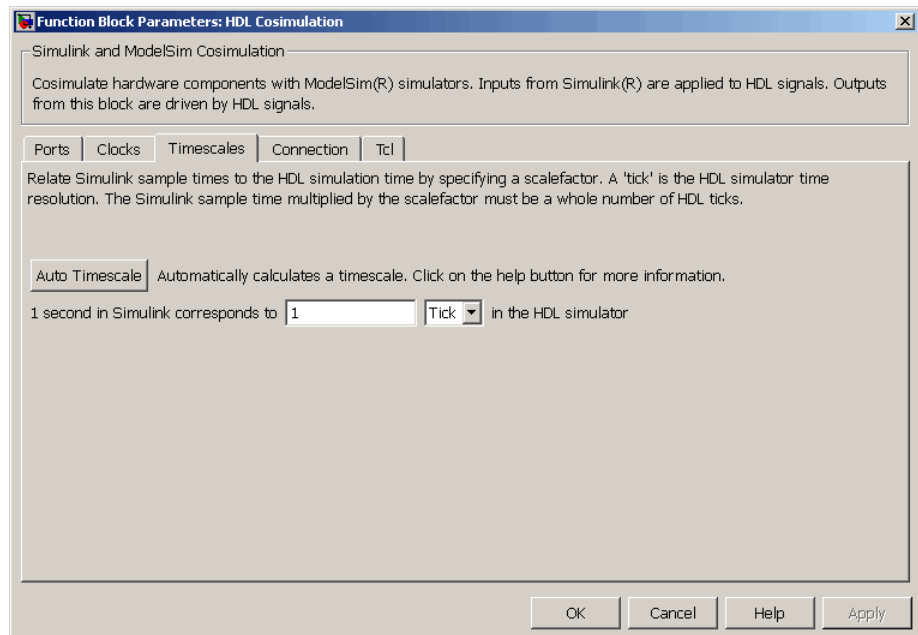
When you select this option, Simulink indicates information about the selected communication method and (if applicable) communication options information on the HDL Cosimulation block icon. If you select shared memory, the icon displays the string **SharedMem**. If you select TCP socket communication, the icon displays the string **Socket** and displays the host name and port number in the format **hostname:port**.

# HDL Cosimulation

In a model that has multiple HDL Cosimulation blocks, with each communicating to different instances of the HDL simulator in different modes, this information helps to distinguish between different cosimulation sessions.

## Timescales Pane

The **Timescales** pane of the HDL Cosimulation block parameters dialog box lets you choose a timing relationship between Simulink and the HDL simulator, either manually or automatically. The following figure shows the default settings of the **Timescales** pane.



The **Timescales** pane specifies a correspondence between one second of Simulink time and some quantity of HDL simulator time. This quantity of HDL simulator time can be expressed in one of the following ways:

- Using *relative timing mode*. EDA Simulator Link MQ defaults to relative timing mode.
- Using *absolute timing mode*

For more information on calculating relative and absolute timing modes, see “Defining the Simulink and HDL Simulator Timing Relationship” on page 8-16.

For detailed information on the relationship between Simulink and the HDL simulator during cosimulation, and on the operation of relative and absolute timing modes, see “Understanding the Representation of Simulation Time” on page 8-15.

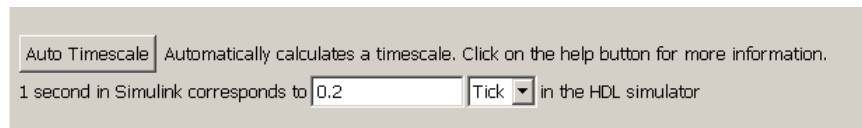
The following sections describe how to specify the timing relationship, either automatically or manually.

### Automatically Specifying the Timing Relationship

You can have the EDA Simulator Link MQ software calculate the timing relationship for you by performing the following steps:

- 1** Verify that the HDL simulator is running. EDA Simulator Link MQ software can get the resolution limit of the HDL simulator only when that simulator is running.
- 2** Click on **Auto Timescale**.

The following graphic shows the result of clicking **Auto Timescale** in the **Timescales** pane of the HDL Cosimulation block in the Manchester Receiver demo.



EDA Simulator Link MQ software analyzes all the clock and port signal rates from the HDL Cosimulation block when it calculates the scale factor.

# HDL Cosimulation

---

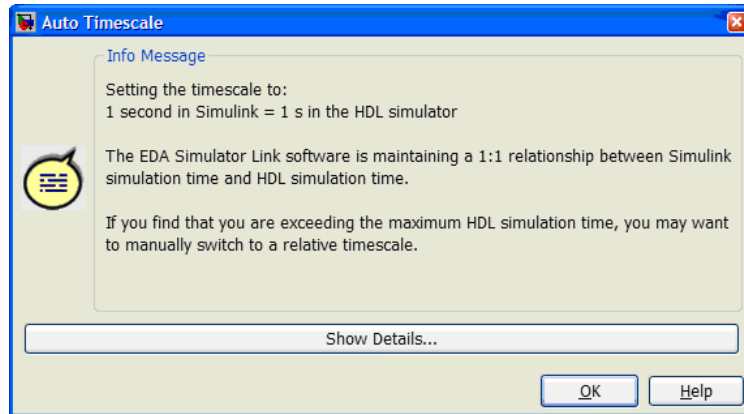
---

**Note** EDA Simulator Link MQ cannot automatically calculate a sample timescale based on any signals driven via Tcl commands or in the HDL simulator. The link software cannot perform such calculations because it cannot know the rates of these signals.

---

The link software returns the sample rate in either seconds or ticks. If the results are in seconds, then the link software was able to resolve the timing differences in favor of fidelity (absolute time). If the results are in ticks, then the link software was best able to resolve the timing differences in favor of efficiency (relative time).

Each time you press Auto Timescale, the EDA Simulator Link MQ software opens an informational GUI display that explains the results of Auto Timescale. If the link software cannot calculate a timescale for the given sample times, use the information in this dialog box to adjust your sample times.



Click **Show Details...** for information specific to your model's signals. Click **OK** to exit the informational dialog box.

**3** Click **Apply** to commit your changes.

---

**Note** EDA Simulator Link MQ does not support Auto Timescale calculated from frame-based signals.

---

For more on the timing relationship between the HDL simulator and Simulink, see “Understanding the Representation of Simulation Time” on page 8-15.

### **Manually Specifying a Relative Timing Relationship**

To manually configure relative timing mode for a cosimulation, perform the following steps:

- 1** Select the **Timescales** tab of the HDL Cosimulation block parameters dialog box.
- 2** Verify that **Tick**, the default setting, is selected. If it is not, then select it from the list on the right.
- 3** Enter a scale factor in the text box on the left. The default scale factor is 1. For example, the next figure, shows the **Timescales** pane configured for a relative timing correspondence of 10 HDL simulator ticks to 1 Simulink second.



1 second in Simulink corresponds to  **Tick** in the HDL simulator

- 4** Click **Apply** to commit your changes.

### **Manually Specifying an Absolute Timing Relationship**

To manually configure absolute timing mode for a cosimulation, perform the following steps:

- 1** Select the **Timescales** tab of the HDL Cosimulation block parameters dialog box.

# HDL Cosimulation

---

- 2 Select a unit of absolute time from the list on the right. The units available include fs (femtoseconds), ps (picoseconds), ns (nanoseconds), us (microseconds), ms (milliseconds), and s (seconds).
- 3 Enter a scale factor in the text box on the left. The default scale factor is 1. For example, in the next figure, the **Timescales** pane is configured for an absolute timing correspondence of 1 HDL simulator second to 1 Simulink second.



- 4 Click **Apply** to commit your changes.

## Clocks Pane

You can create optional rising-edge and falling-edge clocks that apply stimuli to your cosimulation model. To do so, use the Clocks pane of the HDL Cosimulation block. You can either specify an explicit period for each clock, or accept a default period of 2. Simulink attempts to create a clock that has a 50% duty cycle and a predefined phase that is inverted for the falling edge case.

Whether you have configured the **Timescales** pane for relative timing mode or absolute timing mode, the following restrictions apply to clock periods:

- If you specify an explicit clock period, you must enter a sample time equal to or greater than 2 resolution units (ticks).
- If the clock period (whether explicitly specified or defaulted) is not an even integer, Simulink cannot create a 50% duty cycle, and therefore the EDA Simulator Link MQ software creates the falling edge at

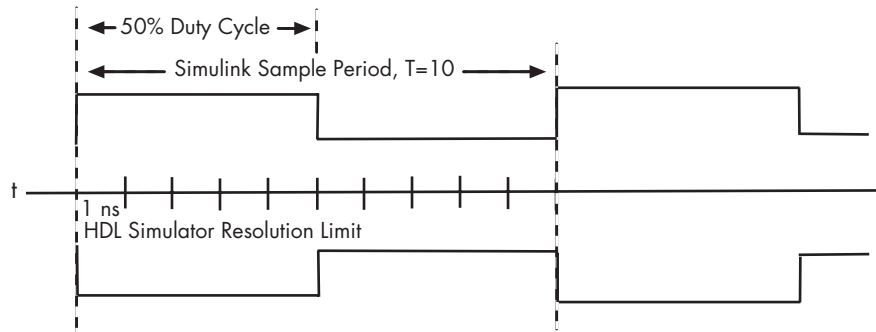
$$\textit{clockperiod} / 2$$

(rounded down to the nearest integer).

The following figure shows a timing diagram that includes rising-edge and falling-edge clocks with a Simulink sample period of  $T=10$  and an

HDL simulator resolution limit of 1 ns. The figure also shows that given those timing parameters, the clock duty cycle is 50%.

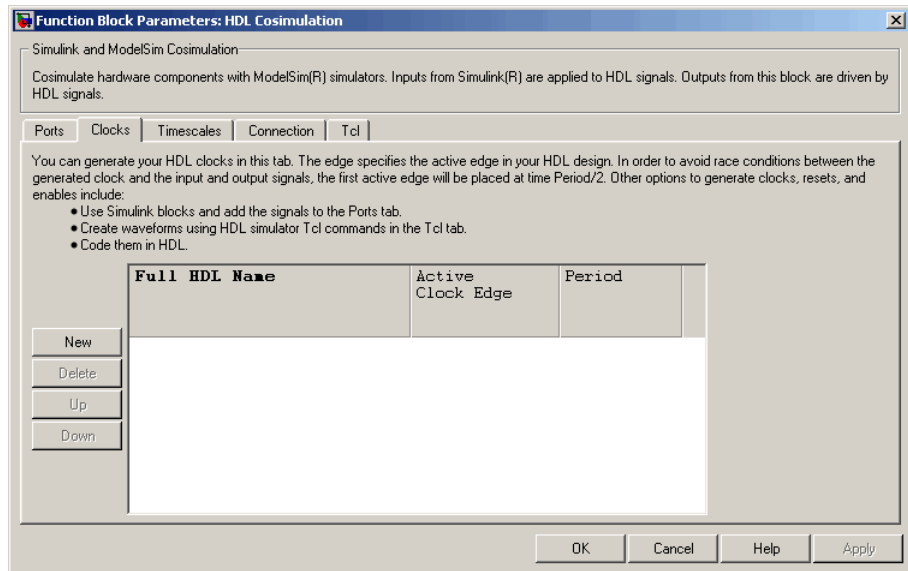
Rising Edge Clock



Falling Edge Clock

For more information on calculating relative and absolute timing modes, see “Defining the Simulink and HDL Simulator Timing Relationship” on page 8-16.

# HDL Cosimulation



The scrolling list at the center of the pane displays HDL clocks that drive values to the HDL signals that you are modeling, using the deposit method.

Maintain the list of clock signals with the buttons on the left of the pane:

- **New** — Add a new clock signal to the list and select it for editing.
- **Delete** — Remove a clock signal from the list.
- **Up** — Move the selected clock signal up one position in the list.
- **Down** — Move the selected clock signal down one position in the list.

To commit edits to the Simulink model, you must also click **Apply**.

To edit the name of a clock signal, double-click it and enter the correct name. To edit the properties of a clock signal, select the appropriate property in that signal row. A clock signal has the following properties.



## Full HDL Name

Specify each clock as a signal path name, using the HDL simulator path name syntax. For example: /manchester/clk.

For information about and requirements for path specifications in Simulink, see “Specifying HDL Signal/Port and Module Paths for Cosimulation” on page 4-16.

---

**Note** You can copy signal path names directly from the HDL simulator **wave** window and paste them into the **Full HDL Name** field, using the standard copy and paste commands in the HDL simulator and Simulink. You must use the Path.Name view and not Db::Path.Name view. After pasting a signal path name into the **Full HDL Name** field, you must click the **Apply** button to complete the paste operation and update the signal list.

---

## Edge

Select **Rising** or **Falling** to specify either a rising-edge clock or a falling-edge clock.

## Period

You must either specify the clock period explicitly or accept the default period of 2.

If you specify an explicit clock period, you must enter a sample time equal to or greater than 2 resolution units (ticks).

If the clock period (whether explicitly specified or defaulted) is not an even integer, Simulink cannot create a 50% duty cycle. Instead, the EDA Simulator Link MQ software creates the falling edge at

$$\text{clockperiod} / 2$$

(rounded down to the nearest integer).

# HDL Cosimulation

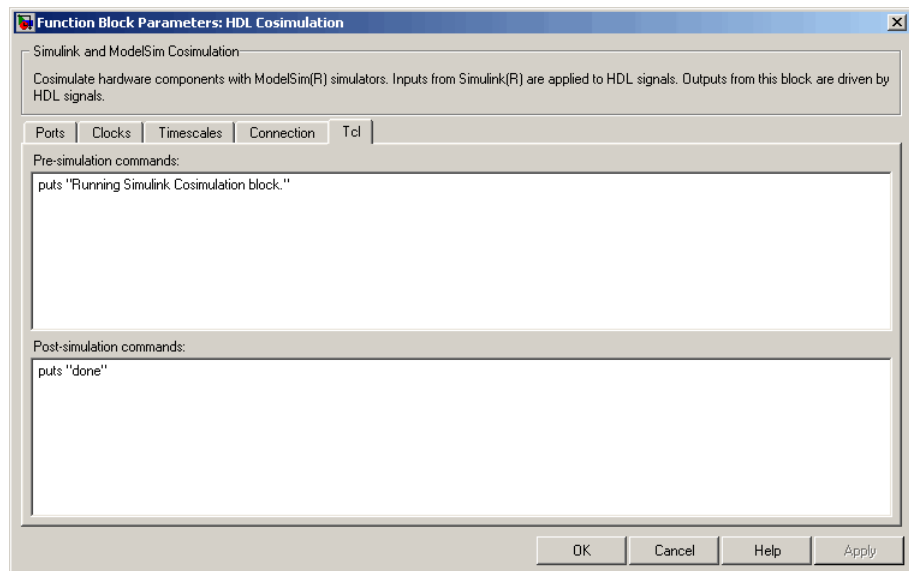
---

**Note** The **Clocks** pane does not support vectored signals. Signals must be logic types with 1 and 0 values.

---

## Tcl Pane

Specify tools command language (Tcl) commands to be executed before and after the HDL simulator simulates the HDL component of your Simulink model.



## Pre-simulation commands

Contains Tcl commands to be executed before the HDL simulator simulates the HDL component of your Simulink model. You can specify one Tcl command per line in the text box or enter multiple commands per line by appending each command with a semicolon (;), the standard Tcl concatenation operator.

Alternatively, you can create a ModelSim DO file that lists Tcl commands and then specify that file with the ModelSim do command as follows:

```
do mycosimstartup.do
```

Use of this field can range from something as simple as a one-line echo command to confirm that a simulation is running to a complex script that performs an extensive simulation initialization and startup sequence.

---

**Note** The command string or DO file that you specify for this parameter cannot include commands that load a ModelSim project or modify simulator state. For example, neither can include commands such as `start`, `stop`, or `restart`.

---

## Post-simulation commands

Contains Tcl commands to be executed after the HDL simulator simulates the HDL component of your Simulink model. You can specify one Tcl command per line in the text box or enter multiple commands per line by appending each command with a semicolon (;), the standard Tcl concatenation operator.

Alternatively, you can create a ModelSim DO file that lists Tcl commands and then specify that file with the ModelSim do command as follows:

```
do mycosimcleanup.do
```

You can include the `quit -f` command in an after-simulation Tcl command string or DO file to force ModelSim to shut down at the end of a cosimulation session. To ensure that all other after-simulation Tcl commands specified for the model will execute, specify all after simulation Tcl commands in a single

# HDL Cosimulation

---

cosimulation block and place `quit` at the end of the command string or DO file.

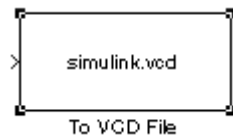
---

**Note** With the exception of `quit`, the command string or DO file that you specify cannot include commands that load a ModelSim project or modify simulator state. For example, they cannot include commands such as `start`, `stop`, or `restart`.

---

**Purpose** Generate value change dump (VCD) file

**Library** EDA Simulator Link MQ



## Description

The To VCD File block generates a VCD file that contains information about changes to signals connected to the block's input ports and names the file with the specified file name. You can use VCD files during design verification in the following ways:

- For comparing results of multiple simulation runs, using the same or different simulator environments
- As input to post-simulation analysis tools
- For porting areas of an existing design to a new design

In addition, you can graphically display VCD file data or analyze the data with postprocessing tools. For example, the ModelSim `vcd2wlf` tool converts a VCD file to a WLF file that you can view in a ModelSim **wave** window. Other examples of postprocessing include the extraction of data pertaining to a particular section of a design hierarchy or data generated during a specific time interval.

Using the Block Parameters dialog box, you can specify the following parameters:

- The file name to be used for the generated file
- The number of block input ports that are to receive signal data
- The timescale to relate Simulink sample times with HDL simulator ticks

## To VCD File

---

VCD files can grow very large for larger designs or smaller designs with longer simulation runs. However, the only limitation on the size of a VCD file generated by the To VCD File block is the maximum number of signals (and symbols) supported, which is  $94^3$  (830,584).

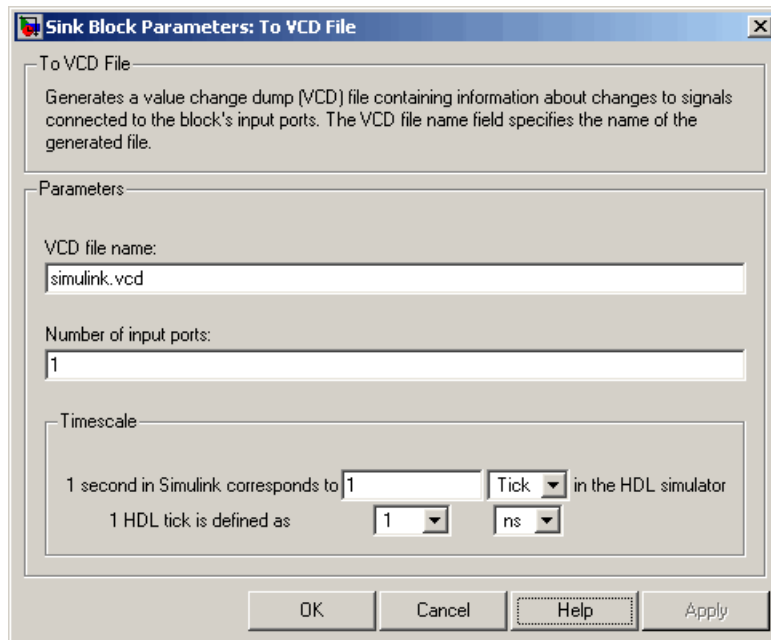
For a description of the VCD file format, see “VCD File Format” on page 12-29.

---

**Note** The toVCD File block is integrated into the Simulink Signal & Scope Manager. See the *Simulink User's Guide* for more information on using the Signal & Scope Manager.

---

## Dialog Box



### VCD file name

The file name to be used for the generated VCD file. If you specify a file name only, Simulink places the file in your current MATLAB directory. Specify a complete path name to place the generated file in a different location. If you specify the same name for multiple To VCD File blocks, Simulink automatically adds a numeric postfix to identify each instance uniquely.

---

**Note** If you want the generated file to have a .vcd file type extension, you must specify it explicitly.

Do not give the same file name to different VCD blocks. Doing so results in invalid VCD files.

---

## Number of input ports

The number of block input ports on which signal data is to be collected. The block can handle up to  $94^3$  (830,584) signals, each of which maps to a unique symbol in the VCD file.

In some cases, a single input port maps to multiple signals (and symbols). This multiple mapping occurs when the input port receives a multidimensional signal.

Because the VCD specification does not include multidimensional signals, Simulink flattens them to a 1D vector in the file.

## Timescale

Choose an optimal timing relationship between Simulink and the HDL simulator.

The timescale options specify a correspondence between one second of Simulink time and some quantity of HDL simulator time. You can express this quantity of HDL simulator time in one of the following ways:

- In *relative* terms (i.e., as some number of HDL simulator ticks). In this case, the cosimulation operates in *relative timing mode*, which is the timing mode default.

To use relative mode, select **Tick** from the pop-up list at the label **in the HDL simulator**, and enter the desired number of ticks in the edit box at **1 second in Simulink corresponds to**. The default value is 1 Tick.

- In *absolute* units (such as milliseconds or nanoseconds). In this case, the cosimulation operates in *absolute timing mode*.

To use absolute mode, select the desired resolution unit from the pop-up list at the label **in the HDL simulator** (available units are **fs, ps, ns, us, ms, s**), and enter the desired number of resolution units in the edit box at **1 second in Simulink corresponds to**. Then, set the value of the HDL simulator tick by selecting 1, 10, or 100 from the pop-up list at **1 HDL**



**Tick is defined as** and the resolution unit from the pop-up list at **defined as**.

## VCD File Format

The format of generated VCD files adheres to IEEE Std 1364-2001. The following table describes the format.

### Generated VCD File Format

File Content	Description
<pre>\$date 23-Sep-2003 14:38:11 \$end</pre>	Data and time the file was generated.
<pre>\$version EDA Simulator Link MQ version 1.0 \$ end</pre>	Version of the VCD block that generated the file.
<pre>\$timescale 1 ns \$ end</pre>	The time scale that was used during the simulation.
<pre>\$scope module manchestermodel \$end</pre>	The scope of the module being dumped.

## Generated VCD File Format (Continued)

File Content	Description
<pre>\$var wire 1 ! Original Data [0] \$end \$var wire 1 " Recovered Clock [0] \$end \$var wire 1 # Recovered Data [0] \$end \$var wire 1 \$ Data Validity [0] \$end</pre>	<p>Variable definitions. Each definition associates a signal with character identification code (symbol).</p> <p>The symbols are derived from printable characters in the ASCII character set from ! to ~.</p> <p>Variable definitions also include the variable type (wire) and size in bits.</p>
<pre>\$upscope \$end</pre>	<p>Marks a change to the next higher level in the HDL design hierarchy.</p>
<pre>\$enddefinitions \$end</pre>	<p>Marks the end of the header and definitions section.</p>
<pre>#0</pre>	<p>Simulation start time.</p>
<pre>\$dumpvars 0! 0" 0# 0\$ \$end</pre>	<p>Lists the values of all defined variables at time equals 0.</p>

## Generated VCD File Format (Continued)

File Content	Description
<pre>#630 1!</pre>	<p>The starting point of logged value changes from checks of variable values made at each simulation time increment.</p> <p>This entry indicates that at 63 nanoseconds, the value of signal <code>Original Data</code> changed from 0 to 1.</p>
<pre>. . . #1160 1# 1\$</pre>	<p>At 116 nanoseconds the values of signals <code>Recovered Data</code> and <code>Data Validity</code> changed from 0 to 1.</p>
<pre>\$dumpoff x! x" x# x\$ \$end</pre>	<p>Marks the end of the file by dumping the values of all variables as the value x.</p>

**To VCD File**

---

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