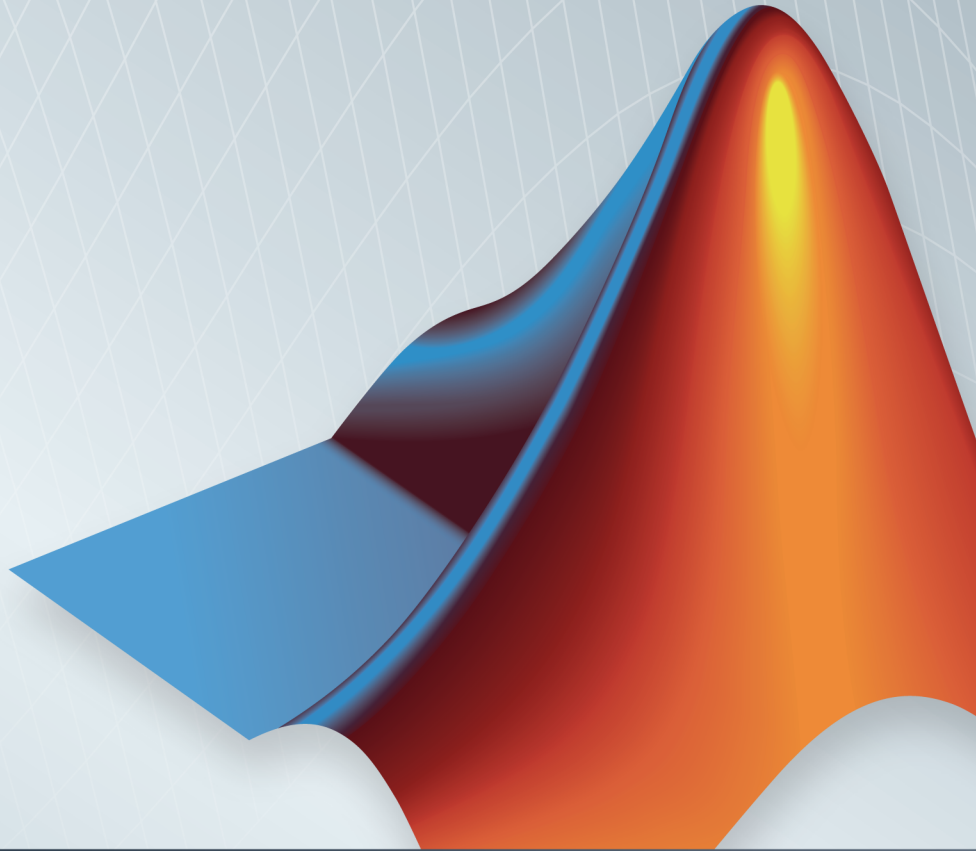
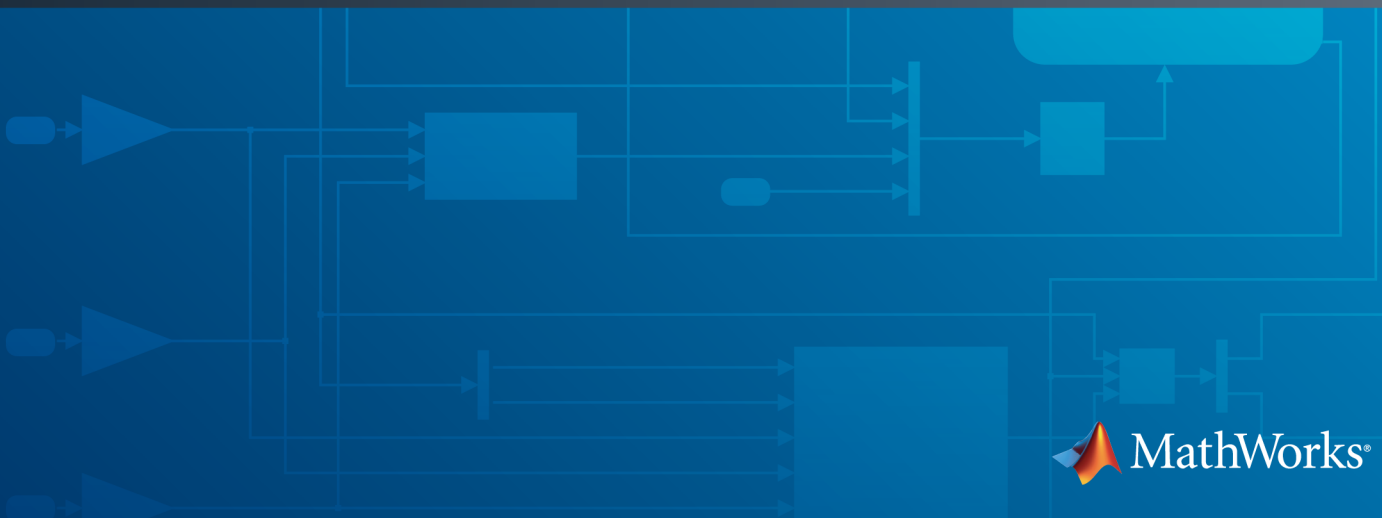


Modeling Guidelines for Code Generation

R2014b



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Modeling Guidelines for Code Generation

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Revision History

September 2010	Online only	New for Version 1.0 (Release 2010b)
April 2011	Online only	Revised for Version 1.1 (Release 2011a)
September 2011	Online only	Revised for Version 1.2 (Release 2011b)
March 2012	Online only	Revised for Version 1.3 (Release 2012a)
September 2012	Online only	Revised for Version 1.4 (Release 2012b)
March 2013	Online only	Revised for Version 1.5 (Release 2013a)
September 2013	Online only	Revised for Version 1.6 (Release 2013b)
March 2014	Online only	Revised for Version 1.7 (Release 2014a)
October 2014	Online only	Revised for Version 1.8 (Release 2014b)

	Introduction	
1		
	Motivation	1-2
	Guideline Template	1-3
	Block Considerations	
2		
	cgsl_0101: Zero-based indexing	2-2
	cgsl_0102: Evenly spaced breakpoints in lookup tables	2-4
	cgsl_0103: Precalculated signals and parameters	2-5
	cgsl_0104: Modeling global shared memory using data stores	2-8
	cgsl_0105: Modeling local shared memory using data stores	2-12
	Modeling Pattern Considerations	
3		
	cgsl_0201: Redundant Unit Delay and Memory blocks	3-2
	cgsl_0202: Usage of For, While, and For Each subsystems with vector signals	3-7

cgs1_0204: Vector and bus signals crossing into atomic subsystems or Model blocks	3-9
cgs1_0205: Signal handling for multirate models	3-14
cgs1_0206: Data integrity and determinism in multitasking models	3-16

Configuration Parameter Considerations

4

cgs1_0301: Prioritization of code generation objectives for code efficiency	4-2
cgs1_0302: Diagnostic settings for multirate and multitasking models	4-3

Introduction

- “Motivation” on page 1-2
- “Guideline Template” on page 1-3

Motivation

MathWorks® intends this document for engineers developing models and generating code for embedded systems using Model-Based Design with MathWorks products. The document focus is on model settings, block usage, and block parameters that impact simulation behavior or code generation.

This document does not address model style or development processes. For more information about creating models in a way that improves consistency, clarity, and readability, see the “MAAB Control Algorithm Modeling”. Development process guidance and additional information for specific standards is available with the IEC Certification Kit (for ISO 26262 and IEC 61508) and DO Qualification Kit (for DO-178) products.

Disclaimer While adhering to the recommendations in this document will reduce the risk that an error is introduced during development and not be detected, it is not a guarantee that the system being developed will be safe. Conversely, if some of the recommendations in this document are not followed, it does not mean that the system being developed will be unsafe.

Guideline Template

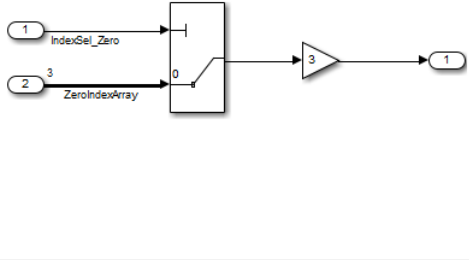
Guideline descriptions are documented, using the following template. Companies that want to create additional guidelines are encouraged to use the same template.

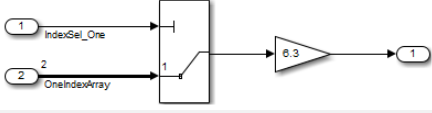
ID: Title	<i>XX_nnnn</i> : Title of the guideline (unique, short)
Description	Description of the guideline
Prerequisites	Links to guidelines that are prerequisites to this guideline (ID: Title)
Notes	Notes for using the guideline
Rationale	Rational for providing the guideline
Model Advisor Check	Title of and link to the corresponding Model Advisor check, if a check exists
References	References to standards that apply to guideline
See Also	Links to additional information
Last Changed	Version number of last change
Examples	Guideline examples

Block Considerations

- “cgsl_0101: Zero-based indexing” on page 2-2
- “cgsl_0102: Evenly spaced breakpoints in lookup tables” on page 2-4
- “cgsl_0103: Precalculated signals and parameters” on page 2-5
- “cgsl_0104: Modeling global shared memory using data stores” on page 2-8
- “cgsl_0105: Modeling local shared memory using data stores” on page 2-12

cgsl_0101: Zero-based indexing

ID: Title	cgsl_0101: Zero-based indexing	
Description	Use zero-based indexing for blocks that require indexing. To set up zero-based indexing, do one of the following:	
	A	Select block parameter Use zero-based contiguous for the Index Vector block.
	B	Set block parameter Index mode to Zero-based for the following blocks: <ul style="list-style-type: none"> • Assignment • Selector • For Iterator
Notes	The C language uses zero-based indexing.	
Rationale	A, B	Use zero-based indexing for compatibility with integrated C code.
	A, B	Results in more efficient C code execution. One-based indexing requires a subtraction operation in generated code.
See Also	"hisl_0021: Consistent vector indexing method"	
Last Changed	R2011b	
Examples		
	<p>Recommended</p> <pre>void ZeroIndex(void) { Y.Out5 = 3.0 * ZeroIndexArray[IndexSel_Zero]; }</pre>	

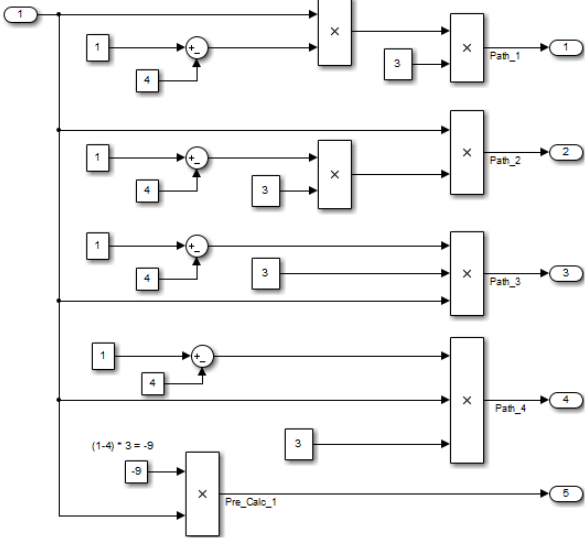
ID: Title	cgs1_0101: Zero-based indexing
	 <p>Not Recommended</p> <pre>void OneIndex(void) { Y.Out1 = OneIndexArray[IndexSel_One - 1] * 6.3; }</pre>

cgsl_0102: Evenly spaced breakpoints in lookup tables

ID: Title	cgsl_0102: Evenly spaced breakpoints in lookup tables	
Description	When you use Lookup Table and Prelookup blocks,	
	A	With <i>non-fixed-point data types</i> , use evenly spaced data breakpoints for the input axis
	B	With <i>fixed-point data types</i> , use power of two spaced breakpoints for the input axis
Notes	Evenly-spaced breakpoints can prevent generated code from including division operations, resulting in faster execution.	
Rationale	A	Improve ROM usage and execution speed.
	B	<p>Improve execution speed.</p> <p>When compared to unevenly-spaced data, power-of-two data can</p> <ul style="list-style-type: none"> • Increase data RAM usage if you require a finer step size • Reduce accuracy if you use a coarser step size <p>Compared to an evenly-spaced data set, there should be minimal cost in memory or accuracy.</p>
Model Advisor Checks	Embedded Coder > “Identify questionable fixed-point operations”	
See Also	“Formulation of Evenly Spaced Breakpoints” in the Simulink® documentation	
Last Changed	R2010b	

cgsl_0103: Precalculated signals and parameters

ID: Title	cgsl_0103: Precalculated signals and parameters	
Description	Precalculate invariant parameters and signals by doing one of the following:	
	A	Manually precalculate the values
	B	Enable the following model optimization parameters: <ul style="list-style-type: none"> • Optimization > Signals and Parameters > Simulation and code generation > Inline parameters • Optimization > Signals and Parameters > Code generation > Signals > Inline invariant signals
Notes	Precalculating variables can reduce local and global memory usage and improve execution speed. If you select Inline parameters and Inline invariant signals , the code generator minimizes the number of run-time calculations by maximizing the number calculations completed before runtime. In some cases, this can lead to a reduction in the number of parameters stored. However, the algorithms the code generator uses have limitations. In some cases, the code is more compact if you calculate the values outside of the Simulink environment. This can improve model efficiency, but can reduce model readability.	
Rationale	A, B	Precalculate data, outside of the Simulink environment, to reduce memory requirements of a system and improve run-time execution.
Last Changed	R2012b	
Examples	In the following model, the four paths are mathematically equivalent. However, due to algorithm limitations, the number of run-time calculations for the paths differs.	

ID: Title	cgsl_0103: Precalculated signals and parameters
	 <pre> Path_1 = InputSignal * -3.0 * 3.0; /* Product: '<Root>/Product4' incorporates: * Inport: '<Root>/In1' */ Path_2 = InputSignal * -9.0; /* Product: '<Root>/Product2' incorporates: * Constant: '<Root>/Constant2' * Inport: '<Root>/In1' */ Path_3 = -9.0 * InputSignal; /* Product: '<Root>/Product5' incorporates: * Constant: '<Root>/Constant2' * Inport: '<Root>/In1' */ Path_4 = -3.0 * InputSignal * 3.0; /* Product: '<Root>/Product6' incorporates: * Constant: '<Root>/Constant3' * Inport: '<Root>/In1' </pre>

ID: Title	cgsl_0103: Precalculated signals and parameters
	<pre data-bbox="522 303 979 355">*/ Pre_Calc_1 = -9.0 * InputSignal;</pre> <p data-bbox="522 381 1313 442">To maximize automatic precalculation, add signals at the end of the set of equations.</p> <p data-bbox="522 468 1291 590">Inlining data reduces the ability to tune model parameters. You should define parameters that require calibration to allow calibration. For more information, see “Parameters” in the Simulink Coder™ documentation.</p>

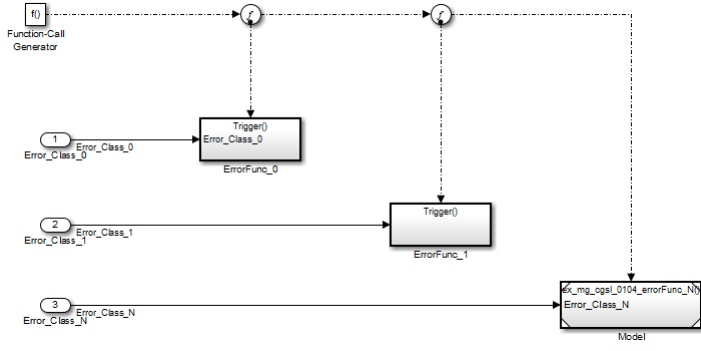
cgsl_0104: Modeling global shared memory using data stores

ID: Title	cgsl_0104: Modeling global shared memory using data stores	
Description	When using data store blocks to model shared memory across multiple models:	
	A	In the Configuration Parameters dialog box, on the Diagnostics pane, set Data Validity > Data Store Memory Block > Duplicate data store names to error for models in the hierarchy
	B	Define the data store using a Simulink Signal or MPT Signal object
Notes	C	Do not use Data Store Memory blocks in the models
	<p>If multiple Data Store blocks use the same data store name within a model, then Simulink interprets each instance of the data store as having a unique local scope.</p> <p>Use the diagnostic Duplicate data store names to help detect unintended identifier reuse. For models intentionally using local data stores, set the diagnostic to warning. Verify that only intentional data stores are included.</p> <p>Merge blocks, used in conjunction with subsystems operating in a mutually exclusive manor, provide a second method of modeling global data across multiple models.</p>	
Rationale	A, B, C	Promotes a modeling pattern where a single consistent data store is used across models and a single global instance is created in the generated code.
See Also	<ul style="list-style-type: none"> • “hisl_0013: Usage of data store blocks” • “hisl_0015: Usage of Merge blocks” • “cgsl_0302: Diagnostic settings for multirate and multitasking models” • “cgsl_0105: Modeling local shared memory using data stores” 	
Last Changed	R2011b	

ID: Title	cgs1_0104: Modeling global shared memory using data stores
Examples	<p>The following examples illustrate the use of data stores as global shared memory. The data store is used to model a global fault flag. A data store is required because the flag can be set in multiple functions and used in the same execution step.</p> <p>The top model contains three subsystems, each utilizing a data store memory. The data store is defined using a <code>mpt.Signal</code> object.</p> <p>mpt.Signal: errorFlag</p> <p>Data type: <input type="text" value="uint16"/> <input type="button" value=">>"/></p> <p>Complexity: <input type="text" value="real"/></p> <p>Dimensions: <input type="text" value="1"/> Dimensions mode: <input type="text" value="Fixed"/></p> <p>Sample time: <input type="text" value="-1"/> Sample mode: <input type="text" value="Sample based"/></p> <p>Minimum: <input type="text" value="[]"/> Maximum: <input type="text" value="[]"/></p> <p>Initial value: <input type="text" value="0"/> Units: <input type="text" value="Error Flag"/></p> <p>Code generation options</p> <p>Storage class: <input type="text" value="Global (Custom)"/></p> <p>Custom attributes</p> <p>Memory section: <input type="text" value="Default"/></p> <p>Header file: <input type="text" value="importData.h"/></p> <p>Owner: <input type="text" value="cgs1_0104_top"/></p> <p>Definition file: <input type="text" value="importData.c"/></p> <p>Persistence level: <input type="text" value="1"/></p>

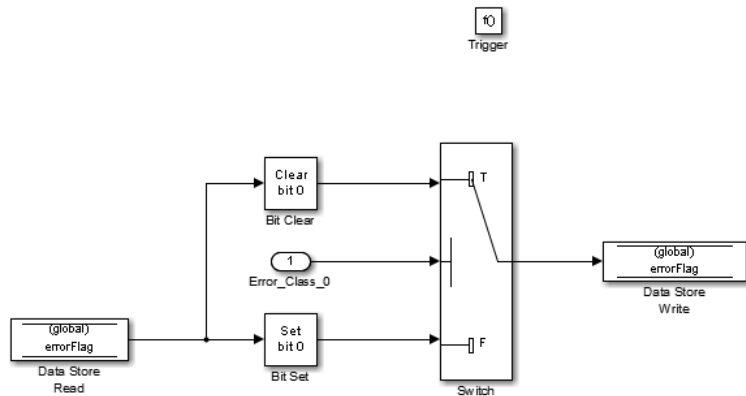
ID: Title

cgsl_0104: Modeling global shared memory using data stores



Recommended

In this example, there are no Data Store Memory blocks. The resulting code uses the same global variable for the full model.



ID: Title

cgs1_0104: Modeling global shared memory using data stores

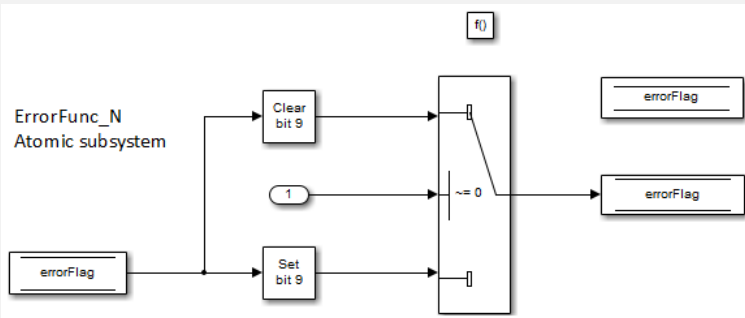
```

void cgs1_0104_top_ErrorFunc_0(void)
{
  if (Error_Class_0) {
    errorFlag = (uint16_T) (~((uint16_T) ((uint16_T) (~errorFlag)) | ((uint16_T) 1U)));
  } else {
    errorFlag = (uint16_T) (errorFlag | ((uint16_T) 1U));
  }
}

```

Not Recommended

In this example, a Data Store Memory block is added into the Model block subsystem. The model subsystem uses a local version of the data store. The Atomic Subsystem use a different version.



```

rtMdlrefDWork_mr_cgs1_0104_errc mr_cgs1_0104_errorF_MdlrefDWork;
void mr_cgs1_0104_errorFunc_N_UsedSM(const boolean_T *rtu_Error_Class_N)
{
  rtDW_mr_cgs1_0104_errorFunc_N_U *localDW =
    &(mr_cgs1_0104_errorF_MdlrefDWork.rtdw);
  if (*rtu_Error_Class_N) {
    localDW->errorFlag = (uint16_T) (~((uint16_T) ((uint16_T) (~localDW->errorFlag))
      | ((uint16_T) 512U)));
  } else {
    localDW->errorFlag = (uint16_T) (localDW->errorFlag | ((uint16_T) 512U));
  }
}

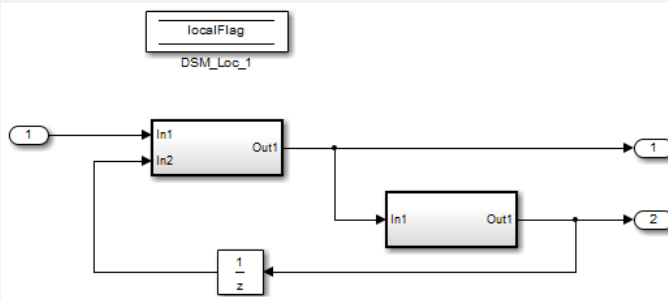
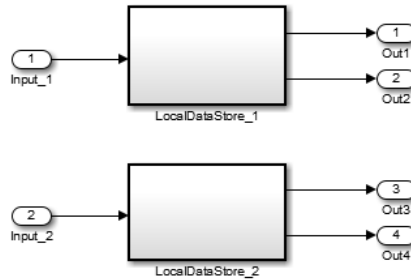
```

cgsl_0105: Modeling local shared memory using data stores

ID: Title	cgsl_0105: Modeling local shared memory using data stores	
Description	When using data store blocks as local shared memory:	
	A	Explicitly create the data store using a Data Store Memory block.
	B	Deselect the block parameter option Data store name must resolve to Simulink signal object .
	C	Consider following a naming convention for local Data Store Memory blocks.
Notes	<p>Use the diagnostic Duplicate data store names to help detect unintended identifier reuse. For models intentionally using local data stores, set the diagnostic to <code>warning</code>. Verify that only intentional data stores are included.</p> <p>Data store blocks are realized as global memory in the generated code. If they are not assigned a specific storage class, they are included in the DWork structure. In the model, the data store is scoped to the defining subsystem and below. In the generated code, the data store has file scope.</p>	
Rationale	A, B	Data store block is treated as a local instance of the data store
	C	Provides graphical feedback that the data store is local
See Also	<ul style="list-style-type: none"> • “cgsl_0104: Modeling global shared memory using data stores” • “cgsl_0302: Diagnostic settings for multirate and multitasking models” • “hisl_0013: Usage of data store blocks” 	
Last Changed	R2011b	
Examples	In some instances, such as a library function, reuse of a local data store is required. In this example the local data store is defined in two subsystems.	

ID: Title

cgsl_0105: Modeling local shared memory using data stores



The instance of localFlag is in scope within the subsystem LocalDataStore_1 and its subsystems.

```
/* Block signals and states (auto storage) for system '<Root>' */
typedef struct {
    real_I localFlag;           /* '<S2>/DSM_Loc_2' */
    real_I localFlag_k;        /* '<S1>/DSM_Loc_1' */
} D_Work_cgsl_0105;
```

In the generated code, the data stores are part of the global DWork structure for the model. Embedded Coder[®] automatically assigns them unique names during the code generation process.

Modeling Pattern Considerations

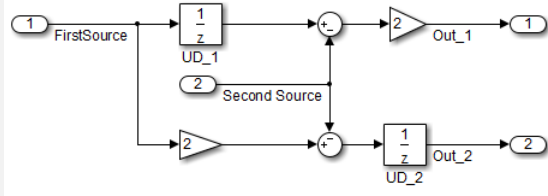
- “cgsl_0201: Redundant Unit Delay and Memory blocks” on page 3-2
- “cgsl_0202: Usage of For, While, and For Each subsystems with vector signals” on page 3-7
- “cgsl_0204: Vector and bus signals crossing into atomic subsystems or Model blocks” on page 3-9
- “cgsl_0205: Signal handling for multirate models” on page 3-14
- “cgsl_0206: Data integrity and determinism in multitasking models” on page 3-16

cgsl_0201: Redundant Unit Delay and Memory blocks

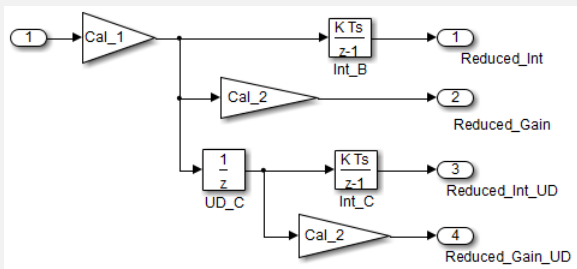
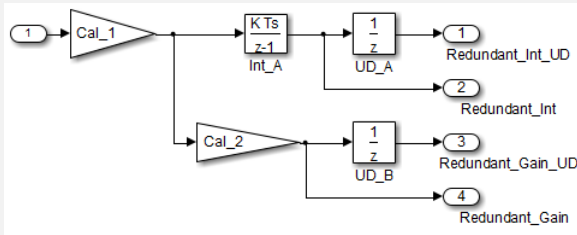
ID: Title	cgsl_0201: Redundant Unit Delay and Memory blocks	
Description	When preparing a model for code generation,	
	A	Remove redundant Unit Delay and Memory blocks.
Rationale	A	Redundant Unit Delay and Memory blocks use additional global memory. Removing the redundancies from a model reduces memory usage without impacting model behavior.
Last Changed	R2013a	
Example	<div data-bbox="327 656 813 838"> </div> <p data-bbox="327 873 798 904">Recommended: Consolidated Unit Delays</p> <pre data-bbox="327 933 1114 1055"> void Reduced(void) { ConsolidatedState_2 = Matrix_UD_Test - (Cal_1 * DWork.UD_3_DSTATE + Cal_2 * DWork.UD_3_DSTATE); DWork.UD_3_DSTATE = ConsolidatedState_2; } </pre>	
	<div data-bbox="327 1076 813 1275"> </div> <p data-bbox="327 1310 822 1341">Not Recommended: Redundant Unit Delays</p> <pre data-bbox="327 1371 1084 1512"> void Redundent(void) { RedundantState = (Matrix_UD_Test - Cal_2 * DWork.UD_1B_DSTATE) - Cal_1 * DWork.UD_1A_DSTATE; DWork.UD_1B_DSTATE = RedundantState; DWork.UD_1A_DSTATE = RedundantState; } </pre>	

ID: Title	cgs1_0201: Redundant Unit Delay and Memory blocks
	<p data-bbox="323 302 1310 427">Unit Delay and Memory blocks exhibit commutative and distributive algebraic properties. When the blocks are part of an equation with one driving signal, you can move the Unit Delay and Memory blocks to a new position in the equation without changing the result.</p> <div data-bbox="323 460 813 687" style="text-align: center;"> </div> <p data-bbox="323 723 1252 753">For the top path in the preceding example, the equations for the blocks are:</p> <ol data-bbox="323 805 825 923" style="list-style-type: none"> 1 $Out_1(t) = UD_1(t)$ 2 $UD_1(t) = In_1(t-1) * Cal_1$ 3 $Out_1(t) = In_1(t-1) * Cal_1$ <p data-bbox="323 953 810 982">For the bottom path, the equations are:</p> <ol data-bbox="323 1034 825 1152" style="list-style-type: none"> 1 $Out_2(t) = UD_2(t) * Cal_1$ 2 $UD_2(t) = In_2(t-1)$ 3 $Out_2(t) = In_2(t-1) * Cal_1$ <p data-bbox="323 1182 1329 1305">In contrast, if you add a secondary signal to the equations, the location of the Unit Delay block impacts the result. As the following example shows, the location of the Unit Delay block impacts the results due the skewing of the time sample between the top and bottom paths.</p>

ID: Title cgsl_0201: Redundant Unit Delay and Memory blocks



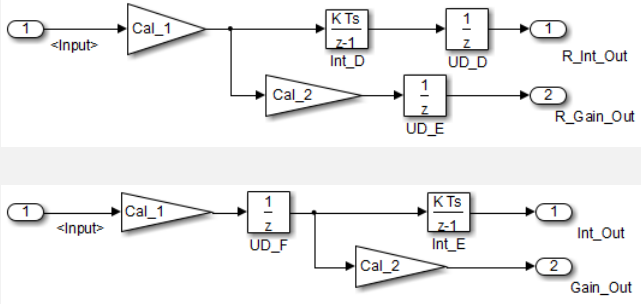
In cases with a single source and multiple destinations, the comparison is more complex. For example, in the following model, you can refactor the two Unit Delay blocks into a single unit delay.



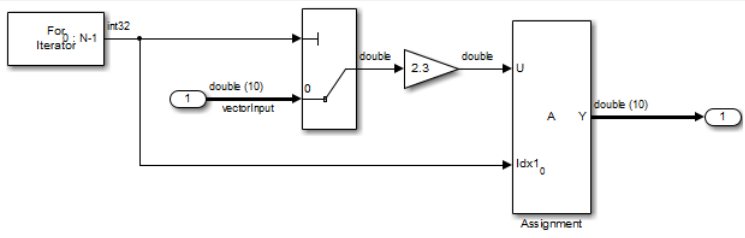
From a black box perspective, the two models are equivalent. However, from a memory and computation perspective, differences exist between the two models.

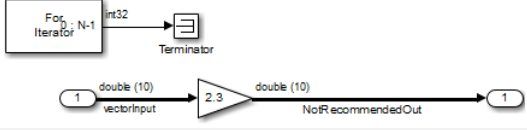
```
{
  real_T rtb_Gain4;
  rtb_Gain4 = Cal_1 * Redundant;
  Y.Redundant_Gain = Cal_2 * rtb_Gain4;
  Y.Redundant_Int = DWork.Int_A;
  Y.Redundant_Int_UD = DWork.UD_A;
  Y.Redundant_Gain_UD = DWork.UD_B;
}
```

ID: Title	cgsl_0201: Redundant Unit Delay and Memory blocks
	<pre> DWork.Int_A = 0.01 * rtb_Gain4 + DWork.Int_A; DWork.UD_A = Y.Redundant_Int; DWork.UD_B = Y.Redundant_Gain; } { real_T rtb_Gain1; real_T rtb_UD_C; rtb_Gain1 = Cal_1 * Reduced; rtb_UD_C = DWork.UD_C; Y.Reduced_Gain_UD = Cal_2 * DWork.UD_C; Y.Reduced_Gain = Cal_2 * rtb_Gain1; Y.Reduced_Int = DWork.Int_B; Y.Reduced_Int_UD = DWork.Int_C; DWork.UD_C = rtb_Gain1; DWork.Int_B = 0.01 * rtb_Gain1 + DWork.Int_B; DWork.Int_C = 0.01 * rtb_UD_C + DWork.Int_C; } { real_T rtb_Gain4_f; real_T rtb_Int_D; rtb_Gain4_f = Cal_1 * U.Input; rtb_Int_D = DWork.Int_D; Y.R_Int_Out = DWork.UD_D; Y.R_Gain_Out = DWork.UD_E; DWork.Int_D = 0.01 * rtb_Gain4_f + DWork.Int_D; DWork.UD_D = rtb_Int_D; DWork.UD_E = Cal_2 * rtb_Gain4_f; } </pre> <p>In this case, the original model is more efficient. In the first code example, there are three bits of global data, two from the Unit Delay blocks (DWork.UD_A and DWork.UD_B) and one from the discrete time integrator (DWork.Int_A). The second code example shows a reduction to one global variable generated by the unit delays (Dwork.UD_C), but there are two global variables due to the redundant Discrete Time Integrator blocks (DWork.Int_B and DWork.Int_C). The Discrete Time Integrator block path introduces an additional local variable (rtb_UD_C) and two additional computations.</p> <p>By contrast, the refactored model (second) below is more efficient.</p>

ID: Title	cgsl_0201: Redundant Unit Delay and Memory blocks
	 <pre data-bbox="326 642 1038 1215"> { real_T rtb_Gain4_f; real_T rtb_Int_D; rtb_Gain4_f = Cal_1 * U.Input; rtb_Int_D = DWork.Int_D; Y.R_Int_Out = DWork.UD_D; Y.R_Gain_Out = DWork.UD_E; DWork.Int_D = 0.01 * rtb_Gain4_f + DWork.Int_D; DWork.UD_D = rtb_Int_D; DWork.UD_E = Cal_2 * rtb_Gain4_f; } { real_T rtb_UD_F; rtb_UD_F = DWork.UD_F; Y.Gain_Out = Cal_2 * DWork.UD_F; Y.Int_Out = DWork.Int_E; DWork.UD_F = Cal_1 * U.Input; DWork.Int_E = 0.01 * rtb_UD_F + DWork.Int_E; } </pre> <p data-bbox="326 1241 1335 1302">The code for the refactored model is more efficient because the branches from the root signal do not have a redundant unit delay.</p>

cgs_l_0202: Usage of For, While, and For Each subsystems with vector signals

ID: Title	cgs_l_0202: Usage of For, While, and For Each subsystems with vector signals	
Description	When developing a model for code generation, <div style="display: flex; border-left: 1px solid black; border-right: 1px solid black; border-bottom: 1px solid black; padding: 5px;"> <div style="border-right: 1px solid black; padding: 5px; width: 50px; text-align: center;">A</div> <div style="padding: 5px;">Use For, While, and For Each subsystems for calculations that require iterative behavior or operate on a subset (frame) of data.</div> </div> <div style="display: flex; border-left: 1px solid black; border-right: 1px solid black; border-bottom: 1px solid black; padding: 5px;"> <div style="border-right: 1px solid black; padding: 5px; width: 50px; text-align: center;">B</div> <div style="padding: 5px;">Avoid using For, While, or For Each subsystems for basic vector operations.</div> </div>	
Rationale	A, B	Avoid redundant loops.
See Also	<ul style="list-style-type: none"> • “Loop unrolling threshold ” in the Simulink documentation • MathWorks Automotive Advisor Board guideline “db_0117: Simulink patterns for vector signals” 	
Last Changed	R2010b	
Examples	<p>The recommended method for preceding calculation is to place the Gain block outside the For Subsystem. If the calculations are required as part of a larger algorithm, you can avoid the nesting of for loops by using Index Vector and Assignment blocks.</p> <div style="text-align: center;">  </div> <p>Recommended</p> <pre>for (s1_iter = 0; s1_iter < 10; s1_iter++) { RecommendedOut[s1_iter] = 2.3 * vectorInput[s1_iter]; }</pre> <p>A common mistake is to embed basic vector operations in a For, While, or For Each subsystem. The following example includes a simple vector gain inside a For subsystem, which results in unnecessary nested for loops.</p>	

ID: Title	cgsl_0202: Usage of For, While, and For Each subsystems with vector signals
	 <p>The diagram illustrates a modeling pattern. At the top, a 'For Iterator' block with '0' and 'N-1' is connected to a 'Terminator' block. Below this, a signal flow starts with a 'double (10)' signal entering a 'vectorInput' block. This signal then passes through a gain block labeled '2.3'. The output is a 'double (10)' signal labeled 'NotRecommendedOut'.</p> <p>Not Recommended</p> <pre> for (s1_iter = 0; s1_iter < 10; s1_iter++) { for (i = 0; i < 10; i++) { NotRecommendedOut[i] = 2.3 * vectorInput[i]; } } </pre>

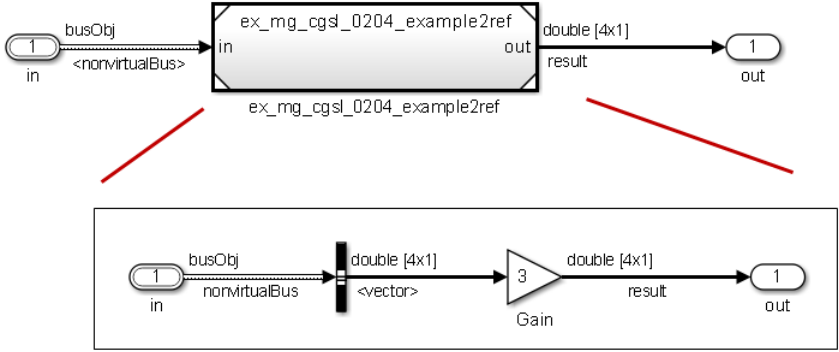
cgs_l_0204: Vector and bus signals crossing into atomic subsystems or Model blocks

ID: Title	cgs_l_0204: Vector and bus signals crossing into atomic subsystems or Model blocks		
Description	When working with vector or bus signals and some of the signal elements are in an atomic subsystem or a referenced model, use the following information to determine how to select signal elements to minimize memory usage.		
A	Bus or vector entering an atomic subsystem:		
	Function packaging: Non-reusable function		
	Function interface: void_void		
		Signals selected outside subsystem results in...	Signal selected inside subsystem results in...
	Virtual Bus	No data copies.	No data copies.
	Nonvirtual Bus	No data copies.	No data copies.
	Vector	A copy of the selected signals in global block I/O structure that is used in the function.	No data copies.
	Function packaging: Non-reusable function		
	Function interface: Allow arguments		
		Signals selected outside subsystem results in	Signal selected inside subsystem results in
Virtual Bus	No data copies. Only the selected signals are passed to the function.	No data copies. Only the selected signals are passed to the function.	

ID: Title	cgsl_0204: Vector and bus signals crossing into atomic subsystems or Model blocks					
		Nonvirtual Bus	No data copies. Only the selected signals are passed to the function.	No data copies. The whole bus is passed to the function.		
		Vector	A copy of the selected signals in a local variable that is passed to the function.	No data copies. The whole vector is passed to the function.		
	Function packaging: Reusable function					
		Signals selected outside subsystem results in	Signal selected inside the subsystem results in			
		Virtual Bus	No data copies. Only the selected signals are passed to the function.	No data copies. Only the selected signals are passed to the function.		
		Nonvirtual Bus	No data copies. Only the selected signals are passed to the function. See Example 1.	No data copies. The whole bus is passed to the function.		
		Vector	A copy of the selected signals in a local variable that is passed to the function.	No data copies. The whole vector is passed to the function.		

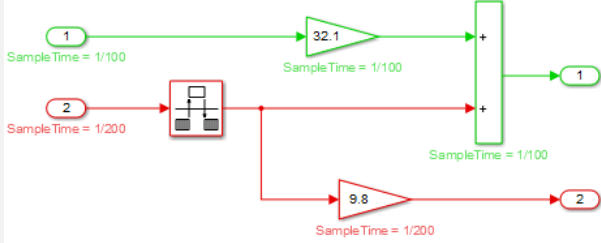
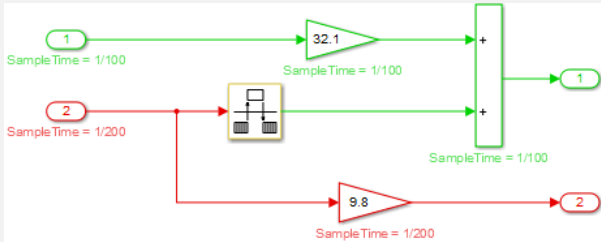
ID: Title	cgs_0204: Vector and bus signals crossing into atomic subsystems or Model blocks										
	B	Bus or vector entering a Model block:									
			<table border="1"> <thead> <tr> <th data-bbox="773 390 1055 499">Signals selected outside subsystem results in...</th> <th data-bbox="1055 390 1338 499">Signal selected inside subsystem results in...</th> </tr> </thead> <tbody> <tr> <td data-bbox="773 499 1055 640">Virtual Bus</td> <td data-bbox="1055 499 1338 640">No data copies. Only selected signals are passed to the function.</td> </tr> <tr> <td data-bbox="773 640 1055 781">Nonvirtual Bus</td> <td data-bbox="1055 640 1338 781">No data copies. The whole bus is passed to the function. See Example 2.</td> </tr> <tr> <td data-bbox="773 781 1055 960">Vector</td> <td data-bbox="1055 781 1338 960">A copy of the selected signals in a local variable that is passed to the function.</td> </tr> </tbody> </table>	Signals selected outside subsystem results in...	Signal selected inside subsystem results in...	Virtual Bus	No data copies. Only selected signals are passed to the function.	Nonvirtual Bus	No data copies. The whole bus is passed to the function. See Example 2.	Vector	A copy of the selected signals in a local variable that is passed to the function.
Signals selected outside subsystem results in...	Signal selected inside subsystem results in...										
Virtual Bus	No data copies. Only selected signals are passed to the function.										
Nonvirtual Bus	No data copies. The whole bus is passed to the function. See Example 2.										
Vector	A copy of the selected signals in a local variable that is passed to the function.										
Notes	<ul style="list-style-type: none"> • Depending on Embedded Coder settings (e.g. optimizations), predecessor blocks and signal storage classes, actual results may differ from the tables. • Virtual busses do not support global data. • If the subsystem is set to Inline, data copies do not occur. 										
Rationale	A, B	Minimize RAM, ROM, and stack usage									
Last Changed	R2014a										
Examples											

ID: Title	cgsl_0204: Vector and bus signals crossing into atomic subsystems or Model blocks
	<p>Example 1: Nonvirtual bus entering an atomic subsystem</p> <ul style="list-style-type: none"> • Function packaging: Reusable function • Selection: Sub-signal selected outside the subsystem <p>Only the selected signals are passed to the function:</p> <pre> 6 void Function(const real_T rtu_in[4], real_T rty_out[4]) 7 { 8 rty_out[0] = 3.0 * rtu_in[0]; 9 rty_out[1] = 3.0 * rtu_in[1]; 10 rty_out[2] = 3.0 * rtu_in[2]; 11 rty_out[3] = 3.0 * rtu_in[3]; 12 } 13 14 void ex_mg_cgsl_0204_example1_step(void) 15 { 16 Function(&nonvirtualBus.vector[0], Y.Out1); 17 } </pre>

ID: Title	cgs1_0204: Vector and bus signals crossing into atomic subsystems or Model blocks
	<p>Example 2: Nonvirtual bus entering a model block</p> <ul style="list-style-type: none"> • Total number of instances allowed per top model: Multiple • Selection: Sub-signal selected inside the referenced model  <p>The diagram illustrates a model block named 'ex_mg_cgs1_0204_example2ref'. It has an input port 'in' connected to a bus signal 'busObj' of type '<nonvirtualBus>'. The block's output is 'out', which is a 'double [4x1]' vector signal. A red arrow points from the block to a detailed view of its internal structure. This view shows the bus signal 'busObj' entering a 'nonvirtualBus' block, which then feeds into a 'Gain' block with a gain of 3. The output of the gain block is a 'double [4x1]' vector signal labeled 'result', which is then connected to the 'out' port of the model block.</p>
	<p>There are no data copies in the code for the main model. The whole bus is passed to the model reference function.</p> <pre data-bbox="427 1060 1283 1156"> 6 void ex_mg_cgs1_0204_example2_step(void) 7 { 8 ex_mg_cgs1_0204_example2ref(&ex_mg_cgs1_0204_example2_U.nonvirtualBus, 9 &ex_mg_cgs1_0204_example2_Y.Out1[0]); </pre> <p>Code for the model reference function:</p> <pre data-bbox="427 1263 1283 1428"> 4 void ex_mg_cgs1_0204_example2ref(const busObj *rtu_in, real_T rty_out[4]) 5 { 6 rty_out[0] = 3.0 * rtu_in->vector[0]; 7 rty_out[1] = 3.0 * rtu_in->vector[1]; 8 rty_out[2] = 3.0 * rtu_in->vector[2]; 9 rty_out[3] = 3.0 * rtu_in->vector[3]; 10 } </pre>

cgsl_0205: Signal handling for multirate models

ID: Title	cgsl_0205: Signal handling for multirate models	
Description	For multirate models, handle the change in operation rate in one of two ways:	
	A	At the destination block, Insert a Rate Transition.
	B	Set the parameter Solver > Automatically handle rate transition for data transfer to either Always or Whenever possible .
Rationale	A,B	Following this guideline supports the handling of data operating at different rates.
Note	<p>Setting the parameter Solver > Automatically handle rate transition for data transfer with the setting to Whenever possible requires inserting a Rate Transition block in locations indicated by Simulink.</p> <p>Setting the parameter Solver > Automatically handle rate transition for data transfer to Always allows Simulink to automatically handle rate transitions by inserting a Rate Transition block. The following exceptions apply:</p> <ul style="list-style-type: none"> • The insertion of a Rate Transition block requires rewiring the block diagram. • Multiple Rate Transition blocks are required: <ul style="list-style-type: none"> • The blocks' sample times are not integer multiples of each other • The blocks use different sample time offsets • One of the rates is asynchronous • An inserted Rate Transition block can have multiple valid configurations. <p>For these cases, manually insert a Rate Transition block or blocks.</p> <p>MathWorks does not recommend using Unit Delay and Zero Order Hold blocks for handling rate transitions.</p>	
Last Changed	R2011a	
Examples	<p>Not Recommended:</p> <p>In this example, the Rate Transition block is inserted at the source, not at the destination of the signal. The model fails to update because the</p>	

ID: Title	cgs_l_0205: Signal handling for multirate models
	<p>two destination blocks (Gain and Sum) run at different rates. To fix this error, insert Rate Transition blocks at the signal destinations and remove Rate Transition blocks from the signal sources. Failure to remove the Rate Transition blocks is a common modeling pattern that might result in errors and inefficient code.</p>  <p>Recommended:</p> <p>In this example, the rate transition is inserted at the destination of the signal.</p> 

cgsl_0206: Data integrity and determinism in multitasking models

ID: Title	cgsl_0206: Data integrity and determinism in multitasking models	
Description	For multitasking models that are deployed with a preemptive (interruptible) operating system, protect the integrity of selected signals by doing one of the following:	
	A	Select the Rate Transition block parameter Ensure data integrity during data transfer .
	B	For Inport blocks in Function Called subsystems, select the block parameter Latch input for feedback signals of function-call subsystem outputs .
	To protect selected signal determinism, do one of the following:	
	C	Select the Rate Transition block parameter Ensure deterministic data transfer (maximum delay) .
	D	<ul style="list-style-type: none"> • Select the model parameter Solver > Automatically handle rate transition for data transfer. • Set the model parameter Solver > Deterministic data transfer to either Whenever possible or Always.
Prerequisites	“cgsl_0205:Signal handling for multirate models”	
Rationale	A,B, C,D	Following this guideline protects data against possible corruption of preemptive (interruptible) operating systems.
Note	<p>Multitasking systems with a non-preemptive operating system do not require data integrity or determinism protection. In this case, clear the parameters Ensure data integrity during data transfer and Ensure deterministic data transfer.</p> <p>Ensuring data integrity and determinism requires additional memory and execution time. To reduce this additional expense, evaluate signals to determine the level of protection that they require.</p>	
See Also	<ul style="list-style-type: none"> • “Rate Transition” • “Data Transfer Problems” 	
Last Changed	R2011a	

Configuration Parameter Considerations

- “cgs1_0301: Prioritization of code generation objectives for code efficiency” on page 4-2
- “cgs1_0302: Diagnostic settings for multirate and multitasking models” on page 4-3

cgsl_0301: Prioritization of code generation objectives for code efficiency

ID: Title	cgsl_0301: Prioritization of code generation objectives for code efficiency	
Description	Prioritize code generation objectives for code efficiency by using the Code Generation Advisor.	
	A	Assign priorities to code (ROM, RAM, and Execution efficiency) efficiency objectives.
	B	Select the relative order of ROM, RAM, and Execution efficiency based on application requirements.
	C	Configure the Code Generation Advisor to run before generating code by setting Check model before generating code on the Code Generation pane of the Configuration Parameters dialog box to On (proceed with warnings) or On (stop for warnings).
Notes	<p>A model's configuration parameters provide control over many aspects of generated code. The prioritization of objectives specifies how configuration parameters are set when conflicts between objectives occur.</p> <p>Prioritizing code efficiency objectives above safety objectives may remove initialization or run-time protection code (for example, saturation range checking for signals out of representable range). Review the resulting parameter configurations to verify that safety requirements are met. For more information about objective tradeoffs for each model parameter, see “Application Considerations” in the Embedded Coder documentation.</p>	
Rationale	A, B, C	When you use the Code Generation Advisor, configuration parameters conform to the objectives that you want and they are consistently enforced.
See also	<ul style="list-style-type: none"> • “Set Objectives — Code Generation Advisor Dialog Box” in the Simulink Coder documentation • “Manage a Configuration Set” in the Simulink documentation • “hisl_0055: Prioritization of code generation objectives for high-integrity systems” 	
Last Changed	R2010b	

cgs1_0302: Diagnostic settings for multirate and multitasking models

ID: Title	cgs1_0302: Diagnostic settings for multirate and multitasking models
Description	<p>For multirate models using either single tasking or multitasking, set to either warning or error the following diagnostics:</p> <ul style="list-style-type: none"> • Diagnostics > Sample Time > Single task rate transition • Diagnostics > Sample Time > Enforce sample time specified by Signal Specification blocks • Diagnostics > Data Validity > Merge Block > Detect multiple driving blocks executing at the same time step <p>For multitasking models, set to either warning or error the following diagnostics:</p> <ul style="list-style-type: none"> • Diagnostics > Sample Time > Multitask task rate transition • Diagnostics > Sample Time > Multitask conditionally executed subsystem • Diagnostics > Sample Time > Tasks with equal priority <p>If the model contains Data Store Memory blocks, set to either Enable all as warnings or Enable all as errors the following diagnostics:</p> <ul style="list-style-type: none"> • Diagnostics > Data Validity > Data Store Memory Block > Detect read before write • Diagnostics > Data Validity > Data Store Memory Block > Detect write after read • Diagnostics > Data Validity > Data Store Memory Block > Detect write after write • Diagnostics > Data Validity > Data Store Memory Block > Multitask data store
Rationale	Setting the diagnostics improves run-time detection of rate and tasking errors.
See Also	<ul style="list-style-type: none"> • “Diagnostics Pane: Solver” • “his1_0013: Usage of data store blocks” • “his1_0044: Configuration Parameters > Diagnostics > Sample Time”

ID: Title	cgs1_0302: Diagnostic settings for multirate and multitasking models
Last Changed	2011a