About This Manual

DSP/BIOS gives developers of mainstream applications on Texas Instruments TMS320C5000™ DSP devices the ability to develop embedded real-time software. DSP/BIOS provides a small firmware real-time library and easy-to-use tools for real-time tracing and analysis.

You should read and become familiar with the *TMS320 DSP/BIOS User’s Guide*, a companion volume to this API reference guide.

Before you read this manual, you may use the *Code Composer Studio* online tutorial and the DSP/BIOS section of the online help to get an overview of DSP/BIOS. This manual discusses various aspects of DSP/BIOS in depth and assumes that you have at least a basic understanding of DSP/BIOS.

Notational Conventions

This document uses the following conventions:

- Program listings, program examples, and interactive displays are shown in a special typeface. Examples use a **bold version** of the special typeface for emphasis; interactive displays use a **bold version** of the special typeface to distinguish commands that you enter from items that the system displays (such as prompts, command output, error messages, etc.).

  Here is a sample program listing:

  ```
  Void copy(HST_Obj *input, HST_Obj *output)
  {
    PIP_Obj     *in, *out;
    Uns         *src, *dst;
    Uns         size;
  }
  ```

- Square brackets ([ and ]) identify an optional parameter. If you use an optional parameter, you specify the information within the brackets. Unless the square brackets are in a **bold** typeface, do not enter the brackets themselves.

Related Documentation From Texas Instruments

The following books describe TMS320 devices and related support tools. To obtain a copy of any of these TI documents, call the Texas Instruments Literature Response Center at (800) 477-8924. When ordering, please identify the book by its title and literature number.

* **TMS320 DSP/BIOS User’s Guide** (literature number SPRU423) provides an overview and description of the DSP/BIOS real-time operating system.*
**TMS320C55x Optimizing C Compiler User’s Guide** (literature number SPRU281) describes the C55x C compiler. This C compiler accepts ANSI standard C source code and produces TMS320 assembly language source code for the C55x generation of devices.

**TMS320C55x Programmer’s Guide** (literature number SPRU376) describes ways to optimize C and assembly code for the TMS320C55x DSPs and includes application program examples.

**TMS320C55x Code Composer Studio Tutorial Online Help** (literature number SPRH097) introduces the Code Composer Studio integrated development environment and software tools. Of special interest to DSP/BIOS users are the Using DSP/BIOS lessons.

### Related Documentation

You can use the following books to supplement this reference guide:


**Programming in C**, Kochan, Steve G., Hayden Book Company


**American National Standard for Information Systems-Programming Language C** X3.159-1989, American National Standards Institute (ANSI standard for C); (out of print)

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August 29, 2012
# Contents

1 API Functional Overview ................................. 8  
   1.1 DSP/BIOS Modules ........................................... 8  
   1.2 Naming Conventions ......................................... 9  
   1.3 Assembly Language Interface Overview .................... 9  
   1.4 DSP/BIOS Tconf Overview .................................. 10  
   1.5 List of Operations ....................................... 11  

2 Application Program Interface .......................... 22  
   2.1 ATM Module ................................................. 23  
   2.2 BUF Module ................................................. 36  
   2.3 C55 Module ................................................. 46  
   2.4 CLK Module ................................................. 59  
   2.5 DEV Module ................................................. 77  
   2.6 GBL Module ............................................... 119  
   2.7 GIO Module ................................................. 128  
   2.8 HOOK Module .............................................. 144  
   2.9 HST Module ................................................. 149  
   2.10 HWI Module .............................................. 153  
   2.11 IDL Module ............................................... 173  
   2.12 LCK Module ............................................... 177  
   2.13 LOG Module .............................................. 183  
   2.14 MBX Module ............................................... 195  
   2.15 MEM Module .............................................. 201  
   2.16 MSGQ Module ............................................. 224  
   2.17 PIP Module ............................................... 259  
   2.18 POOL Module ............................................. 277  
   2.19 PRD Module .............................................. 281  
   2.20 PWRM Module ............................................ 288  
   2.21 QUE Module .............................................. 323  
   2.22 RTDX Module ............................................ 338  
   2.23 SEM Module .............................................. 354  
   2.24 SIO Module .............................................. 365  
   2.25 STS Module .............................................. 390  
   2.26 SWI Module .............................................. 399  
   2.27 SYS Module ............................................. 426  
   2.28 TRC Module ............................................. 442  
   2.29 TSK Module ............................................. 446  
   2.30 std.h and stdlib.h functions ................................ 482  

A Function Callability and Error Tables ..................... 484  
   A.1 Function Callability Table ................................ 484  
   A.2 DSP/BIOS Error Codes .................................... 491  

B C55x DSP/BIOS Register Usage .......................... 493  
   B.1 Overview .................................................. 493
<table>
<thead>
<tr>
<th>Figure</th>
<th>Description</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>2-1</td>
<td>MYSEG Heap Initial Memory Map</td>
<td>212</td>
</tr>
<tr>
<td>2-2</td>
<td>MYSEG Memory Map After Allocation</td>
<td>213</td>
</tr>
<tr>
<td>2-3</td>
<td>MYSEG Memory Map After Modified Allocation</td>
<td>214</td>
</tr>
<tr>
<td>2-4</td>
<td>Writers and Reader of a Message Queue</td>
<td>227</td>
</tr>
<tr>
<td>2-5</td>
<td>Components of the MSGQ Architecture</td>
<td>227</td>
</tr>
<tr>
<td>2-6</td>
<td>MSGQ Function Calling Sequence</td>
<td>228</td>
</tr>
<tr>
<td>2-7</td>
<td>Pipe Schematic</td>
<td>260</td>
</tr>
<tr>
<td>2-8</td>
<td>Allocators and Message Pools</td>
<td>278</td>
</tr>
<tr>
<td>2-9</td>
<td>Buffer Layout as Defined by STATICPOOL_Params</td>
<td>280</td>
</tr>
<tr>
<td>2-10</td>
<td>PRD Tick Cycles</td>
<td>285</td>
</tr>
<tr>
<td>2-11</td>
<td>Statistics Accumulation on the Host</td>
<td>392</td>
</tr>
</tbody>
</table>
## Tables

<table>
<thead>
<tr>
<th>Table</th>
<th>Description</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>1-2</td>
<td>DSP/BIOS Operations</td>
<td>11</td>
</tr>
<tr>
<td>2-1</td>
<td>Timer Counter Rates, Targets, and Resets</td>
<td>61</td>
</tr>
<tr>
<td>2-2</td>
<td>High-Resolution Time Determination</td>
<td>62</td>
</tr>
<tr>
<td>2-3</td>
<td>HWI interrupts for the ‘C55x</td>
<td>160</td>
</tr>
<tr>
<td>2-4</td>
<td>Conversion Characters for LOG_printf</td>
<td>191</td>
</tr>
<tr>
<td>2-5</td>
<td>Typical Memory Segments for C5000 Boards</td>
<td>210</td>
</tr>
<tr>
<td>2-6</td>
<td>Statistics Units for HWI, PIP, PRD, and SWI Modules</td>
<td>391</td>
</tr>
<tr>
<td>2-7</td>
<td>Conversion Characters Recognized by SYS_printf</td>
<td>433</td>
</tr>
<tr>
<td>2-8</td>
<td>Conversion Characters Recognized by SYS_sprintf</td>
<td>435</td>
</tr>
<tr>
<td>2-9</td>
<td>Conversion Characters Recognized by SYS_vprintf</td>
<td>437</td>
</tr>
<tr>
<td>2-10</td>
<td>Conversion Characters Recognized by SYS_vsprintf</td>
<td>439</td>
</tr>
<tr>
<td>2-11</td>
<td>Events and Statistics Traced by TRC</td>
<td>442</td>
</tr>
<tr>
<td>A-1</td>
<td>Function Callability</td>
<td>484</td>
</tr>
<tr>
<td>A-2</td>
<td>RTS Function Calls</td>
<td>491</td>
</tr>
<tr>
<td>A-3</td>
<td>Error Codes</td>
<td>491</td>
</tr>
</tbody>
</table>
This chapter provides an overview to the TMS320C55x DSP/BIOS API functions.

### Table 1–1. DSP/BIOS Modules

<table>
<thead>
<tr>
<th>Module</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ATM Module</td>
<td>Atomic functions written in assembly language</td>
</tr>
<tr>
<td>BUF Module</td>
<td>Maintains buffer pools of fixed size buffers</td>
</tr>
<tr>
<td>C55 Module</td>
<td>Target-specific functions</td>
</tr>
<tr>
<td>CLK Module</td>
<td>System clock manager</td>
</tr>
<tr>
<td>DEV Module</td>
<td>Device driver interface</td>
</tr>
<tr>
<td>GBL Module</td>
<td>Global setting manager</td>
</tr>
<tr>
<td>GIO Module</td>
<td>I/O module used with IOM mini-drivers</td>
</tr>
<tr>
<td>HOOK Module</td>
<td>Hook function manager</td>
</tr>
<tr>
<td>HST Module</td>
<td>Host channel manager</td>
</tr>
<tr>
<td>HWI Module</td>
<td>Hardware interrupt manager</td>
</tr>
<tr>
<td>IDL Module</td>
<td>Idle function and processing loop manager</td>
</tr>
<tr>
<td>LCK Module</td>
<td>Resource lock manager</td>
</tr>
<tr>
<td>LOG Module</td>
<td>Event Log manager</td>
</tr>
<tr>
<td>MBX Module</td>
<td>Mailboxes manager</td>
</tr>
<tr>
<td>MEM Module</td>
<td>Memory manager</td>
</tr>
<tr>
<td>MSGQ Module</td>
<td>Variable-length message manager</td>
</tr>
</tbody>
</table>

1. **DSP/BIOS Modules**

1.1 **DSP/BIOS Modules**

Table 1–1. DSP/BIOS Modules
1.2 Naming Conventions

The format for a DSP/BIOS operation name is a 3- or 4-letter prefix for the module that contains the operation, an underscore, and the action.

1.3 Assembly Language Interface Overview

The assembly interface that was provided for some of the DSP/BIOS APIs has been deprecated. They are no longer documented.

Assembly functions can call C functions. Remember that the C compiler adds an underscore prefix to function names, so when calling a C function from assembly, add an underscore to the beginning of the C function name. For example, call _myfunction instead of myfunction. See the TMS320C55x Optimizing Compiler User’s Guide for more details.

When you are using the DSP/BIOS Configuration Tool, use a leading underscore before the name of any C function you configure. (The DSP/BIOS Configuration Tool generates assembly code, but does not add the underscore automatically.) If you are using Tconf, do not add an underscore before the function name; Tconf internally adds the underscore needed to call a C function from assembly.

All DSP/BIOS APIs follow standard C calling conventions as documented in the C programmer’s guide for the device you are using.

DSP/BIOS APIs save and restore context for each thread during a context switch. Your code should simply follow standard C register usage conventions. Code written in assembly language should be written to conform to the register usage model specified in the C compiler manual for your device. When writing assembly language, take special care to make sure the C context is preserved. For example, if you change the AMR register on the 'C6000, you should be sure to change it back before returning from your assembly language routine. See the Register Usage appendix in this book to see how DSP/BIOS uses specific registers.
1.4 DSP/BIOS Tconf Overview

The section describing each module in this manual lists properties that can be configured in Tconf scripts, along with their types and default values. The sections on manager properties and instance properties also provide Tconf examples that set each property.

For details on Tconf scripts, see the DSP/BIOS Tconf User’s Guide (SPRU007). The language used is JavaScript with an object model specific to the needs of DSP/BIOS configuration.

In general, property names of Module objects are in all uppercase letters. For example, "STACKSIZE". Property names of Instance objects begin with a lowercase word. Subsequent words have their first letter capitalized. For example, "stackSize".

Default values for many properties are dependent on the values of other properties. The defaults shown are those that apply if related property values have not been modified. Default values for many HWI properties are different for each instance.

The data types shown for the properties are not used as syntax in Tconf scripts. However, they do indicate the type of values that are valid for each property. The types used are as follows:

- **Arg.** Arg properties hold arguments to pass to program functions. They may be strings, integers, labels, or other types as needed by the program function.
- **Bool.** You may assign a value of either true or 1 to set a Boolean property to true. You may assign a value of either false or 0 (zero) to set a Boolean property to false. Do not set a Boolean property to the quoted string "true" or "false".
- **EnumInt.** Enumerated integer properties accept a set of valid integer values. These values are displayed in a drop-down list in the DSP/BIOS Configuration Tool.
- **EnumString.** Enumerated string properties accept certain string values. These values are displayed in a drop-down list in the DSP/BIOS Configuration Tool.
- **Extern.** Properties that hold function names use the Extern type. In order to specify a function Extern, use the prog.extern() method as shown in the examples to refer to objects defined as asm, C, or C++ language symbols. The default language is C.
- **Int16.** Integer properties hold 16-bit unsigned integer values. The value range accepted for a property may have additional limits.
- **Int32.** Long integer properties hold 32-bit unsigned integer values. The value range accepted for a property may have additional limits.
- **Numeric.** Numeric properties hold either 32-bit signed or unsigned values or decimal values, as appropriate for the property.
- **Reference.** Properties that reference other configures objects contain an object reference. Use the prog.get() method to specify a reference to another object.
- **String.** String properties hold text strings.
### 1.5 List of Operations

#### Table 1-2: DSP/BIOS Operations

**ATM module operations**

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>ATM_andi, ATM_andu</td>
<td>Atomically AND memory location with mask and return previous value</td>
</tr>
<tr>
<td>ATM_cleari, ATM_clearu</td>
<td>Atomically clear memory location and return previous value</td>
</tr>
<tr>
<td>ATM_deci, ATM_decu</td>
<td>Atomically decrement memory and return new value</td>
</tr>
<tr>
<td>ATM_inci, ATM_incu</td>
<td>Atomically increment memory and return new value</td>
</tr>
<tr>
<td>ATM_ori, ATM_oru</td>
<td>Atomically OR memory location with mask and return previous value</td>
</tr>
<tr>
<td>ATM_seti, ATM_setu</td>
<td>Atomically set memory and return previous value</td>
</tr>
</tbody>
</table>

**BUF module operations**

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>BUF_alloc</td>
<td>Allocate a fixed memory buffer out of the buffer pool</td>
</tr>
<tr>
<td>BUF_create</td>
<td>Dynamically create a buffer pool</td>
</tr>
<tr>
<td>BUF_delete</td>
<td>Delete a dynamically created buffer pool</td>
</tr>
<tr>
<td>BUF_free</td>
<td>Free a fixed memory buffer into the buffer pool</td>
</tr>
<tr>
<td>BUF_maxbuff</td>
<td>Check the maximum number of buffers used from the buffer pool</td>
</tr>
<tr>
<td>BUF_stat</td>
<td>Determine the status of a buffer pool (buffer size, number of free buffers, total number of buffers in the pool)</td>
</tr>
</tbody>
</table>

**C55 operations**

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>C55_disableIER0, C55_disableIER1, C55_disableInt</td>
<td>Disable certain maskable interrupts</td>
</tr>
<tr>
<td>C55_enableIER0, C55_enableIER1, C55_enableInt</td>
<td>Enable certain maskable interrupts</td>
</tr>
<tr>
<td>C55_l2AckInt</td>
<td>Acknowledge an L2 interrupt (OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>C55_l2DisableMIR, C55_l2DisableMIR1</td>
<td>Disable certain level 2 interrupts (OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>C55_l2EnableMIR, C55_l2EnableMIR1</td>
<td>Enable certain level 2 interrupts (OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>C55_l2SetIntPriority</td>
<td>Set the priority of an L2 interrupt (OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>C55_plug</td>
<td>C function to plug an interrupt vector</td>
</tr>
</tbody>
</table>
### CLK module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>CLK_countspms</td>
<td>Number of hardware timer counts per millisecond</td>
</tr>
<tr>
<td>CLK_cpuCyclesPerHtime</td>
<td>Return multiplier for converting high-res time to CPU cycles</td>
</tr>
<tr>
<td>CLK_cpuCyclesPerLtime</td>
<td>Return multiplier for converting low-res time to CPU cycles</td>
</tr>
<tr>
<td>CLK_gettime</td>
<td>Get high-resolution time</td>
</tr>
<tr>
<td>CLK_gettime</td>
<td>Get low-resolution time</td>
</tr>
<tr>
<td>CLK_getprd</td>
<td>Get period register value</td>
</tr>
<tr>
<td>CLK_reconfig</td>
<td>Reset timer period and registers</td>
</tr>
<tr>
<td>CLK_setTimerFunc</td>
<td>Assign function to a timer (C5505, C5515, C5517, C5535 only)</td>
</tr>
<tr>
<td>CLK_start</td>
<td>Restart the low-resolution timer</td>
</tr>
<tr>
<td>CLK_stop</td>
<td>Halt the low-resolution timer</td>
</tr>
</tbody>
</table>

### DEV module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>DEV_createDevice</td>
<td>Dynamically creates device with user-defined parameters</td>
</tr>
<tr>
<td>DEV_deleteDevice</td>
<td>Deletes the dynamically created device</td>
</tr>
<tr>
<td>DEV_match</td>
<td>Match a device name with a driver</td>
</tr>
<tr>
<td>Dxx_close</td>
<td>Close device</td>
</tr>
<tr>
<td>Dxx_ctrl</td>
<td>Device control operation</td>
</tr>
<tr>
<td>Dxx_idle</td>
<td>Idle device</td>
</tr>
<tr>
<td>Dxx_init</td>
<td>Initialize device</td>
</tr>
<tr>
<td>Dxx_issue</td>
<td>Send a buffer to the device</td>
</tr>
<tr>
<td>Dxx_open</td>
<td>Open device</td>
</tr>
<tr>
<td>Dxx_ready</td>
<td>Check if device is ready for I/O</td>
</tr>
<tr>
<td>Dxx_reclaim</td>
<td>Retrieve a buffer from a device</td>
</tr>
<tr>
<td>DGN Driver</td>
<td>Software generator driver</td>
</tr>
<tr>
<td>DGS Driver</td>
<td>Stackable gather/scatter driver</td>
</tr>
<tr>
<td>DHL Driver</td>
<td>Host link driver</td>
</tr>
<tr>
<td>DIO Driver</td>
<td>Class driver</td>
</tr>
<tr>
<td>DNL Driver</td>
<td>Null driver</td>
</tr>
<tr>
<td>DOV Driver</td>
<td>Stackable overlap driver</td>
</tr>
<tr>
<td>Function</td>
<td>Operation</td>
</tr>
<tr>
<td>-------------</td>
<td>------------------------------------------------</td>
</tr>
<tr>
<td>DPI Driver</td>
<td>Pipe driver</td>
</tr>
<tr>
<td>DST Driver</td>
<td>Stackable split driver</td>
</tr>
<tr>
<td>DTR Driver</td>
<td>Stackable streaming transformer driver</td>
</tr>
</tbody>
</table>

### GBL module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>GBL_getClkin</td>
<td>Get configured value of board input clock in KHz</td>
</tr>
<tr>
<td>GBL_getFrequency</td>
<td>Get current frequency of the CPU in KHz</td>
</tr>
<tr>
<td>GBL_getProcId</td>
<td>Get configured processor ID used by MSGQ</td>
</tr>
<tr>
<td>GBL_getVersion</td>
<td>Get DSP/BIOS version information</td>
</tr>
<tr>
<td>GBL_setFrequency</td>
<td>Set frequency of CPU in KHz for DSP/BIOS</td>
</tr>
<tr>
<td>GBL_setProcId</td>
<td>Set configured value of processor ID used by MSGQ</td>
</tr>
</tbody>
</table>

### GIO module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>GIO_abort</td>
<td>Abort all pending input and output</td>
</tr>
<tr>
<td>GIO_control</td>
<td>Device-specific control call</td>
</tr>
<tr>
<td>GIO_create</td>
<td>Allocate and initialize a GIO object</td>
</tr>
<tr>
<td>GIO_delete</td>
<td>Delete underlying IOM mini-drivers and free GIO object and its structure</td>
</tr>
<tr>
<td>GIO_flush</td>
<td>Drain output buffers and discard any pending input</td>
</tr>
<tr>
<td>GIO_new</td>
<td>Initialize a pre-allocated GIO object</td>
</tr>
<tr>
<td>GIO_read</td>
<td>Synchronous read command</td>
</tr>
<tr>
<td>GIO_submit</td>
<td>Submit a GIO packet to the mini-driver</td>
</tr>
<tr>
<td>GIO_write</td>
<td>Synchronous write command</td>
</tr>
</tbody>
</table>

### HOOK module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>HOOK_getenv</td>
<td>Get environment pointer for a given HOOK and TSK combination</td>
</tr>
<tr>
<td>HOOK_setenv</td>
<td>Set environment pointer for a given HOOK and TSK combination</td>
</tr>
</tbody>
</table>

### HST module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>HST_getpipe</td>
<td>Get corresponding pipe object</td>
</tr>
</tbody>
</table>
### List of Operations

#### HWI module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>HWI_disable</td>
<td>Globally disable hardware interrupts</td>
</tr>
<tr>
<td>HWI_dispatch</td>
<td>Plug the HWI dispatcher</td>
</tr>
<tr>
<td>HWI_enable</td>
<td>Globally enable hardware interrupts</td>
</tr>
<tr>
<td>HWI_enter</td>
<td>Hardware interrupt service routine prolog</td>
</tr>
<tr>
<td>HWI_exit</td>
<td>Hardware interrupt service routine epilog</td>
</tr>
<tr>
<td>HWI_isHWI</td>
<td>Check to see if called in the context of an HWI</td>
</tr>
<tr>
<td>HWI_restore</td>
<td>Restore global interrupt enable state</td>
</tr>
</tbody>
</table>

#### IDL module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>IDL_run</td>
<td>Make one pass through idle functions</td>
</tr>
</tbody>
</table>

#### LCK module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>LCK_create</td>
<td>Create a resource lock</td>
</tr>
<tr>
<td>LCK_delete</td>
<td>Delete a resource lock</td>
</tr>
<tr>
<td>LCK_pend</td>
<td>Acquire ownership of a resource lock</td>
</tr>
<tr>
<td>LCK_post</td>
<td>Relinquish ownership of a resource lock</td>
</tr>
</tbody>
</table>

#### LOG module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>LOG_disable</td>
<td>Disable a log</td>
</tr>
<tr>
<td>LOG_enable</td>
<td>Enable a log</td>
</tr>
<tr>
<td>LOG_error/LOG_message</td>
<td>Write a message to the system log</td>
</tr>
<tr>
<td>LOG_event</td>
<td>Append an unformatted message to a log</td>
</tr>
<tr>
<td>LOG_printf</td>
<td>Append a formatted message to a message log</td>
</tr>
<tr>
<td>LOG_reset</td>
<td>Reset a log</td>
</tr>
</tbody>
</table>

#### MBX module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>MBX_create</td>
<td>Create a mailbox</td>
</tr>
<tr>
<td>MBX_delete</td>
<td>Delete a mailbox</td>
</tr>
</tbody>
</table>
### MEM module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>MBX_pend</td>
<td>Wait for a message from mailbox</td>
</tr>
<tr>
<td>MBX_post</td>
<td>Post a message to mailbox</td>
</tr>
</tbody>
</table>

### MSGQ module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSGQ_alloc</td>
<td>Allocate a message. Performed by writer.</td>
</tr>
<tr>
<td>MSGQ_close</td>
<td>Closes a message queue. Performed by reader.</td>
</tr>
<tr>
<td>MSGQ_count</td>
<td>Return the number of messages in a message queue</td>
</tr>
<tr>
<td>MSGQ_free</td>
<td>Free a message. Performed by reader.</td>
</tr>
<tr>
<td>MSGQ_get</td>
<td>Receive a message from the message queue. Performed by reader.</td>
</tr>
<tr>
<td>MSGQ_getAttrs</td>
<td>Get attributes of a message queue.</td>
</tr>
<tr>
<td>MSGQ_getDstQueue</td>
<td>Get destination message queue field in a message.</td>
</tr>
<tr>
<td>MSGQ_getMsgId</td>
<td>Return the message ID from a message.</td>
</tr>
<tr>
<td>MSGQ_getMsgSize</td>
<td>Return the message size from a message.</td>
</tr>
<tr>
<td>MSGQ_getSrcQueue</td>
<td>Extract the reply destination from a message.</td>
</tr>
<tr>
<td>MSGQ_isLocalQueue</td>
<td>Return whether queue is local.</td>
</tr>
<tr>
<td>MSGQ_locate</td>
<td>Synchronously find a message queue. Performed by writer.</td>
</tr>
<tr>
<td>MSGQ_locateAsync</td>
<td>Asynchronously find a message queue. Performed by writer.</td>
</tr>
<tr>
<td>MSGQ_open</td>
<td>Opens a message queue. Performed by reader.</td>
</tr>
<tr>
<td>MSGQ_put</td>
<td>Place a message on a message queue. Performed by writer.</td>
</tr>
</tbody>
</table>
## List of Operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSGQ_release</td>
<td>Release a located message queue. Performed by writer.</td>
</tr>
<tr>
<td>MSGQ_setErrorHandler</td>
<td>Set up handling of internal MSGQ errors.</td>
</tr>
<tr>
<td>MSGQ_setMsgId</td>
<td>Sets the message ID in a message.</td>
</tr>
<tr>
<td>MSGQ_setSrcQueue</td>
<td>Sets the reply destination in a message.</td>
</tr>
</tbody>
</table>

### PIP module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>PIP_alloc</td>
<td>Get an empty frame from a pipe</td>
</tr>
<tr>
<td>PIP_free</td>
<td>Recycle a frame that has been read back into a pipe</td>
</tr>
<tr>
<td>PIP_get</td>
<td>Get a full frame from a pipe</td>
</tr>
<tr>
<td>PIP_getReaderAddr</td>
<td>Get the value of the readerAddr pointer of the pipe</td>
</tr>
<tr>
<td>PIP_getReaderNumFrames</td>
<td>Get the number of pipe frames available for reading</td>
</tr>
<tr>
<td>PIP_getReaderSize</td>
<td>Get the number of words of data in a pipe frame</td>
</tr>
<tr>
<td>PIP_getWriterAddr</td>
<td>Get the value of the writerAddr pointer of the pipe</td>
</tr>
<tr>
<td>PIP_getWriterNumFrames</td>
<td>Get the number of pipe frames available to be written to</td>
</tr>
<tr>
<td>PIP_getWriterSize</td>
<td>Get the number of words that can be written to a pipe frame</td>
</tr>
<tr>
<td>PIP_peek</td>
<td>Get the pipe frame size and address without actually claiming the pipe frame</td>
</tr>
<tr>
<td>PIP_put</td>
<td>Put a full frame into a pipe</td>
</tr>
<tr>
<td>PIP_reset</td>
<td>Reset all fields of a pipe object to their original values</td>
</tr>
<tr>
<td>PIP_setWriterSize</td>
<td>Set the number of valid words written to a pipe frame</td>
</tr>
</tbody>
</table>

### PRD module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>PRD_getticks</td>
<td>Get the current tick counter</td>
</tr>
<tr>
<td>PRD_start</td>
<td>Arm a periodic function for one-time execution</td>
</tr>
<tr>
<td>PRD_stop</td>
<td>Stop a periodic function from execution</td>
</tr>
<tr>
<td>PRD_tick</td>
<td>Advance tick counter, dispatch periodic functions</td>
</tr>
</tbody>
</table>

### PWRM module operations (’C5509 devices)

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_changeSetpoint</td>
<td>Initiate a change to the V/F setpoint</td>
</tr>
<tr>
<td>PWRM_configure</td>
<td>Set new configuration parameters for PWRM</td>
</tr>
<tr>
<td>PWRM_getCapabilities</td>
<td>Get information on PWRM’s capabilities on the current platform</td>
</tr>
<tr>
<td>PWRM_getCurrentSetpoint</td>
<td>Get the current setpoint in effect</td>
</tr>
<tr>
<td>Function</td>
<td>Operation</td>
</tr>
<tr>
<td>--------------------------</td>
<td>---------------------------------------------------------------------------</td>
</tr>
<tr>
<td>PWRM_getDependencyCount</td>
<td>Get count of dependencies currently declared on a resource</td>
</tr>
<tr>
<td>PWRM_getNumSetpoints</td>
<td>Get the number of setpoints supported for the current platform</td>
</tr>
<tr>
<td>PWRM_getSetpointInfo</td>
<td>Get the corresponding frequency and CPU core voltage for a setpoint</td>
</tr>
<tr>
<td>PWRM_getTransitionLatency</td>
<td>Get the latency to scale between setpoints</td>
</tr>
<tr>
<td>PWRM_idleClocks</td>
<td>Immediately idle the clock domains</td>
</tr>
<tr>
<td>PWRM_registerNotify</td>
<td>Register a function to be called on a specific power event</td>
</tr>
<tr>
<td>pwrmNotifyFxn</td>
<td>Function to be called on a registered power event</td>
</tr>
<tr>
<td>PWRM_releaseDependency</td>
<td>Release a dependency that has been previously declared</td>
</tr>
<tr>
<td>PWRM_setDependency</td>
<td>Declare a dependency upon a resource</td>
</tr>
<tr>
<td>PWRM_sleepDSP</td>
<td>Transition the DSP to a new sleep state</td>
</tr>
<tr>
<td>PWRM_unregisterNotify</td>
<td>Unregister for an event notification from PWRM</td>
</tr>
</tbody>
</table>

**QUE module operations**

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>QUE_create</td>
<td>Create an empty queue</td>
</tr>
<tr>
<td>QUE_delete</td>
<td>Delete an empty queue</td>
</tr>
<tr>
<td>QUE_dequeue</td>
<td>Remove from front of queue (non-atomically)</td>
</tr>
<tr>
<td>QUE_empty</td>
<td>Test for an empty queue</td>
</tr>
<tr>
<td>QUE_enqueue</td>
<td>Insert at end of queue (non-atomically)</td>
</tr>
<tr>
<td>QUE_get</td>
<td>Get element from front of queue (atomically)</td>
</tr>
<tr>
<td>QUE_head</td>
<td>Return element at front of queue</td>
</tr>
<tr>
<td>QUE_insert</td>
<td>Insert in middle of queue (non-atomically)</td>
</tr>
<tr>
<td>QUE_new</td>
<td>Set a queue to be empty</td>
</tr>
<tr>
<td>QUE_next</td>
<td>Return next element in queue (non-atomically)</td>
</tr>
<tr>
<td>QUE_prev</td>
<td>Return previous element in queue (non-atomically)</td>
</tr>
<tr>
<td>QUE_put</td>
<td>Put element at end of queue (atomically)</td>
</tr>
<tr>
<td>QUE_remove</td>
<td>Remove from middle of queue (non-atomically)</td>
</tr>
</tbody>
</table>

**RTDX module operations**

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>RTDX_channelBusy</td>
<td>Return status indicating whether a channel is busy</td>
</tr>
<tr>
<td>RTDX_CreateInputChannel</td>
<td>Declare input channel structure</td>
</tr>
</tbody>
</table>
## List of Operations

### SEM module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>RTDX_CreateOutputChannel</td>
<td>Declare output channel structure</td>
</tr>
<tr>
<td>RTDX_disableInput</td>
<td>Disable an input channel</td>
</tr>
<tr>
<td>RTDX_disableOutput</td>
<td>Disable an output channel</td>
</tr>
<tr>
<td>RTDX_enableInput</td>
<td>Enable an input channel</td>
</tr>
<tr>
<td>RTDX_enableOutput</td>
<td>Enable an output channel</td>
</tr>
<tr>
<td>RTDX_isInputEnabled</td>
<td>Return status of the input data channel</td>
</tr>
<tr>
<td>RTDX_isOutputEnabled</td>
<td>Return status of the output data channel</td>
</tr>
<tr>
<td>RTDX_read</td>
<td>Read from an input channel</td>
</tr>
<tr>
<td>RTDX_readNB</td>
<td>Read from an input channel without blocking</td>
</tr>
<tr>
<td>RTDX_sizeofInput</td>
<td>Return the number of bytes read from an input channel</td>
</tr>
<tr>
<td>RTDX_write</td>
<td>Write to an output channel</td>
</tr>
</tbody>
</table>

### SIO module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>SIO_buffersize</td>
<td>Size of the buffers used by a stream</td>
</tr>
<tr>
<td>SIO_create</td>
<td>Create stream</td>
</tr>
<tr>
<td>SIO_ctl</td>
<td>Perform a device-dependent control operation</td>
</tr>
<tr>
<td>SIO_delete</td>
<td>Delete stream</td>
</tr>
<tr>
<td>SIO_flush</td>
<td>Idle a stream by flushing buffers</td>
</tr>
<tr>
<td>SIO_get</td>
<td>Get buffer from stream</td>
</tr>
</tbody>
</table>
### List of Operations

#### SIO module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>SIO_idle</td>
<td>Idle a stream</td>
</tr>
<tr>
<td>SIO_issue</td>
<td>Send a buffer to a stream</td>
</tr>
<tr>
<td>SIO_put</td>
<td>Put buffer to a stream</td>
</tr>
<tr>
<td>SIO_ready</td>
<td>Determine if device for stream is ready</td>
</tr>
<tr>
<td>SIO_reclaim</td>
<td>Request a buffer back from a stream</td>
</tr>
<tr>
<td>SIO_reclaimx</td>
<td>Request a buffer and frame status back from a stream</td>
</tr>
<tr>
<td>SIO_segid</td>
<td>Memory section used by a stream</td>
</tr>
<tr>
<td>SIO_select</td>
<td>Select a ready device</td>
</tr>
<tr>
<td>SIO_staticbuf</td>
<td>Acquire static buffer from stream</td>
</tr>
</tbody>
</table>

#### STS module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>STS_add</td>
<td>Add a value to a statistics object</td>
</tr>
<tr>
<td>STS_delta</td>
<td>Add computed value of an interval to object</td>
</tr>
<tr>
<td>STS_reset</td>
<td>Reset the values stored in an STS object</td>
</tr>
<tr>
<td>STS_set</td>
<td>Store initial value of an interval to object</td>
</tr>
</tbody>
</table>

#### SWI module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>SWI_andn</td>
<td>Clear bits from SWI’s mailbox and post if becomes 0</td>
</tr>
<tr>
<td>SWI_andnHook</td>
<td>Specialized version of SWI_andn</td>
</tr>
<tr>
<td>SWI_create</td>
<td>Create a software interrupt</td>
</tr>
<tr>
<td>SWI_dec</td>
<td>Decrement SWI’s mailbox and post if becomes 0</td>
</tr>
<tr>
<td>SWI_delete</td>
<td>Delete a software interrupt</td>
</tr>
<tr>
<td>SWI_disable</td>
<td>Disable software interrupts</td>
</tr>
<tr>
<td>SWI_enable</td>
<td>Enable software interrupts</td>
</tr>
<tr>
<td>SWI_getattrs</td>
<td>Get attributes of a software interrupt</td>
</tr>
<tr>
<td>SWI_getmbox</td>
<td>Return SWI’s mailbox value</td>
</tr>
<tr>
<td>SWI_getpri</td>
<td>Return an SWI’s priority mask</td>
</tr>
<tr>
<td>SWI_inc</td>
<td>Increment SWI’s mailbox and post</td>
</tr>
<tr>
<td>SWI_isSWI</td>
<td>Check to see if called in the context of a SWI</td>
</tr>
<tr>
<td>SWI_or</td>
<td>Set or mask in an SWI’s mailbox and post</td>
</tr>
<tr>
<td>SWI_orHook</td>
<td>Specialized version of SWI_or</td>
</tr>
</tbody>
</table>
### List of Operations

#### Function | Operation
--- | ---
SWI_post | Post a software interrupt
SWI_raisepri | Raise an SWI’s priority
SWI_restorepri | Restore an SWI’s priority
SWI_self | Return address of currently executing SWI object
SWI_setattrs | Set attributes of a software interrupt

#### SYS module operations

#### Function | Operation
--- | ---
SYS_abort | Abort program execution
SYS_atexit | Stack an exit handler
SYS_error | Flag error condition
SYS_exit | Terminate program execution
SYS_putchar | Output a single character
SYS_printf, SYS_sprintf, SYS_vprintf, SYS_vsprintf | Formatted output

#### TRC module operations

#### Function | Operation
--- | ---
TRC_disable | Disable a set of trace controls
TRC_enable | Enable a set of trace controls
TRC_query | Test whether a set of trace controls is enabled

#### TSK module operations

#### Function | Operation
--- | ---
TSK_checkstacks | Check for stack overflow
TSK_create | Create a task ready for execution
TSK_delete | Delete a task
TSK_deltatime | Update task STS with time difference
TSK_disable | Disable DSP/BIOS task scheduler
TSK_enable | Enable DSP/BIOS task scheduler
TSK_exit | Terminate execution of the current task
TSK_getenv | Get task environment
TSK_geterr | Get task error number
TSK_getname | Get task name
TSK_getpri | Get task priority
TSK_getsts | Get task STS object
### List of Operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>TSK_isTSK</td>
<td>Check to see if called in the context of a TSK</td>
</tr>
<tr>
<td>TSK_itick</td>
<td>Advance system alarm clock (interrupt only)</td>
</tr>
<tr>
<td>TSK_self</td>
<td>Returns a handle to the current task</td>
</tr>
<tr>
<td>TSK_setenv</td>
<td>Set task environment</td>
</tr>
<tr>
<td>TSK_seterr</td>
<td>Set task error number</td>
</tr>
<tr>
<td>TSK_setpri</td>
<td>Set a task execution priority</td>
</tr>
<tr>
<td>TSK_settime</td>
<td>Set task STS previous time</td>
</tr>
<tr>
<td>TSK_sleep</td>
<td>Delay execution of the current task</td>
</tr>
<tr>
<td>TSK_stat</td>
<td>Retrieve the status of a task</td>
</tr>
<tr>
<td>TSK_tick</td>
<td>Advance system alarm clock</td>
</tr>
<tr>
<td>TSK_time</td>
<td>Return current value of system clock</td>
</tr>
<tr>
<td>TSK_yield</td>
<td>Yield processor to equal priority task</td>
</tr>
</tbody>
</table>

### C library stdlib.h

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>atexit</td>
<td>Registers one or more exit functions used by exit</td>
</tr>
<tr>
<td>calloc</td>
<td>Allocates memory block initialized with zeros</td>
</tr>
<tr>
<td>exit</td>
<td>Calls the exit functions registered in atexit</td>
</tr>
<tr>
<td>free</td>
<td>Frees memory block</td>
</tr>
<tr>
<td>getenv</td>
<td>Searches for a matching environment string</td>
</tr>
<tr>
<td>malloc</td>
<td>Allocates memory block</td>
</tr>
<tr>
<td>realloc</td>
<td>Resizes previously allocated memory block</td>
</tr>
</tbody>
</table>

### DSP/BIOS std.h special utility C macros

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>ArgToInt(arg)</td>
<td>Casting to treat Arg type parameter as integer (Int) type on the given target</td>
</tr>
<tr>
<td>ArgToPtr(arg)</td>
<td>Casting to treat Arg type parameter as pointer (Ptr) type on the given target</td>
</tr>
</tbody>
</table>
This chapter describes the DSP/BIOS API modules and functions.

<table>
<thead>
<tr>
<th>Topic</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.1 ATM Module</td>
<td>23</td>
</tr>
<tr>
<td>2.2 BUF Module</td>
<td>36</td>
</tr>
<tr>
<td>2.3 C55 Module</td>
<td>46</td>
</tr>
<tr>
<td>2.4 CLK Module</td>
<td>59</td>
</tr>
<tr>
<td>2.5 DEV Module</td>
<td>77</td>
</tr>
<tr>
<td>2.6 GBL Module</td>
<td>119</td>
</tr>
<tr>
<td>2.7 GIO Module</td>
<td>128</td>
</tr>
<tr>
<td>2.8 HOOK Module</td>
<td>144</td>
</tr>
<tr>
<td>2.9 HST Module</td>
<td>149</td>
</tr>
<tr>
<td>2.10 HWI Module</td>
<td>153</td>
</tr>
<tr>
<td>2.11 IDL Module</td>
<td>173</td>
</tr>
<tr>
<td>2.12 LCK Module</td>
<td>177</td>
</tr>
<tr>
<td>2.13 LOG Module</td>
<td>183</td>
</tr>
<tr>
<td>2.14 MBX Module</td>
<td>195</td>
</tr>
<tr>
<td>2.15 MEM Module</td>
<td>201</td>
</tr>
<tr>
<td>2.16 MSGQ Module</td>
<td>224</td>
</tr>
<tr>
<td>2.17 PIP Module</td>
<td>259</td>
</tr>
<tr>
<td>2.18 POOL Module</td>
<td>277</td>
</tr>
<tr>
<td>2.19 PRD Module</td>
<td>281</td>
</tr>
<tr>
<td>2.20 PWRM Module</td>
<td>288</td>
</tr>
<tr>
<td>2.21 QUE Module</td>
<td>323</td>
</tr>
<tr>
<td>2.22 RTDX Module</td>
<td>338</td>
</tr>
<tr>
<td>2.23 SEM Module</td>
<td>354</td>
</tr>
<tr>
<td>2.24 SIO Module</td>
<td>365</td>
</tr>
<tr>
<td>2.25 STS Module</td>
<td>390</td>
</tr>
<tr>
<td>2.26 SWI Module</td>
<td>399</td>
</tr>
<tr>
<td>2.27 SYS Module</td>
<td>426</td>
</tr>
<tr>
<td>2.28 TRC Module</td>
<td>442</td>
</tr>
<tr>
<td>2.29 TSK Module</td>
<td>446</td>
</tr>
<tr>
<td>2.30 std.h and stdlib.h functions</td>
<td>482</td>
</tr>
</tbody>
</table>
2.1 ATM Module

The ATM module includes assembly language functions.

Functions

- ATM_andi, ATM_andu. AND memory and return previous value
- ATM_cleari, ATM_clearu. Clear memory and return previous value
- ATM_deci, ATM_decu. Decrement memory and return new value
- ATM_inci, ATM_incu. Increment memory and return new value
- ATM_ori, ATM_oru. OR memory and return previous value
- ATM_seti, ATM_setu. Set memory and return previous value

Description

ATM provides a set of assembly language functions that are used to manipulate variables with interrupts disabled. These functions can therefore be used on data shared between tasks, and on data shared between tasks and interrupt routines.
### ATM_andi

**Atomically AND Int memory location and return previous value**

#### C Interface

**Syntax**

```
ival = ATM_andi(idst, isrc);
```

**Parameters**

- `volatile Int *idst; /* pointer to integer */`
- `Int isrc; /* integer mask */`

**Return Value**

- `Int ival; /* previous value of *idst */`

#### Description

`ATM_andi` atomically ANDs the mask contained in `isrc` with a destination memory location and overwrites the destination value `*idst` with the result as follows:

```
`interrupt disable`
ival = *idst;
*idst = ival & isrc;
`interrupt enable`
return(ival);
```

`ATM_andi` is written in assembly language, efficiently disabling interrupts on the target processor during the call.

#### See Also

- `ATM_andu`
- `ATM_ori`
**ATM_andu** Atomically AND Uns memory location and return previous value

## C Interface

**Syntax**

```c
uval = ATM_andu(udst, usrc);
```

**Parameters**

- `volatile Uns *udst; /* pointer to unsigned */`
- `Uns usrc; /* unsigned mask */`

**Return Value**

- `Uns uval; /* previous value of *udst */`

**Description**

`ATM_andu` atomically ANDs the mask contained in `usrc` with a destination memory location and overwrites the destination value `*udst` with the result as follows:

```c
`interrupt disable`

uval = *udst;

*udst = uval & usrc;

`interrupt enable`

return(uval);
```

`ATM_andu` is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

- `ATM_andi`
- `ATM_oru`
**ATM_cleari**  
*Atomically clear Int memory location and return previous value*

**C Interface**

**Syntax**

```
ival = ATM_cleari(idst);
```

**Parameters**

- `volatile Int *idst; /* pointer to integer */`

**Return Value**

- `Int ival; /* previous value of *idst */`

**Description**

ATM_cleari atomically clears an Int memory location and returns its previous value as follows:

```
`interrupt disable`
ival = *idst;
*dst = 0;
`interrupt enable`
return (ival);
```

ATM_cleari is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

- ATM_clearu
- ATM_seti
**ATM_clearu**  
Atomically clear Uns memory location and return previous value

### C Interface

**Syntax**

```c
uval = ATM_clearu(udst);
```

**Parameters**

- `volatile Uns *udst;` /* pointer to unsigned */

**Return Value**

- `Uns uval;` /* previous value of *udst */

**Description**

ATM_clearu atomically clears an Uns memory location and returns its previous value as follows:

```c
interrupt disable
uval = *udst;
*udst = 0;
interrupt enable
return (uval);
```

ATM_clearu is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

- ATM_cleari
- ATM_setu
**ATM_deci**  
*Atomically decrement Int memory and return new value*

**C Interface**

**Syntax**

```c
ival = ATM_deci(idst);
```

**Parameters**

- `volatile Int *idst;` /* pointer to integer */

**Return Value**

- `Int ival;` /* new value after decrement */

**Description**

ATM_deci atomically decrements an Int memory location and returns its new value as follows:

```c
`interrupt disable`
ival = *idst - 1;
*idst = ival;
`interrupt enable`
return (ival);
```

ATM_deci is written in assembly language, efficiently disabling interrupts on the target processor during the call.

Decrementing a value equal to the minimum signed integer results in a value equal to the maximum signed integer.

**See Also**

- ATM_decu
- ATM_inci
**ATM_decu** Atomically decrement Uns memory and return new value

### C Interface

**Syntax**

```c
uval = ATM_decu(udst);
```

**Parameters**

- `volatile Uns *udst; /* pointer to unsigned */`

**Return Value**

- `Uns uval; /* new value after decrement */`

### Description

ATM_decu atomically decrements a Uns memory location and returns its new value as follows:

```c
`interrupt disable`
    uval = *udst - 1;
    *udst = uval;
`interrupt enable`
    return (uval);
```

ATM_decu is written in assembly language, efficiently disabling interrupts on the target processor during the call.

Decrementing a value equal to the minimum unsigned integer results in a value equal to the maximum unsigned integer.

### See Also

- `ATM_deci`
- `ATM_incu`
ATM_inci

**Syntax**

```c
ival = ATM_inci(idst);
```

**Parameters**

- `volatile Int *idst; /* pointer to integer */`

**Return Value**

- `Int ival; /* new value after increment */`

**Description**

ATM_inci atomically increments an Int memory location and returns its new value as follows:

```
`interrupt disable`
ival = *idst + 1;
*idst = ival;
`interrupt enable`
return (ival);
```

ATM_inci is written in assembly language, efficiently disabling interrupts on the target processor during the call.

Incrementing a value equal to the maximum signed integer results in a value equal to the minimum signed integer.

**See Also**

- ATM_deci
- ATM_incu
**ATM_incu**  
*Atomically increment Uns memory and return new value*

### C Interface

**Syntax**

```c
uval = ATM_incu(udst);
```

**Parameters**

- `volatile Uns *udst;` /* pointer to unsigned */

**Return Value**

- `Uns uval;` /* new value after increment */

**Description**

ATM_incu atomically increments an Uns memory location and returns its new value as follows:

```c
`interrupt disable`

uval = *udst + 1;
*udst = uval;
`interrupt enable`

return (uval);
```

ATM_incu is written in assembly language, efficiently disabling interrupts on the target processor during the call.

Incrementing a value equal to the maximum unsigned integer results in a value equal to the minimum unsigned integer.

**See Also**

- ATM_decu
- ATM_inci
ATM_ori

Atomically OR int memory location and return previous value

C Interface

Syntax

ival = ATM_ori(idst, isrc);

Parameters

volatile Int *idst; /* pointer to integer */
Int isrc; /* integer mask */

Return Value

Int  ival;  /* previous value of *idst */

Description

ATM_ori atomically ORs the mask contained in isrc with a destination memory location and overwrites the destination value *idst with the result as follows:

`interrupt disable`
ival = *idst;
*idst = ival | isrc;
`interrupt enable`
return(ival);

ATM_ori is written in assembly language, efficiently disabling interrupts on the target processor during the call.

See Also

ATM_andi
ATM_oru
ATM_oru  Atomically OR Uns memory location and return previous value

C Interface

Syntax

\[
uval = ATM_oru(udst, usrc);
\]

Parameters

- `volatile Uns *udst; /* pointer to unsigned */`
- `Uns usrc; /* unsigned mask */`

Return Value

- `Uns uva; /* previous value of *udst */`

Description

`ATM_oru` atomically ORs the mask contained in `usrc` with a destination memory location and overwrites the destination value `*udst` with the result as follows:

```c
'\text{\texttt{interrupt disable}}'
\begin{verbatim}
uval = *udst;
*udst = uval | usrc;
\text{\texttt{interrupt enable}}
\end{verbatim}
\begin{verbatim}
return(uval);
\end{verbatim}
```

`ATM_oru` is written in assembly language, efficiently disabling interrupts on the target processor during the call.

See Also

- `ATM_andu`
- `ATM_ori`
**ATM_seti**  
**Atomically set Int memory and return previous value**

**C Interface**

Syntax

```c
iold = ATM_seti(idst, inew);
```

Parameters

- `volatile Int *idst; /* pointer to integer */`
- `Int inew; /* new integer value */`

Return Value

- `Int iold; /* previous value of *idst */`

**Description**

ATM_seti atomically sets an Int memory location to a new value and returns its previous value as follows:

```
`interrupt disable`
ival = *idst;
*idst = inew;
`interrupt enable`
return (ival);
```

ATM_seti is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

- `ATM_setu`
- `ATM_cleari`
**ATM_setu**  
*Atomically set Uns memory and return previous value*

**C Interface**

Syntax

```c
uold = ATM_setu(udst, unew);
```

Parameters

- `volatile Uns *udst;` /* pointer to unsigned */
- `Uns unew;` /* new unsigned value */

Return Value

- `Uns uold;` /* previous value of *udst */

**Description**

`ATM_setu` atomically sets an Uns memory location to a new value and returns its previous value as follows:

```
`interrupt disable`
  uval = *udst;
  *udst = unew;
`interrupt enable`
return (uval);
```

`ATM_setu` is written in assembly language, efficiently disabling interrupts on the target processor during the call.

**See Also**

- `ATM_clearu`
- `ATM_seti`
2.2 BUF Module

The BUF module maintains buffer pools of fixed-size buffers.

Functions

- **BUF_alloc.** Allocate a fixed-size buffer from the buffer pool
- **BUF_create.** Dynamically create a buffer pool
- **BUF_delete.** Delete a dynamically-created buffer pool
- **BUF_free.** Free a fixed-size buffer back to the buffer pool
- **BUF_maxbuff.** Get the maximum number of buffers used in a pool
- **BUF_stat.** Get statistics for the specified buffer pool

Constants, Types, and Structures

```c
typedef unsigned long MEM_sizep;

#define BUF_ALLOCSTAMP 0xcafe
#define BUF_FREESTAMP 0xbeef

typedef struct BUF_Obj {
    Ptr startaddr;   /* Start addr of buffer pool */
    MEM_sizep size;   /* Size before alignment */
    MEM_sizep postalignsize; /* Size after align */
    Ptr nextfree;     /* Ptr to next free buffer */
    Uns totalbuffers; /* # of buffers in pool */
    Uns freebuffers;  /* # of free buffers in pool */
    Int segid;        /* Mem seg for buffer pool */
} BUF_Obj, *BUF_Handle;

typedef struct BUF_Attrs {
    Int segid;  /* segment for element allocation */
} BUF_Attrs;

BUF_Attrs BUF_ATTRS = {/* default attributes */
    0,
};

typedef struct BUF_Stat {
    MEM_sizep postalignsize; /* Size after align */
    MEM_sizep size;   /* Original size of buffer */
    Uns totalbuffers; /* Total buffers in pool */
    Uns freebuffers;  /* # of free buffers in pool */
} BUF_Stat;
```

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the BUF Manager Properties and BUF Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>
Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>bufSeg</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>bufCount</td>
<td>Int32</td>
<td>1</td>
</tr>
<tr>
<td>size</td>
<td>Int32</td>
<td>4 (&quot;C55x&quot;)</td>
</tr>
<tr>
<td>align</td>
<td>Int32</td>
<td>2 (&quot;C55x&quot;)</td>
</tr>
<tr>
<td>len</td>
<td>Int32</td>
<td>4 (&quot;C55x&quot;)</td>
</tr>
<tr>
<td>postalignsize</td>
<td>Int32</td>
<td>4 (&quot;C55x&quot;)</td>
</tr>
</tbody>
</table>

Description
The BUF module maintains pools of fixed-size buffers. These buffer pools can be created statically or dynamically. Dynamically-created buffer pools are allocated from a dynamic memory heap managed by the MEM module. Applications typically allocate buffer pools statically when size and alignment constraints are known at design time. Run-time allocation is used when these constraints vary during execution.

Within a buffer pool, all buffers have the same size and alignment. Although each frame has a fixed length, the application can put a variable amount of data in each frame, up to the length of the frame. You can create multiple buffer pools, each with a different buffer size.

Buffers can be allocated and freed from a pool as needed at run-time using the BUF_alloc and BUF_free functions.

The advantages of allocating memory from a buffer pool instead of from the dynamic memory heaps provided by the MEM module include:

- **Deterministic allocation times.** The BUF_alloc and BUF_free functions require a constant amount of time. Allocating and freeing memory through a heap is not deterministic.
- **Callable from all thread types.** Allocating and freeing buffers is atomic and non-blocking. As a result, BUF_alloc and BUF_free can be called from all types of DSP/BIOS threads: HWI, SWI, TSK, and IDL. In contrast, HWI and SWI threads cannot call MEM_alloc.
- **Optimized for fixed-length allocation.** In contrast MEM_alloc is optimized for variable-length allocation.
- **Less fragmentation.** Since the buffers are of fixed-size, the pool does not become fragmented.

BUF Manager Properties

The following global properties can be set for the BUF module in the BUF Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment to contain all BUF objects. (A BUF object may be stored in a different location than the buffer pool memory itself.)
  
  Tconf Name: OBJMEMSEG  Type: Reference
  
  Example: bios.BUF.OBJMEMSEG = prog.get("myMEM");
BUF Object Properties

The following properties can be set for a buffer pool object in the BUF Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script. To create an BUF object in a configuration script, use the following syntax:

```javascript
var myBuf = bios.BUF.create("myBUF");
```

The Tconf examples that follow assume the object has been created as shown.

- **comment.** Type a comment to identify this BUF object.
  
  Tconf Name: comment Type: String
  
  Example: `myBuf.comment = "my BUF";`

- **Memory segment for buffer pool.** Select the memory segment in which the buffer pool is to be created. The linker decides where in the segment the buffer pool starts.
  
  Tconf Name: bufSeg Type: Reference
  
  Example: `myBuf.bufSeg = prog.get("myMEM");`

- **Buffer count.** Specify the number of fixed-length buffers to create in this pool.
  
  Tconf Name: bufCount Type: Int32
  
  Example: `myBuf.bufCount = 128;`

- **Buffer size.** Specify the size (in MADUs) of each fixed-length buffer inside this buffer pool. The default size shown is the minimum valid value for that platform. This size may be adjusted to accommodate the alignment in the "Buffer size after alignment" property.
  
  Tconf Name: size Type: Int32
  
  Example: `myBuf.size = 4;`

- **Buffer alignment.** Specify the alignment boundary for fixed-length buffers in the pool. Each buffer is aligned on boundaries with a multiple of this number. The default size shown is the minimum valid value for that platform. The value must be a power of 2.
  
  Tconf Name: align Type: Int32
  
  Example: `myBuf.align = 2;`

- **Buffer pool length.** The actual length of the buffer pool (in MADUs) is calculated by multiplying the Buffer count by the Buffer size after alignment. You cannot modify this value directly.
  
  Tconf Name: len Type: Int32
  
  Example: `myBuf.len = 4;`

- **Buffer size after alignment.** This property shows the modified Buffer size after applying the alignment. For example, if the Buffer size is 9 and the alignment is 4, the Buffer size after alignment is 12 (the next whole number multiple of 4 after 9).
  
  Tconf Name: postalignsize Type: Int32
  
  Example: `myBuf.postalignsize = 4;`
**BUF_alloc**  Allocate a fixed-size buffer from a buffer pool

*C Interface*

**Syntax**

```c
bufaddr = BUF_alloc(buf);
```

**Parameters**

- **BUF_Handle buf; /* buffer pool object handle */**

**Return Value**

- **Ptr bufaddr; /* pointer to free buffer */**

**Reentrant**

yes

**Description**

BUF_alloc allocates a fixed-size buffer from the specified buffer pool and returns a pointer to the buffer. BUF_alloc does not initialize the allocated buffer space.

The buf parameter is a handle to identify the buffer pool object, from which the fixed size buffer is to be allocated. If the buffer pool was created dynamically, the handle is the one returned by the call to BUF_create. If the buffer pool was created statically, the handle can be referenced as shown in the example that follows.

If buffers are available in the specified buffer pool, BUF_alloc returns a pointer to the buffer. If no buffers are available, BUF_alloc returns NULL.

The BUF module manages synchronization so that multiple threads can share the same buffer pool for allocation and free operations.

The time required to successfully execute BUF_alloc is deterministic (constant over multiple calls).

**Example**

```c
extern BUF_Obj bufferPool;
BUF_Handle buffPoolHandle = &bufferPool;

Ptr buffPtr;

/* allocate a buffer */
buffPtr = BUF_alloc(buffPoolHandle);
if (buffPtr == NULL)
{
    SYS_abort("BUF_alloc failed");
}
```

**See Also**

BUF_free
MEM_alloc
**BUF_create**

*Dynamically create a buffer pool*

**C Interface**

Syntax

```c
buf = BUF_create(numbuff, size, align, attrs);
```

Parameters

- **Uns numbuff; /* number of buffers in the pool */**
- **MEM_sizep size; /* size of a single buffer in the pool */**
- **Uns align; /* alignment for each buffer in the pool */**
- **BUF_Attrs *attrs; /* pointer to buffer pool attributes */**

Return Value

- **BUF_Handle buf; /* buffer pool object handle */**

**Reentrant**

no

**Description**

BUF_create creates a buffer pool object dynamically. The parameters correspond to the properties available for statically-created buffer pools, which are described in the BUF Object Properties topic.

The numbuff parameter specifies how many fixed-length buffers the pool should contain. This must be a non-zero number.

The size parameter specifies how long each fixed-length buffer in the pool should be in MADUs. This must be a non-zero number. The size you specify is adjusted as needed to meet the alignment requirements, so the actual buffer size may be larger. The MEM_sizep type is defined as follows:

```c
typedef unsigned long MEM_sizep;
```

The align parameter specifies the alignment boundary for buffers in the pool. Each buffer is aligned on a boundary with an address that is a multiple of this number. The value must be a power of 2. The size of buffers created in the pool is automatically increased to accommodate the alignment you specify.

BUF_create ensures that the size and alignment are set to at least the minimum values permitted for the platform. The minimum size permitted is 4 (’C55x) MADUs. The minimum alignment permitted is 2 (’C55x).

The attrs parameter points to a structure of type BUF_Attrs, which is defined as follows:

```c
typedef struct BUF_Attrs {
    Int segid; /* segment for element allocation*/
} BUF_Attrs;
```

The segid element can be used to specify the memory segment in which buffer pool should be created. If attrs is NULL, the new buffer pool is created the default attributes specified in BUF_ATTRS, which uses the default memory segment.

BUF_create calls MEM_alloc to dynamically create the BUF object's data structure and the buffer pool.

BUF_create returns a handle to the buffer pool of type BUF_Handle. If the buffer pool cannot be created, BUF_create returns NULL. The pool may not be created if the numbuff or size parameter is zero or if the memory available in the specified heap is insufficient.

The time required to successfully execute BUF_create is not deterministic (that is, the time varies over multiple calls).
Constraints and Calling Context

- BUF_create cannot be called from a SWI or HWI.
- The product of the size (after adjusting for the alignment) and numbuff parameters should not exceed the maximum Uns value.
- The alignment should be greater than the minimum value and must be a power of 2. If it is not, proper creation of buffer pool is not guaranteed.

Example

```c
BUF_Handle myBufpool;
BUF_Attrs myAttrs;

myAttrs = BUF_ATTRS;
myBufpool = BUF_create(5, 4, 2, &myAttrs);
if( myBufpool == NULL ){
    LOG_printf(&trace,"BUF_create failed!");
}
```

See Also

- BUF_delete
**BUF_delete**

*Delete a dynamically-created buffer pool*

**C Interface**

```c
Syntax
status = BUF_delete(buf);
```

**Parameters**

- `BUF_Handle buf; /* buffer pool object handle */`

**Return Value**

- `Uns status; /* returned status */`

**Reentrant**

*no*

**Description**

BUF_delete frees the buffer pool object and the buffer pool memory referenced by the handle provided.

The `buf` parameter is the handle that identifies the buffer pool object. This handle is the one returned by the call to BUF_create. BUF_delete cannot be used to delete statically created buffer pool objects.

BUF_delete returns 1 if it has successfully freed the memory for the buffer object and buffer pool. It returns 0 (zero) if it was unable to delete the buffer pool.

BUF_delete calls MEM_free to delete the BUF object and to free the buffer pool memory. MEM_free must acquire a lock to the memory before proceeding. If another task already holds a lock on the memory, there is a context switch.

The time required to successfully execute BUF_delete is not deterministic (that is, the time varies over multiple calls).

**Constraints and Calling Context**

- BUF_delete cannot be called from a SWI or HWI.
- BUF_delete cannot be used to delete statically created buffer pool objects. No check is performed to ensure that this is the case.
- BUF_delete assumes that all the buffers allocated from the buffer pool have been freed back to the pool.

**Example**

```c
BUF_Handle myBufpool;
Uns delstat;

delstat = BUF_delete(myBufpool);
if( delstat == 0 ){
    LOG_printf(&trace,"BUF_delete failed!");
}
```

**See Also**

- BUF_create
**BUF_free**  
*Free a fixed memory buffer into the buffer pool*

**C Interface**

Syntax

```c
status = BUF_free(buf, bufaddr);
```

Parameters

- **BUF_Handle** buf; /* buffer pool object handle */
- **Ptr** bufaddr; /* address of buffer to free */

Return Value

- **Bool** status; /* returned status */

**Reentrant**

yes

**Description**

BUF_free frees the specified buffer back to the specified buffer pool. The newly freed buffer is then available for further allocation by BUF_alloc.

The buf parameter is the handle that identifies the buffer pool object. This handle is the one returned by the call to BUF_create.

The bufaddr parameter is the pointer returned by the corresponding call to BUF_alloc.

BUF_free always returns TRUE if DSP/BIOS real-time analysis is disabled (in the GBL Module Properties). If real-time analysis is enabled, BUF_free returns TRUE if the bufaddr parameter is within the range of the specified buffer pool; otherwise it returns FALSE.

The BUF module manages synchronization so that multiple threads can share the same buffer pool for allocation and free operations.

The time required to successfully execute BUF_free is deterministic (constant over multiple calls).

**Example**

```c
extern BUF_Obj bufferPool;
BUF_Handle buffPoolHandle = &bufferPool;
Ptr buffPtr;

...

BUF_free(buffPoolHandle, buffPtr);
```

**See Also**

- BUF_alloc
- MEM_free
**BUF_maxbuff**  
*Check the maximum number of buffers from the buffer pool*

**C Interface**

**Syntax**

```
count = BUF_maxbuff(buf);
```

**Parameters**

- `BUF_Handle buf; /* buffer pool object Handle */`

**Return Value**

- `Uns count; /*maximum number of buffers used */`

**Reentrant**

- `no`

**Description**

BUF_maxbuff returns the maximum number of buffers that have been allocated from the specified buffer pool at any time. The count measures the number of buffers in use, not the total number of times buffers have been allocated.

The `buf` parameter is the handle that identifies the buffer pool object. This handle is the one returned by the call to BUF_create.

BUF_maxbuff distinguishes free and allocated buffers via a stamp mechanism. Allocated buffers are marked with the BUF_ALLOCSTAMP stamp (0xc0e). If the application happens to change this stamp to the BUF_FREESTAMP stamp (0xbeef), the count may be inaccurate. Note that this is not an application error. This stamp is only used for BUF_maxbuff, and changing it does not affect program execution.

The time required to successfully execute BUF_maxbuff is not deterministic (that is, the time varies over multiple calls).

**Constraints and Calling Context**

- BUF_maxbuff cannot be called from a SWI or HWI.
- The application must implement synchronization to ensure that other threads do not perform BUF_alloc during the execution of BUF_maxbuff. Otherwise, the count returned by BUF_maxbuff may be inaccurate.

**Example**

```c
extern BUF_Obj bufferPool;
BUF_Handle buffPoolHandle = &bufferPool;
Int maxbuff;

maxbuff =BUF_maxbuff(buffPoolHandle);
LOG_printf(&trace, "Max buffers used: %d", maxbuff);
```

**See Also**
**BUF_stat**  
*Determine the status of a buffer pool*

### C Interface

**Syntax**
```
BUF_stat(buf, statbuf);
```

**Parameters**
- `BUF_Handle buf;`  /* buffer pool object handle */
- `BUF_Stat *statbuf;`  /* pointer to buffer status structure */

**Return Value**
- `none`

**Reentrant**
- `yes`

**Description**

BUF_stat returns the status of the specified buffer pool.

The `buf` parameter is the handle that identifies the buffer pool object. This handle is the one returned by the call to BUF_create.

The `statbuf` parameter must be a structure of type `BUF_Stat`. The BUF_stat function fills in all the fields of the structure. The `BUF_Stat` type has the following fields:

```c
typedef struct BUF_Stat {
   MEM_sizep postalignsize;  /* Size after align */
   MEM_sizep size;   /* Original size of buffer */
   Uns totalbuffers; /* Total # of buffers in pool */
   Uns freebuffers;  /* # of free buffers in pool */
} BUF_Stat;
```

Size values are expressed in Minimum Addressable Data Units (MADUs). BUF_stat collects statistics with interrupts disabled to ensure the correctness of the statistics gathered.

The time required to successfully execute BUF_stat is deterministic (constant over multiple calls).

**Example**
```
extern BUF_Obj bufferPool;
BUF_Handle buffPoolHandle = &bufferPool;
BUF_Stat stat;

BUF_stat(buffPoolHandle, &stat);
LOG_printf(&trace, "Free buffers Available: %d", stat.freebuffers);
```

**See Also**
- MEM_stat
2.3 C55 Module

The C55 module include target-specific functions for the TMS320C5000 family

Functions

- C55_disableIER0, C55_disableIER1. ASM macros to disable selected interrupts in the IER0/IER1, respectively
- C55_disableInt. Disable an individual interrupt.
- C55_enableIER0, C55_enableIER1. ASM macros to enable selected interrupts in the IER0/IER1, respectively
- C55_enableInt. Enable an individual interrupt.
- C55_l2AckInt. Explicitly acknowledge an L2 interrupt
- C55_l2DisableMIR, C55_l2DisableMIR1. Disable a set of L2 interrupts
- C55_l2EnableMIR, C55_l2EnableMIR1. Enable a set of L2 interrupts
- C55_l2SetIntPriority. Set the priority of a L2 interrupt
- C55_plug. Plug interrupt vector

Description

The C55 module provide certain target-specific functions and definitions for the TMS320C5000 family of processors.

See the c55.h file for a complete list of definitions for hardware flags for C. The c55.h file contain C language macros, #defines for various TMS320C5000 registers, and structure definitions. The c55.h55 file also contain assembly language macros for saving and restoring registers in HWIs.
**C55_disableIER0, C55_disableIER1**

Disable certain maskable interrupts

**C Interface**

**Syntax**

```c
oldmask = C55_disableIER0(mask);
oldmask = C55_disableIER1(mask);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Uns</td>
<td>mask; /* disable mask */</td>
</tr>
</tbody>
</table>

**Return Value**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Uns</td>
<td>oldmask; /* actual bits cleared by disable mask */</td>
</tr>
</tbody>
</table>

**Description**

C55_disableIER0 and C55_disableIER1 disable interrupts by clearing the bits specified by mask in the Interrupt Enable Register (IER0/IER1).

C55_disableIER0 and C55_disableIER1 return a mask of bits actually cleared. This return value should be passed to C55_enableIER0 or C55_enableIER1 to re-enable interrupts.

See C55_enableIER0, C55_enableIER1 for a description and code examples for safely protecting a critical section of code from interrupts.

**See Also**

C55_enableIER0, C55_enableIER1
C55_disableInt

Disable an individual interrupt

C Interface

Syntax

C55_disableInt(vecid);

Parameters

Uns vecid; /* vector ID for interrupt */

Return Value

Void

Description

This function disables an individual interrupt referenced by a vector ID. The vector ID can match a level 1 interrupt (vecids 0-31) or an OMAP 2320/2420 level 2 interrupt (vecids 32-63). For OMAP 2320, the additional level 2 interrupts 32-63 can be disabled using vecids 64-95.

The c55.h header file provides some convenient interrupt ID definitions.

See Also

C55_enableInt
C55_enableIER0, C55_enableIER1

Enable certain maskable interrupts

C Interface

Syntax

C55_enableIER0(oldmask);
C55_enableIER1(oldmask);

Parameters

Uns oldmask; /* enable mask */

Return Value

Void

Description

C55_disableIER0, C55_disableIER1, C55_enableIER0, and C55_enableIER1 disable and enable specific internal interrupts by modifying the Interrupt Enable Register (IER0/IER1). C55_disableIER0 and C55_disableIER1 clear the bits specified by the mask parameter in the Interrupt Mask Register and return a mask of the bits it cleared. C55_enableIER0 and C55_enableIER1 set the bits specified by the oldmask parameter in the Interrupt Mask Register.

C55_disableIER0 and C55_disableIER1 and C55_enableIER0 and C55_enableIER1 are usually used in tandem to protect a critical section of code from interrupts. The following code examples show a region protected from all maskable interrupts:

/* C example */
Uns oldmask;

oldmask0 = c55_disableIER0(~0);
`do some critical operation;`
`do not call TSK_sleep, SEM_post, etc.`
c55_enableIER0(oldmask0);

Note: DSP/BIOS kernel calls that can cause rescheduling of tasks (for example, SEM_post and TSK_sleep) should be avoided within a C55_disableIER0, C55_disableIER1, C55_enableIER0, and / C55_enableIER1 block since the interrupts can be disabled for an indeterminate amount of time if a task switch occurs.
You can use C55_disableIER0, C55_disableIER1, C55_enableIER0, and C55_enableIER1 to disable selected interrupts, while allowing other interrupts to occur. However, if another hardware interrupt occurs during this region, it could cause a task switch. You can prevent this by enclosing it with TSK_disable / TSK_enable to disable DSP/BIOS task scheduling.

Uns oldmask;

TKS_disable();
oldmask0 = C55_disableIER0(INTMASK0);
oldmask1 = C55_disableIER1(INTMASK1);
`do some critical operation;``
`NOT OK to call TSK_sleep, SEM_post, etc.`
C55_enableIER0(oldmask0);
C55_enableIER0(oldmask1);
TSK_enable();

**Note:** If you use C55_disableIER0, C55_disableIER1, C55_enableIER0, and C55_enableIER1 to disable only some interrupts, you must surround this region with SWI_disable / SWI_enable, to prevent an intervening HWI from causing a SWI or TSK switch.

The second approach is preferable if it is important not to disable all interrupts in your system during the critical operation.

**See Also**
C55_disableIER0, C55_disableIER1
C55_enableInt  
Enable an individual interrupt

C Interface

Syntax
C55_enableInt(vecid);

Parameters
Uns vecid; /* vector ID for interrupt */

Return Value
Void

Description
This function enables an individual interrupt referenced by a vector ID. The vector ID can match a level 1 interrupt (vecids 0-31) or an OMAP2320/2420 level 2 interrupt (vecids 32-63). For OMAP 2320, the additional level 2 interrupts 32-63 can be enabled using vecids 64-95.

The c55.h header file provides some convenient interrupt ID definitions.

Example
Void main ()
{
    HWI_Attrs attrs = HWI_ATTRS;
    // pass vector ID to myIsr
    attrs.arg = (Arg)C55_L2_INT1;
    // Plug Level 2 Interrupt #1 Vector
    HWI_dispatchPlug(C55_L2_INT1, (Fxn)myIsr, &attrs);
    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}

See Also
C55_disableInt
**C55_l2AckInt**  
*Explicitly acknowledge an L2 interrupt*

**C Interface**

**Syntax**

C55_l2AckInt();

**Parameters**

Void

**Return Value**

Void

**Description**

This API applies to the OMAP 2320/2420 platforms only.

The L2IC requires the interrupts be explicitly acknowledged prior to returning from an ISR in order to allow other L2 interrupts to be processed.

The DSP/BIOS HWI dispatcher handles this acknowledgement for HWI functions coded in C that use the HWI dispatcher. The HWI_enter and HWI_exit macros provide this functionality for HWI functions coded in assembly.

The C55_l2AckInt function is for use only in HWI functions that are coded in C but that do not use the HWI dispatcher. Such functions are "interrupt" defined C code ISRs, which are dynamically plugged using C55_plug or statically plugged using Tconf.

The C55_l2AckInt function is #defined so that inline code is generated in order to minimize the register context saving code generated by the compiler when using the "interrupt" keyword.

**Important:** Recall that ISRs defined using the "interrupt" keyword are not allowed to call any DSP/BIOS functions. The C55_l2AckInt function is an exception to this rule.

**Constraints and Calling Context**

- This API must be called only in the context of a HWI function. That function must be coded in C using the interrupt keyword. The HWI must not use the HWI dispatcher. In addition, the HWI function must not call any DSP/BIOS functions other than C55_l2AckInt.

**Example**

```c
interrupt void myIsr()
{
    // Acknowledge this level 2 interrupt to the L2IC
    C55_l2AckInt();

    // Your code here
}
```

**See Also**

C55_l2DisableMIR
**C55_l2DisableMIR**  
_Disable certain level 2 interrupts_

**C Interface**

Syntax

```c
C55_l2DisableMIR(mirmask);
```

Parameters

- **LgUns mirmask; /* disable mask */**

Return Value

**Void**

**Description**

This API applies to OMAP 2320/2420 platforms only.

C55_l2DisableMIR disables level 2 interrupts by setting the bits specified by mirmask in the Interrupt Mask Register (MIR). The MIR is a register in the Level 2 Interrupt Controller (L2IC) that defines which level 2 interrupts (0-31) are enabled or disabled. (Set bits are disabled.)

This function provides the functionality of C55_disableIer0/1 for level 2 interrupts. The mirmask argument is a 32-bit bitmask that defines which level 2 interrupts to disable.

**See Also**

C55_l2EnableMIR
C55_l2DisableMIR1  

Disable certain level 2 interrupts

C Interface

Syntax

C55_l2DisableMIR1(mir1mask);

Parameters

LgUns mir1mask; /* disable mask */

Return Value

Void

Description

This API applies to the OMAP 2320 platform only.

C55_l2DisableMIR1 disables level 2 interrupts by setting the bits specified by mir1mask in the Interrupt Mask Register1 (MIR1). The MIR1 is a register in the Level 2 Interrupt Controller (L2IC) that defines which level 2 interrupts (32-63) are enabled or disabled. (Set bits are disabled.)

This function provides the functionality of C55_disableIer0/1 for level 2 interrupts. The mir1mask argument is a 32-bit bitmask that defines which level 2 interrupts to disable.

See Also

C55_l2EnableMIR1
C55_l2EnableMIR  

Enable certain level 2 interrupts

C Interface

Syntax

C55_l2EnableMIR(mirmask);

Parameters

LgUns mirmask; /* disable mask */

Return Value

Void

Description

This API applies to the OMAP 2320/2420 platforms only.

C55_l2EnableMIR enables level 2 interrupts by clearing the bits specified by mirmask in the Interrupt Mask Register (MIR). The MIR is a register in the Level 2 Interrupt Controller (L2IC) that defines which level 2 interrupts (0-31) are enabled or disabled. (Cleared bits are enabled.)

This function provides the functionality of C55_enableIer0/1 for level 2 interrupts. The mirmask argument is a 32-bit bitmask that defines which level 2 interrupts to enable.

Example

// Enables L2 interrupts 10, 11, 12, 13
// 0x3c00 = 11110000000000 binary
C55_l2EnableMIR(0x00003c00);

See Also

C55_l2DisableMIR


**C55_l2EnableMIR1**  
*Enable certain level 2 interrupts*

**C Interface**

Syntax

```c
C55_l2EnableMIR1(mir1mask);
```

Parameters

- `LgUns mir1mask; /* disable mask */`

Return Value

- `Void`

**Description**

This API applies to the OMAP 2320 platform only.

C55_l2EnableMIR1 enables level 2 interrupts by clearing the bits specified by `mir1mask` in the Interrupt Mask Register 1 (MIR1). The MIR1 is a register in the Level 2 Interrupt Controller (L2IC) that defines which level 2 interrupts (32-63) are enabled or disabled. (Cleared bits are enabled.)

This function provides the functionality of `C55_enableIer0/1` for level 2 interrupts. The `mir1mask` argument is a 32-bit bitmask that defines which level 2 interrupts to enable.

**Example**

```c
// Enables L2 interrupts 42, 43, 44, 45
// 0x3c00 = 11110000000000 binary
C55_l2EnableMIR1(0x00003c00);
```

**See Also**

- `C55_l2DisableMIR1`
C55_l2SetIntPriority — Set the priority of a level 2 interrupt

C Interface

Syntax

C55_l2SetIntPriority(vecid, priority);

Parameters

Uns vecid; /* vector ID of interrupt */
Uns priority; /* new priority of interrupt */

Return Value

Void

Description

This API applies to the OMAP 2320/2420 platforms only.

The Level 2 Interrupt Controller (L2IC) allows you to set the relative priority of each of the level 2 interrupts.

The default interrupt priorities match the interrupt number. That is, level 2 interrupts 0-31 (logical interrupt IDs 32-63) have priorities 0-31 respectively. The additional OMAP 2320 L2 interrupts 32-63 (logical interrupt IDs 64-95) have priorities 32-63 respectively.

The L2 controller defines level 0 to be the highest priority and level 31 the lowest (63 for the OMAP 2320). Therefore the default priority settings give highest priority to L2 interrupt 0 and lowest to interrupt 31 (63 for the OMAP 2320).

The level 2 interrupt priority setting is independent of whether the interrupt is serviced by the dispatcher or not.

Example

Void main()
{
    HWI_Attrs attrs;
    attrs = HWI_ATTRS;

    attrs.arg = (Arg)C55_L2_INT10;
    HWI_dispatchPlug( C55_L2_INT10, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT10, 0);

    ...
}

See Also

C55_enableInt
C55_plug

C function to plug an interrupt vector

C Interface

Syntax

C55_plug(vecid, fxn);

Parameters

Int vecid; /* interrupt id */
Fxn fxn; /* pointer to HWI function */

Return Value

Void

Description

C55_plug hooks up the specified function as the branch target for a hardware interrupt (fielded by the CPU) at the vector address corresponding to vecid. C55_plug does not enable the interrupt. Use C55_enableIER0, C55_enableIER1 to enable specific interrupts.

Constraints and Calling Context

• vecid must be a valid interrupt ID in the range of 0-31. (The range is 0-95 for OMAP 2320. The range is 0-63 for OMAP 2420.)

See Also

C55_enableIER0, C55_enableIER1
2.4 CLK Module

The CLK module is the clock manager.

Functions

- CLK_countspms. Timer counts per millisecond
- CLK_cpuCyclesPerHtime. Return high-res time to CPU cycles factor
- CLK_cpuCyclesPerLtime. Return low-res time to CPU cycles factor
- CLK_gethtime. Get high-resolution time
- CLK_getltime. Get low-resolution time
- CLK_getprd. Get period register value
- CLK_reconfig. Reset timer period and registers using CPU frequency
- CLK_setTimerFunc. Assign function to a timer (C5505, C5515, C5517, C5535 only)
- CLK_start. Restart low-resolution timer
- CLK_stop. Stop low-resolution timer

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the CLK Manager Properties and CLK Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>C55x Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>TIMERS_BASE</td>
<td>Numeric</td>
<td>0x7000 (OMAP 2420 only)</td>
</tr>
<tr>
<td>TIMERS_BASE_DATAMEM</td>
<td>Numeric</td>
<td>0x7ee000 (OMAP 2420 only)</td>
</tr>
<tr>
<td>TIMERSELECT</td>
<td>String</td>
<td>&quot;Timer 0&quot; (&quot;Timer 5&quot; for OMAP 2420)</td>
</tr>
<tr>
<td>ENABLECLK</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>HIRESTIME</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>ENABLEHTIME</td>
<td>Bool</td>
<td>true (C5501, 5502, OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>MICROSECONDS</td>
<td>Int16</td>
<td>1000.0071</td>
</tr>
<tr>
<td>CONFIGURETIMER</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>FIXTDDR</td>
<td>Bool</td>
<td>false (not for OMAP 2320/2420)</td>
</tr>
<tr>
<td>LOAD_TIM</td>
<td>Int16</td>
<td>2999 (1x10, 59xx only)</td>
</tr>
<tr>
<td>TCRTDDR</td>
<td>EnumInt</td>
<td>0 (0 to 15) (not for OMAP 2320/2420)</td>
</tr>
<tr>
<td>TCRPTV</td>
<td>EnumInt</td>
<td>0 (0 to 7) (1x10, 59xx only)</td>
</tr>
<tr>
<td>PRD</td>
<td>Int16</td>
<td>46666, 7499, or 59999 (varies by platform) (not used for 1x10, 59xx)</td>
</tr>
</tbody>
</table>
The CLK module provides methods for gathering timing information and for invoking functions periodically. The CLK module provides real-time clocks with functions to access the low-resolution and high-resolution times. These times can be used to measure the passage of time in conjunction with STS accumulator objects, as well as to add timestamp messages in event logs.

DSP/BIOS provides the following timing methods:

- **Timer Counter.** This DSP/BIOS counter changes at a relatively fast platform-specific rate that is determined by your CLK Manager Property settings. This counter is used only if the Clock Manager is enabled in the CLK Manager Properties.

- **Low-Resolution Time.** This time is incremented when the timer counter reaches its target value. When this time is incremented, any functions defined for CLK objects are run.

- **High-Resolution Time.** For some platforms, the timer counter is also used to determine the high-resolution time. For other platforms, a different timer is used for the high-resolution time.

- **Periodic Rate.** The PRD functions can be run at a multiple of the clock interrupt rate (the low-resolution rate) if you enable the "Use CLK Manager to Drive PRD" in the PRD Manager Properties.

- **System Clock.** The PRD rate, in turn, can be used to run the system clock, which is used to measure TSK-related timeouts and ticks. If you set the "TSK Tick Driven By" in the TSK Manager Properties to "PRD", the system clock ticks at the specified multiple of the clock interrupt rate (the low-resolution rate).

### Timer Counter

The timer counter changes at a relatively fast rate until it reaches a target value. When the target value is reached, the timer counter is reset, a timer interrupt occurs, the low-resolution time is incremented, and any functions defined for CLK objects are run.
Table 2-1 shows the rate at which the timer counter changes, its target value, and how the value is reset once the target value has been reached.

<table>
<thead>
<tr>
<th>Platform</th>
<th>Timer Counter Rate</th>
<th>Target Value</th>
<th>Value Reset</th>
</tr>
</thead>
<tbody>
<tr>
<td>'C5501, 'C5502</td>
<td>Incremented at CLKOUT / (PLLDIV1 * (TDDR+1)), where CLKOUT is the DSP clock speed in MHz (see GBL Module Properties), and TDDR is the value of the timer divide-down register (see CLK Manager Properties). PLLDIV1 is an additional divide-down factor; DSP/BIOS assumes its value is 4. If you change the value of PLLDIV1, timings will be incorrect.</td>
<td>PRD value</td>
<td>Counter reset to 0.</td>
</tr>
<tr>
<td>'C5503, 'C5507, 'C5509, 'C5510, 'C5561</td>
<td>Decremented at CLKOUT / (TDDR+1), where CLKOUT is the DSP clock speed in MHz (see GBL Module Properties) and TDDR is the value of the timer divide-down register (see CLK Manager Properties).</td>
<td>0</td>
<td>Counter reset to PRD value.</td>
</tr>
<tr>
<td>1x10 and 59xx</td>
<td>Decremented at: CLKOUT * (2^{(TCRPTV+1)}), where CLKOUT is the DSP clock speed in MHz (see GBL Module Properties) and TCRPTV is the value in the prescalar register (see CLK Manager Properties).</td>
<td>0</td>
<td>Counter reset to PRD value.</td>
</tr>
<tr>
<td>OMAP 2320</td>
<td>Incremented at DSP clock speed</td>
<td>Counter register rolls over.</td>
<td>Counter reset to 0.</td>
</tr>
<tr>
<td>OMAP 2420</td>
<td>Incremented at the INPUTCLK rate, which is usually either 32 kHz or 12 MHz (see CLK Manager Properties).</td>
<td>Counter register rolls over.</td>
<td>Counter reset to period register value of 0xFFFFFFFF minus PRD value in CLK Manager Properties.</td>
</tr>
</tbody>
</table>

Low-Resolution Time

When the value of the timer counter is reset to the value in the right-column of Table 2-1, the following actions happen:

- A timer interrupt occurs
- As a result of the timer interrupt, the HWI object for the timer runs the CLK_F_isr function.
- The CLK_F_isr function causes the low-resolution time to be incremented by 1.
- The CLK_F_isr function causes all the CLK Functions to be performed in sequence in the context of that HWI.

Therefore, the low-resolution clock ticks at the timer interrupt rate and returns the number of timer interrupts that have occurred. You can use the CLK_gettime function to get the low-resolution time and the CLK_getprd function to get the value of the period register property.

You can use GBL_setFrequency, CLK_stop, CLK_reconfig, and CLK_start to change the low-resolution timer rate.

The low-resolution time is stored as a 32-bit value. Its value restarts at 0 when the maximum value is reached.
High-Resolution Time

The high-resolution time is determined as follows for your platform:

Table 2-2: High-Resolution Time Determination

<table>
<thead>
<tr>
<th>Platform</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>'C5501, 'C5502</td>
<td>A separate DSP/BIOS counter for the high-resolution time runs at the following rate: CLKOUT / PLLDIV1. This timer counter is stored in 64 bits.</td>
</tr>
<tr>
<td>'C5503, 'C5507, 'C5509, 'C5510, 'C5561</td>
<td>Number of times the timer counter has been decremented.</td>
</tr>
<tr>
<td>1x10 and 59xx</td>
<td>Number of times the timer counter has been decremented.</td>
</tr>
<tr>
<td>OMAP 2320</td>
<td>Number of times the timer counter has been incremented.</td>
</tr>
<tr>
<td>OMAP 2420</td>
<td>The value of Timer 7 running at 12 MHz. This value is stored in 32 bits.</td>
</tr>
</tbody>
</table>

You can use the CLK_gethtime function to get the high-resolution time and the CLK_countspms function to get the number of hardware timer counter register ticks per millisecond.

The high-resolution time is stored as a 32-bit value. For platforms that use the same timer counter as the low-resolution time, the 32-bit high-resolution time is actually calculated by multiplying the low-resolution time by the value of the PRD property and adding number of timer counter increments or decrements (depending on your platform) since the last timer counter reset.

The high-resolution value restarts at 0 when the maximum value is reached.

CLK Functions

The CLK functions performed when a timer interrupt occurs are performed in the context of the hardware interrupt that caused the system clock to tick. Therefore, the amount of processing performed within CLK functions should be minimized and these functions can only invoke DSP/BIOS calls that are allowable from within an HWI.

Note: CLK functions should not call HWI_enter and HWI_exit as these are called internally by DSP/BIOS when it runs CLK_F_isr. Additionally, CLK functions should not use the interrupt keyword or the INTERRUPT pragma in C functions.

CLK Manager Properties

The following global properties can be set for the CLK module in the CLK Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the CLK objects created in the configuration.
  - Tconf Name: OBJMEMSEG
  - Type: Reference
  - Example: `bios.CLK.OBJMEMSEG = prog.get("myMEM");`

- **CPU Interrupt.** Shows which HWI interrupt is used to drive the timer services. The value is changed automatically when you change the Timer Selection. This is an informational property only.
  - Tconf Name: N/A
• **Timer Selection.** The on-device timer to use. Changing this setting also automatically changes the CPU Interrupt used to drive the timer services and the function property of the relevant HWI objects.

  Tconf Name: **TIMERSELECT**
  Type: String
  Options: "Timer 0", "Timer 1" (exception: "Timer 5" and "Timer 6" for OMAP 2420)
  Example: `bios.CLK.TIMERSELECT = "Timer 0";`

• **Base Address of Timers in IO Space.** This property points to the address of GP timer 5 within the DSP address space. This location is set by the DSP MMU configuration shown in Section D.2.2, *GEL Configuration*. The locations of timers 6 and 7 are determined by adding 0x0400 and 0x0800 respectively to the base address. (OMAP 2420 only)

  Tconf Name: **TIMERS_BASE**
  Type: Numeric
  Example: `bios.CLK.TIMERS_BASE = 0x07000;`

• **Base Address of Timers in Data Space.** This property points to the address of the OMAP 2420 timers as mapped in the Data space by the ARM. (OMAP 2420 only)

  Tconf Name: **TIMERS_BASE_DATAMEM**
  Type: Numeric
  Example: `bios.CLK.TIMERS_BASE_DATAMEM = 0x7ee000;`

• **Enable CLK Manager.** If this property is set to true, the on-device timer hardware is used to drive the high- and low-resolution times and to trigger execution of CLK functions. On platforms where the separate ENABLEHTIME property is available, setting the ENABLECLK property to true and the ENABLEHTIME property to false enables only the low-resolution timer.

  Tconf Name: **ENABLECLK**
  Type: Bool
  Example: `bios.CLK.ENABLECLK = true;`

• **Use high resolution time for internal timings.** If this property is set to true, the high-resolution timer is used to monitor internal periods. Otherwise the less intrusive, low-resolution timer is used.

  Tconf Name: **HIRESTIME**
  Type: Bool
  Example: `bios.CLK.HIRESTIME = true;`

• **Enable high resolution timer.** If this property is set to true, this parameter enables the high-resolution timer. This property is available only for the 'C5501, 'C5502, and OMAP 2320/2420. For platforms that use only one timer, the high-resolution and low-resolution timers are both enabled and disabled by the "Enable CLK Manager" property.

  Tconf Name: **ENABLEHTIME**
  Type: Bool
  Example: `bios.CLK.ENABLEHTIME = true;`

• **Microseconds/Int.** The number of microseconds between timer interrupts. The period register is set to a value that achieves the desired period as closely as possible.

  Tconf Name: **MICROSECONDS**
  Type: Int16
  Example: `bios.CLK.MICROSECONDS = 1000;`

• **Directly configure on-device timer registers.** If this property is set to true, the timer’s hardware registers, PRD and TDDR, can be directly set to the desired values. In this case, the Microseconds/Int property is computed based on the values in PRD and TDDR and the CPU clock speed in the GBL Module Properties.

  Tconf Name: **CONFIGURETIMER**
  Type: Bool
  Example: `bios.CLK.CONFIGURETIMER = false;`
• **Fix TDDR.** If this property is set to true, the value in the TDDR property is not modified by changes to the Microseconds/Int property. (Not available for OMAP 2320/2420.)

  Tconf Name: FIXTDDR  
  Type: Bool  
  Example: bios.CLK.FIXTDDR = false;

• **TDDR register.** The value of the on-device timer prescalar. (Not available for 1x10, 59xx, and OMAP 2320/2420.)

  Platform | Options | Size  | Registers |
  --------|---------|-------|-----------|
  'C5503,'C5507,'C5509,'C5510,'C5561 | 00h to 0fh  | 4 bits | part of TCR |
  'C5501,'C5502 | 00h to 0xffffffff | 32 bits | PRD3:PRD4 |

  Tconf Name: TCRDTDDR  
  Type: EnumInt  
  Example: bios.CLK.TCRDTDDR = 2;

• **PRD Register.** This value specifies the interrupt period and is used to configure the PRD register. The default value varies depending on the platform.

  Tconf Name: PRD  
  Type: Int16  
  Example: bios.CLK.PRD = 33250;

• **LOAD_TIM register.** This value is used to configure the PRD register. This is supported only for the 1x10 (1510, 1610, and 1710) and 59xx (5905, 5910, and 5912).

  Tconf Name: LOAD_TIM  
  Type: Int16  
  Example: bios.CLK.LOAD_TIM = 2999;

• **PTV register.** Sets the prescalar register value of the timer. This value is used in calculating the rate at which the timer counter is decremented. The valid values of 0 to 7 lead to prescale values from 02 hex to 100 hex. (1x10 and 59xx only.)

  Tconf Name: TCRPTV  
  Type: EnumInt  
  Options: 0 to 7  
  Example: bios.CLK.TCRPTV = 0;

• **Clock Rate to ltime timer.** Specify the rate in MHz for the low-resolution time. On the OMAP 2420, this may be either the 0.032 MHz clock, the 12 MHz clock, or the external clock. (OMAP 2420 only.)

  Tconf Name: INPUTCLK  
  Type: Numeric  
  Example: bios.CLK.INPUTCLK = 0.032;

• **Clock Rate to htime timer.** Specify the rate in MHz for the high-resolution time. On the OMAP 2420, this may be either the 0.032 MHz clock, the 12 MHz clock, or the external clock. (OMAP 2420 only.)

  Tconf Name: HTIMECLK  
  Type: Numeric  
  Example: bios.CLK.HTIMECLK = 12.0;

• **Instructions/Int.** The number of instruction cycles represented by the period specified above. This is an informational property only.

  Tconf Name: N/A

• **Timer 0-2 Function.** Specifies the function to be executed when the corresponding timer interrupt occurs. (C5505, C5515, C5517, C5535 only)

  Tconf Name: INPUTCLK  
  Type: Numeric  
  Example: bios.CLK.TIMER0FUNC = prog.extern("timer0Fx");
Timer 0-2 Argument. Specifies the argument to be passed to the timer function when the corresponding timer interrupt occurs. (C5505, C5515, C5517, C5535 only)

Tconf Name: INPUTCLK Type: Numeric
Example: bios.CLK.TIMER0ARG = 0;

CLK Object Properties

The Clock Manager allows you to create an arbitrary number of CLK objects. Clock objects have functions, which are executed by the Clock Manager every time a timer interrupt occurs. These functions can invoke any DSP/BIOS operations allowable from within an HWI except HWI_enter or HWI_exit.

To create a CLK object in a configuration script, use the following syntax:

```javascript
var myClk = bios.CLK.create("myClk");
```

The following properties can be set for a clock function object in the CLK Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. The Tconf examples assume the myClk object has been created as shown.

- **comment.** Type a comment to identify this CLK object.
  
  Tconf Name: comment Type: String
  Example: myClk.comment = "Runs timeFxnx";

- **function.** The function to be executed when the timer hardware interrupt occurs. This function must be written like an HWI function; it must be written in C or assembly and must save and restore any registers this function modifies. However, this function can not call HWI_enter or HWI_exit because DSP/BIOS calls them internally before and after this function runs.

  These functions should be very short as they are performed frequently.

  Since all CLK functions are performed at the same periodic rate, functions that need to run at a multiple of that rate should either count the number of interrupts and perform their activities when the counter reaches the appropriate value or be configured as PRD objects.

  If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. (The DSP/BIOS Configuration Tool generates assembly code, which must use leading underscores when referencing C functions or labels.) If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.

  Tconf Name: fxn Type: Extern
  Example: myClk.fxn = prog.extern("timeFxnx");

- **order.** You can change the sequence in which CLK functions are executed by specifying the order property of all the CLK functions.

  Tconf Name: order Type: Int16
  Example: myClk.order = 2;
**CLK_countspms**  *Number of hardware timer counts per millisecond*

**C Interface**

Syntax

```c
ncounts = CLK_countspms();
```

**Parameters**

```
Void
```

**Return Value**

```
LgUns ncounts;
```

**Reentrant**

```
yes
```

**Description**

CLK_countspms returns the number of high-resolution timer counts per millisecond. See Table 2-2 on page 62 for information about how the high-resolution rate is set.

CLK_countspms can be used to compute an absolute length of time from the number of low resolution timer interrupts. For example, the following code computes time in milliseconds.

```c
    timeAbs = (CLK_getltime() * CLK_getprd()) / CLK_countspms();
```

The equation below computes time in milliseconds since the last wrap of the high-resolution timer counter.

```c
    timeAbs = CLK_gethtime() / CLK_countspms();
```

**See Also**

- CLK_gethtime
- CLK_getprd
- CLK_cpuCyclesPerHtime
- CLK_cpuCyclesPerLtime
- GBL_getClkin
- STS_delta
CLK_cpuCyclesPerHtime  

Return multiplier for converting high-res time to CPU cycles

C Interface

Syntax
   ncycles = CLK_cpuCyclesPerHtime(Void);

Parameters
   Void

Return Value
   Float  ncycles;

Reentrant
   yes

Description
CLK_cpuCyclesPerHtime returns the multiplier required to convert from high-resolution time to CPU cycles. High-resolution time is returned by CLK_gethtime.

For example, the following code returns the number of CPU cycles and the absolute time elapsed during processing.

time1 = CLK_gethtime();
... processing ...
time2 = CLK_gethtime();
CPUcycles = (time2 - time1) * CLK_cpuCyclesPerHtime();
/* calculate absolute time in milliseconds */
TimeAbsolute = CPUcycles / GBL_getFrequency();

See Also
CLK_gethtime
CLK_getprd
GBL_getClkin
CLK_cpuCyclesPerLtime

Return multiplier for converting low-res time to CPU cycles

C Interface

Syntax

ncycles = CLK_cpuCyclesPerLtime(Void);

Parameters

Void

Return Value

Float ncycles;

Reentrant

yes

Description

CLK_cpuCyclesPerLtime returns the multiplier required to convert from low-resolution time to CPU cycles. Low-resolution time is returned by CLK_getltime.

For example, the following code returns the number of CPU cycles and milliseconds elapsed during processing.

time1 = CLK_getltime();
... processing ...
time2 = CLK_getltime();
CPUcycles = (time2 - time1) * CLK_cpuCyclesPerLtime();
/* calculate absolute time in milliseconds */
TimeAbsolute = CPUcycles / GBL_getFrequency();

See Also

CLK_getltime
CLK_getprd
GBL_getClkin

www.ti.com
**CLK_gethtime**  
*Get high-resolution time*

**C Interface**

**Syntax**

```
curtime = CLK_gethtime();
```

**Parameters**

Void

**Return Value**

LgUns curtime /* high-resolution time */

**Reentrant**

no

**Description**

CLK_gethtime returns the number of high-resolution clock cycles that have occurred as a 32-bit value. When the number of cycles reaches the maximum value that can be stored in 32 bits, the value wraps back to 0. See “High-Resolution Time” on page 62 for information about how the high-resolution rate is set.

CLK_gethtime provides a value with greater accuracy than CLK_getlttime, but which wraps back to 0 more frequently. For example, if the timer tick rate is 200 MHz, then regardless of the period register value, the CLK_gethtime value wraps back to 0 approximately every 86 seconds.

CLK_gethtime can be used in conjunction with STS_set and STS_delta to benchmark code. CLK_gethtime can also be used to add a time stamp to event logs.

**Constraints and Calling Context**

- CLK_gethtime cannot be called from the program’s main() function.

**Example**

```plaintext
/* ======== showTime ======== */

Void showTicks
{
    LOG_printf(&trace, "time = %d", CLK_gethtime());
}
```

**See Also**

CLK_gethtime  
PRD_getticks  
STS_delta
CLK_getltime

Get low-resolution time

C Interface

Syntax

```c
currtime = CLK_getltime();
```

Parameters

- Void

Return Value

- LgUns curtime /* low-resolution time */

Reentrant

- yes

Description

CLK_getltime returns the number of timer interrupts that have occurred as a 32-bit time value. When the number of interrupts reaches the maximum value that can be stored in 32 bits, value wraps back to 0 on the next interrupt.

The low-resolution time is the number of timer interrupts that have occurred. See “Low-Resolution Time” on page 61 for information about how this rate is set.

The default low resolution interrupt rate is 1 millisecond/interrupt. By adjusting the period register, you can set rates from less than 1 microsecond/interrupt to more than 1 second/interrupt.

CLK_getltime provides a value with more accuracy than CLK_gettime, but which wraps back to 0 more frequently. For example, if the timer tick rate is 80 MHz, and you use the default period register value of 40000, the CLK_getltime value wraps back to 0 approximately every 107 seconds, while the CLK_getltime value wraps back to 0 approximately every 49.7 days.

CLK_getltime is often used to add a time stamp to event logs for events that occur over a relatively long period of time.

Constraints and Calling Context

- CLK_getltime cannot be called from the program’s main() function.

Example

```c
/* ======== showTicks ======== */

Void showTicks
{
    LOG_printf(&trace, "time = 0x%x %x",
        (Int)(CLK_getltime() >> 16), (Int)CLK_getltime());
}
```

See Also

- CLK_gettime
- PRD_getticks
- STS_delta
**CLK_getprd**  
*Get period register value*

**C Interface**

**Syntax**

```c
period = CLK_getprd();
```

**Parameters**

- **Void**

**Return Value**

- **Uns** `period` /* period register value */

**Reentrant**

- **yes**

**Description**

CLK_getprd returns the number of high-resolution timer counts per low-resolution interrupt. See Table 2-2 on page 62 for information about how the high-resolution rate is set.

CLK_getprd can be used to compute an absolute length of time from the number of low-resolution timer interrupts. For example, the following code computes time in milliseconds.

```c
timeAbs = (CLK_getltime() * CLK_getprd()) / CLK_countspms();
```

**See Also**

- CLK_countspms
- CLK_gettime
- CLK_cpuCyclesPerHtime
- CLK_cpuCyclesPerLtime
- GBL_getClkin
- STS_delta
CLK_reconfig

Reset timer period and registers using current CPU frequency

C Interface

Syntax

status = CLK_reconfig();

Parameters

Void

Return Value

Bool status /* FALSE if failed */

Reentrant

yes

Description

This function needs to be called after a call to GBL_setFrequency. It computes values for the timer period and the prescalar registers using the new CPU frequency. The new values for the period and prescalar registers ensure that the CLK interrupt runs at the statically configured interval in microseconds.

The return value is FALSE if the timer registers cannot accommodate the current frequency or if some other internal error occurs.

When calling CLK_reconfig outside of main(), you must also call CLK_stop and CLK_start to stop and restart the timer. Use the following call sequence:

/* disable interrupts if an interrupt could lead to another call to CLK_reconfig or if interrupt processing relies on having a running timer */
HWI_disable() or SWI_disable()
GBL_setFrequency(cpuFreqInKhz);
CLK_stop();
CLK_reconfig();
CLK_start();
HWI_restore() or SWI_enable()

When calling CLK_reconfig from main(), the timer has not yet been started. (The timer is started as part of BIOS_startup(), which is called internally after main.) As a result, you can use the following simplified call sequence in main():

GBL_setFrequency(cpuFreqInKhz);
CLK_reconfig(Void);

Note that GBL_setFrequency does not affect the PLL, and therefore has no effect on the actual frequency at which the DSP is running. It is used only to make DSP/BIOS aware of the DSP frequency you are using.

Constraints and Calling Context

- When calling CLK_reconfig from anywhere other than main(), you must also use CLK_stop and CLK_start.
• Call HWI_disable/HWI_restore or SWI_disable/SWI_enable around a block that stops, configures, and restarts the timer as needed to prevent re-entrancy or other problems. That is, you must disable interrupts if an interrupt could lead to another call to CLK_reconfig or if interrupt processing relies on having a running timer to ensure that these non-reentrant functions are not interrupted.

• If you use the PWRM module for V/F scaling and the "Reprogram BIOS clock after frequency scaling" PWRM property is configured as "true", do not call CLK_reconfig. This is because the PWRM module internally calls this API.

• If you do not stop and restart the timer, CLK_reconfig can only be called from the program’s main() function.

• If you use CLK_reconfig, you should also use GBL_setFrequency.

See Also
GBL_getFrequency
GBL_setFrequency
CLK_start
CLK_stop
CLK_setTimerFunc

Set the function for a special timer

C Interface

Syntax

CLK_setTimerFunc(timerId, *func, arg);

Parameters

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Uns</td>
<td>timerId: */ timer ID number */</td>
</tr>
<tr>
<td>Void</td>
<td>(<em>func)(Arg); /</em> function for timer to run */</td>
</tr>
<tr>
<td>Arg</td>
<td>arg; /* argument to pass to timer function */</td>
</tr>
</tbody>
</table>

Return Value

Void

Description

Certain C55x devices include three 32-bit general-purpose timers. Currently, the devices that provide such timers are the C5505, C5515, C5517, and C5535.

This function dynamically sets a timer interrupt function for one of the three timers. See Appendix E for details.

The timerId should be 0, 1, or 2 to correspond to the timer being used. By default, the DSP/BIOS CLK manager uses timer 0.

The timer interrupt function you specify should have the following signature:

Void timerfunc(Arg arg);

Your timer function must acknowledge the timer's interrupt and clear the timer's interrupt pending status in the timer's "interrupt" register as well as its corresponding status in the "Timer Interrupt Aggregation Flag Register" at IO address 0x1c14.

For example, the following statement dynamically sets timer 1's interrupt handler:

CLK_setTimerFunc(1, myTimer1Func, 4);

When timer 1's interrupt occurs, the CLK interrupt dispatcher calls the configured handler as follows:

myTimer1Func(4);

In addition to specifying a user function using this API, you must fully configure the timer specified by timerId.

See Also

C55_enableInt
**CLK_start**  
*Restart the low-resolution timer*

### C Interface

**Syntax**

```
CLK_start();
```

**Parameters**

`Void`

**Return Value**

`Void`

**Reentrant**

`no`

**Description**

This function starts the low-resolution timer if it has been halted by `CLK_stop`. The period and prescalar registers are updated to reflect any changes made by a call to `CLK_reconfig`. This function then resets the timer counters and starts the timer.

`CLK_start` should only be used in conjunction with `CLK_reconfig` and `CLK_stop`. See the section on `CLK_reconfig` for details and the allowed calling sequence.

Note that all 'C55x platforms except the 'C5501, 'C5502, and OMAP 2320/2420 use the same timer to drive low-resolution and high-resolution times. On such platforms, both times are affected by this API.

### Constraints and Calling Context

- Call `HWI_disable/HWI_restore` or `SWI_disable/SWI_enable` around a block that stops, configures, and restarts the timer as needed to prevent re-entrancy or other problems. That is, you must disable interrupts if an interrupt could lead to another call to `CLK_start` or if interrupt processing relies on having a running timer to ensure that these non-reentrant functions are not interrupted.
- This function cannot be called from `main()`.
- If you use the PWRM module for V/F scaling and the "Reprogram BIOS clock after frequency scaling" PWRM property is "true", do not call `CLK_start`. This is because the PWRM module internally calls this API.

### See Also

- `CLK_reconfig`
- `CLK_stop`
- `GBL_setFrequency`
CLK_stop

Halt the low-resolution timer

C Interface

Syntax

CLK_stop();

Parameters

Void

Return Value

Void

Reentrant

no

Description

This function stops the low-resolution timer. It can be used in conjunction with CLK_reconfig and
CLK_start to reconfigure the timer at run-time.

Note that all 'C55x platforms except the 'C5501, 'C5502, and OMAP 2320/2420 use the same timer to
drive low-resolution and high-resolution times. On such platforms, both times are affected by this API.

CLK_stop should only be used in conjunction with CLK_reconfig and CLK_start, and only in the required
calling sequence. See the section on CLK_reconfig for details.

Constraints and Calling Context

• Call HWI_disable/HWI_restore or SWI_disable/SWI_enable around a block that stops, configures,
and restarts the timer as needed to prevent re-entrancy or other problems. That is, you must disable
interrupts if an interrupt could lead to another call to CLK_stop or if interrupt processing relies on
having a running timer to ensure that these non-reentrant functions are not interrupted

• This function cannot be called from main().

• If you use the PWRM module for V/F scaling and the "Reprogram BIOS clock after frequency scaling"
PWRM property is "true", do not call CLK_stop. This is because the PWRM module internally calls
this API.

See Also

CLK_reconfig
CLK_start
GBL_setFrequency
2.5 DEV Module

The DEV module provides the device interface.

Functions

- DEV_createDevice. Dynamically create device
- DEV_deleteDevice. Delete dynamically-created device
- DEV_match. Match device name with driver
- Dxx_close. Close device
- Dxx_ctrl. Device control
- Dxx_idle. Idle device
- Dxx_init. Initialize device
- Dxx_issue. Send frame to device
- Dxx_open. Open device
- Dxx_ready. Device ready
- Dxx_reclaim. Retrieve frame from device

Description

DSP/BIOS provides two device driver models that enable applications to communicate with DSP peripherals: IOM and SIO/DEV.

The components of the IOM model are illustrated in the following figure. It separates hardware-independent and hardware-dependent layers. Class drivers are hardware independent; they manage device instances, synchronization and serialization of I/O requests. The lower-level mini-driver is hardware-dependent. See the DSP/BIOS Driver Developer’s Guide (SPRU616) for more information on the IOM model.

The SIO/DEV model provides a streaming I/O interface. In this model, the application indirectly invokes DEV functions implemented by the driver managing the physical device attached to the stream, using generic functions provided by the SIO module. See the DSP/BIOS User’s Guide (SPRU423) for more information on the SIO/DEV model.
The model used by a device is identified by its function table type. A type of IOM_Fxns is used with the IOM model. A type of DEV_Fxns is used with the DEV/SIO model.

The DEV module provides the following capabilities:

- **Device object creation.** You can create device objects through static configuration or dynamically through the DEV_createDevice function. The DEV_deleteDevice and DEV_match functions are also provided for managing device objects.

- **Driver function templates.** The Dxx functions listed as part of the DEV module are templates for driver functions. These are the functions you create for drivers that use the DEV/SIO model.

### Constants, Types, and Structures

```c
#define DEV_INPUT       0
#define DEV_OUTPUT      1

typedef struct DEV_Frame {  /* frame object */
    QUE_Elem   link;       /* queue link */
    Ptr        addr;       /* buffer address */
    size_t     size;       /* buffer size */
    Arg        misc;       /* reserved for driver */
    Arg        arg;        /* user argument */
    Uns        cmd;        /* mini-driver command */
    Int        status;     /* status of command */
} DEV_Frame;

typedef struct DEV_Obj {  /* device object */
    QUE_Handle todevice; /* downstream frames here */
    QUE_Handle fromdevice; /* upstream frames here */
    size_t   bufsize; /* buffer size */
    Uns      nbufs;  /* number of buffers */
    Int      segid;  /* buffer segment ID */
    Int      mode;   /* DEV_INPUT/DEV_OUTPUT */
    #if (defined(_54_) && defined(_FAR_MODE)) || defined(_55_)
        LgInt    devid; /* device ID */
    #else
        Int      devid; /* device ID */
    #endif
    Ptr      params;  /* device parameters */
    Ptr      object;  /* ptr to dev instance obj */
    DEV_Fxns fxns;   /* driver functions */
    Uns      timeout; /* SIO_reclaim timeout value */
    Uns      align;   /* buffer alignment */
    DEV_Callback  *callback; /* pointer to callback */
} DEV_Obj;

typedef struct DEV_Fxns { /* driver function table */
    Int     (*close)(   DEV_Handle );
    Int     (*ctrl)(    DEV_Handle, Uns, Arg );
    Int     (*idle)(    DEV_Handle, Bool );
    Int     (*issue)(   DEV_Handle );
    Int     (*open)(    DEV_Handle, String );
```
Bool (*ready)( DEV_Handle, SEM_Handle );
size_t (*reclaim)( DEV_Handle );
} DEV_Fxns;

typedef struct DEV_Callback {
    Fxn     fxn;    /* function */
    Arg     arg0;   /* argument 0 */
    Arg     arg1;   /* argument 1 */
} DEV_Callback;

typedef struct DEV_Device { /* device specifier */
    String  name;  /* device name */
    Void *  fxns;  /* device function table*/
    #if (defined(_54_) && defined(_FAR_MODE)) || defined(_55_)
        LgInt  devid; /* device ID */
    #else
        Int    devid; /* device ID */
    #endif
    Ptr     params; /* device parameters */
    Uns     type;  /* type of the device */
    Ptr     devp;  /* pointer to device handle */
} DEV_Device;

typedef struct DEV_Attrs {
    #if (defined(_54_) && defined(_FAR_MODE)) || defined(_55_)
        LgInt  devid; /* device id */
    #else
        Int    devid; /* device id */
    #endif
    Ptr     params; /* device parameters */
    Uns     type;  /* type of the device */
    Ptr     devp;  /* device global data ptr */
} DEV_Attrs;

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DEV Manager Properties and DEV Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>initFxn</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>fnxTable</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>fnxTableType</td>
<td>EnumString</td>
<td>&quot;DEV_Fxns&quot; (&quot;IOM_Fxns&quot;)</td>
</tr>
<tr>
<td>deviceId</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>params</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>deviceGlobalDataPtr</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
</tbody>
</table>

DEV Manager Properties

The default configuration contains managers for the following built-in device drivers:
• **DGN Driver** *(software generator driver).* pseudo-device that generates one of several data streams, such as a sin/cos series or white noise. This driver can be useful for testing applications that require an input stream of data.

• **DHL Driver** *(host link driver).* Driver that uses the HST interface to send data to and from the Host Channel Control Analysis Tool.

• **DIO Adapter** *(class driver).* Driver used with the device driver model.

• **DPI Driver** *(pipe driver).* Software device used to stream data between DSP/BIOS tasks.

To configure devices for other drivers, use Tconf to create a User-defined Device (UDEV) object. There are no global properties for the user-defined device manager.

The following additional device drivers are supplied with DSP/BIOS:

• **DGS Driver.** Stackable gather/scatter driver

• **DNL Driver.** Null driver

• **DOV Driver.** Stackable overlap driver

• **DST Driver.** Stackable “split” driver

• **DTR Driver.** Stackable streaming transformer driver

**DEV Object Properties**

The following properties can be set for a user-defined device in the UDEV Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. To create a user-defined device object in a configuration script, use the following syntax:

```javascript
var myDev = bios.UDEV.create("myDev");
```

The Tconf examples assume the myDev object is created as shown.

• **comment.** Type a comment to identify this object.
  ```javascript
  Tconf Name: comment Type: String
  Example: myDev.comment = "My device";
  ```

• **init function.** Specify the function to run to initialize this device. Use a leading underscore before the function name if the function is written in C and you are using the DSP/BIOS Configuration Tool. If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.
  ```javascript
  Tconf Name: initFxn Type: Arg
  Example: myDev.initFxn = prog.extern("myInit");
  ```

• **function table ptr.** Specify the name of the device functions table for the driver or mini-driver. This table is of type DEV_Fxns or IOM_Fxns depending on the setting for the function table type property.
  ```javascript
  Tconf Name: fxnTable Type: Arg
  Example: myDev.fxnTable = prog.extern("mydevFxnTable");
  ```

• **function table type.** Choose the type of function table used by the driver to which this device interfaces. Use the IOM_Fxns option if you are using the DIO class driver to interface to a mini-driver with an IOM_Fxns function table. Otherwise, use the DEV_Fxns option for other drivers that use a DEV_Fxns function table and Dxx functions. You can create a DIO object only if a UDEV object with the IOM_Fxns function table type exists.
  ```javascript
  Tconf Name: fxnTableType Type: EnumString
  Options: "DEV_Fxns", "IOM_Fxns"
  Example: myDev.fxnTableType = "DEV_Fxns";
  ```
- **device id.** Specify the device ID. If the value you provide is non-zero, the value takes the place of a value that would be appended to the device name in a call to SIO_create. The purpose of such a value is driver-specific.
  Tconf Name: deviceId Type: Arg
  Example: myDev.deviceId = prog.extern("devID");

- **device params ptr.** If this device uses additional parameters, provide the name of the parameter structure. This structure should have a name with the format DXX_Params where XX is the two-letter code for the driver used by this device.
  Use a leading underscore before the structure name if the structure is declared in C and you are using the DSP/BIOS Configuration Tool.
  Tconf Name: params Type: Arg
  Example: myDev.params = prog.extern("myParams");

- **device global data ptr.** Provide a pointer to any global data to be used by this device. This value can be set only if the function table type is IOM_Fxns.
  Tconf Name: deviceGlobalDataPtr Type: Arg
  Example: myDev.deviceGlobalDataPtr = 0x00000000;
DEV_createDevice

Dynamically create device

C Interface

Syntax

```
status = DEV_createDevice(name, fxns, initFxns, attrs);
```

Parameters

- **name**: String; /* name of device to be created */
- **fxns**: Void *; /* pointer to device function table */
- **initFxns**: Fxn; /* device init function */
- **attrs**: DEV_Attrs *; /* pointer to device attributes */

Return Value

- **status**: Int; /* result of operation */

Reentrant

- **no**

Description

DEV_createDevice allows an application to create a user-defined device object at run-time. The object created has parameters similar to those defined statically for the DEV Object Properties. After being created, the device can be used as with statically-created DEV objects.

The name parameter specifies the name of the device. The device name should begin with a slash (/) for consistency with statically-created devices and to permit stacking drivers. For example "/codec" might be the name. The name must be unique within the application. If the specified device name already exists, this function returns failure.

The fxns parameter points to the device function table. The function table may be of type DEV_Fxns or IOM_Fxns.

The initFxns parameter specifies a device initialization function. The function passed as this parameter is run if the device is created successfully. The initialization function is called with interrupts disabled. If several devices may use the same driver, the initialization function (or a function wrapper) should ensure that one-time initialization actions are performed only once.

The attrs parameter points to a structure of type DEV_Attrs. This structure is used to pass additional device attributes to DEV_createDevice. If attrs is NULL, the device is created with default attributes. DEV_Attrs has the following structure:

```
typedef struct DEV_Attrs {
    #if (defined(_54_) && defined(_FAR_MODE)) || defined(_55_)
        LgInt     devid;  /* device id */
    #else
        Int       devid;  /* device id */
    #endif
    Ptr       params; /* device parameters */
    Uns       type;   /* type of the device */
    Ptr       devp;   /* device global data ptr */
} DEV_Attrs;
```

The devid item specifies the device ID. If the value you provide is non-zero, the value takes the place of a value that would be appended to the device name in a call to SIO_create. The purpose of such a value is driver-specific. The default value is NULL.
The params item specifies the name of a parameter structure that may be used to provide additional parameters. This structure should have a name with the format DXX_Params where XX is the two-letter code for the driver used by this device. The default value is NULL.

The type item specifies the type of driver used with this device. The default value is DEV_IOMTYPE. The options are:

<table>
<thead>
<tr>
<th>Type</th>
<th>Use With</th>
</tr>
</thead>
<tbody>
<tr>
<td>DEV_IOMTYPE</td>
<td>Mini-drivers used in the IOM model.</td>
</tr>
<tr>
<td>DEV_SIOTYPE</td>
<td>DIO adapter with SIO streams or other DEV/SIO drivers</td>
</tr>
</tbody>
</table>

The devp item specifies the device global data pointer, which points to any global data to be used by this device. This value can be set only if the table type is IOM_Fxns. The default value is NULL.

If an initFxn is specified, that function is called as a result of calling DEV_createDevice. In addition, if the device type is DEV_IOMTYPE, the mdBindDev function in the function table pointed to by the fxns parameter is called as a result of calling DEV_createDevice. Both of these calls are made with interrupts disabled.

DEV_createDevice returns one of the following status values:

<table>
<thead>
<tr>
<th>Constant</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>SYS_OK</td>
<td>Success.</td>
</tr>
<tr>
<td>SYS_EINVAL</td>
<td>A device with the specified name already exists.</td>
</tr>
<tr>
<td>SYS_EALLOC</td>
<td>The heap is not large enough to allocate the device.</td>
</tr>
</tbody>
</table>

DEV_createDevice calls SYS_error if mdBindDev returns a failure condition. The device is not created if mdBindDev fails, and DEV_createDevice returns the IOM error returned by the mdBindDev failure.

**Constraints and Calling Context**

- This function cannot be called from a SWI or HWI.
- This function can only be used if dynamic memory allocation is enabled.
- The device function table must be consistent with the type specified in the attrs structure. DSP/BIOS does not check to ensure that the types are consistent.
Example

    Int status;

    /* Device attributes of device "/pipe0" */
    DEV_Attrs dpiAttrs = {
        NULL,
        NULL,
        DEV_SIOTYPE,
        0
    };

    status = DEV_createDevice("/pipe0", &DPI_FXNS,
        (Fxn)DPI_init, &dpiAttrs);
    if (status != SYS_OK) {
        SYS_abort("Unable to create device");
    }

See Also
    SIO_create
DEV_deleteDevice | Delete a dynamically-created device

C Interface

Syntax
```
status = DEV_deleteDevice(name);
```

Parameters
```
String name; /* name of device to be deleted */
```

Return Value
```
Int status; /* result of operation */
```

Reentrant
no

Description
DEV_deleteDevice deallocates the specified dynamically-created device and deletes it from the list of devices in the application.

The name parameter specifies the device to delete. This name must match a name used with DEV_createDevice.

Before deleting a device, delete any SIO streams that use the device. SIO_delete cannot be called after the device is deleted.

If the device type is DEV_IOMTYPE, the mdUnBindDev function in the function table pointed to by the fxns parameter of the device is called as a result of calling DEV_deleteDevice. This call is made with interrupts disabled.

DEV_createDevice returns one of the following status values:

<table>
<thead>
<tr>
<th>Constant</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>SYS_OK</td>
<td>Success.</td>
</tr>
<tr>
<td>SYS_ENODEV</td>
<td>No device with the specified name exists.</td>
</tr>
</tbody>
</table>

DEV_deleteDevice calls SYS_error if mdUnBindDev returns a failure condition. The device is deleted even if mdUnBindDev fails, but DEV_deleteDevice returns the IOM error returned by mdUnBindDev.

Constraints and Calling Context

- This function cannot be called from a SWI or HWI.
- This function can be used only if dynamic memory allocation is enabled.
- The device name must match a dynamically-created device. DSP/BIOS does not check that the device was not created statically.

Example
```
status = DEV_deleteDevice("/pipe0");
```

See Also
SIO_delete
DEV_match

Match a device name with a driver

C Interface

Syntax

```c
substr = DEV_match(name, device);
```

Parameters

- **String** name; /* device name */
- **DEV_Device** **device;** /* pointer to device table entry */

Return Value

- **String** substr; /* remaining characters after match */

Description

DEV_match searches the device table for the first device name that matches a prefix of name. The output parameter, device, points to the appropriate entry in the device table if successful and is set to NULL on error. The DEV_Device structure is defined in dev.h.

The substr return value contains a pointer to the characters remaining after the match. This string is used by stacking devices to specify the name(s) of underlying devices (for example, /scale10/sine might match /scale10, a stacking device, which would, in turn, use /sine to open the underlying generator device).

See Also

SIO_create
**Dxx_close**

*Close device*

**Important:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer’s Guide* (SPRU616).

---

**C Interface**

Syntax

```c
status = Dxx_close(device);
```

Parameters

- **DEV_Handle** device; /* device handle */

Return Value

- **Int** status; /* result of operation */

**Description**

`Dxx_close` closes the device associated with `device` and returns an error code indicating success (SYS_OK) or failure. `device` is bound to the device through a prior call to `Dxx_open`.

`SIO_delete` first calls `Dxx_idle` to idle the device. Then it calls `Dxx_close`.

Once `device` has been closed, the underlying device is no longer accessible via this descriptor.

**Constraints and Calling Context**

- `device` must be bound to a device by a prior call to `Dxx_open`.

**See Also**

- `Dxx_idle`
- `Dxx_open`
- `SIO_delete`
Dxx_ctrl

Device control operation

Important: This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the DSP/BIOS Driver Developer’s Guide (SPRU616).

C Interface

Syntax

```c
status = Dxx_ctrl(device, cmd, arg);
```

Parameters

- `DEV_Handle device /* device handle */`
- `Uns cmd; /* driver control code */`
- `Arg arg; /* control operation argument */`

Return Value

- `Int status; /* result of operation */`

Description

Dxx_ctrl performs a control operation on the device associated with `device` and returns an error code indicating success (SYS_OK) or failure. The actual control operation is designated through `cmd` and `arg`, which are interpreted in a driver-dependent manner.

Dxx_ctrl is called by SIO_ctrl to send control commands to a device.

Constraints and Calling Context

- device must be bound to a device by a prior call to Dxx_open.

See Also

- SIO_ctrl
C Interface

Syntax

status = Dxx_idle(device, flush);

Parameters

DEV_Handle  device; /* device handle */
Bool         flush;    /* flush output flag */

Return Value

Int  status; /* result of operation */

Description

Dxx_idle places the device associated with device into its idle state and returns an error code indicating success (SYS_OK) or failure. Devices are initially in this state after they are opened with Dxx_open.

Dxx_idle returns the device to its initial state. Dxx_idle should move any frames from the device->todevice queue to the device->fromdevice queue. In SIO_ISSUERECLAIM mode, any outstanding buffers issued to the stream must be reclaimed in order to return the device to its true initial state.

Dxx_idle is called by SIO_idle, SIO_flush, and SIO_delete to recycle frames to the appropriate queue.

flush is a boolean parameter that indicates what to do with any pending data of an output stream. If flush is TRUE, all pending data is discarded and Dxx_idle does not block waiting for data to be processed. If flush is FALSE, the Dxx_idle function does not return until all pending output data has been rendered. All pending data in an input stream is always discarded, without waiting.

Constraints and Calling Context

•  device must be bound to a device by a prior call to Dxx_open.

See Also

SIO_delete
SIO_idle
SIO_flush
**Dxx_init**  
*Initialize device*

**Important:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**C Interface**

**Syntax**

```c
Dxx_init();
```

**Parameters**

- **Void**

**Return Value**

- **Void**

**Description**

Dxx_init is used to initialize the device driver module for a particular device. This initialization often includes resetting the actual device to its initial state.

Dxx_init is called at system startup, before the application's main() function is called.
**Dxx_issue**

*Send a buffer to the device*

**Important:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer’s Guide* (SPRU616).

---

**C Interface**

Syntax

```c
status = Dxx_issue(device);
```

**Parameters**

- `DEV_Handle device; /* device handle */`

**Return Value**

- `Int status; /* result of operation */`

**Description**

*Dxx_issue* is used to notify a device that a new frame has been placed on the device->todevice queue. If the device was opened in DEV_INPUT mode, *Dxx_issue* uses this frame for input. If the device was opened in DEV_OUTPUT mode, *Dxx_issue* processes the data in the frame, then outputs it. In either mode, *Dxx_issue* ensures that the device has been started and returns an error code indicating success (SYS_OK) or failure.

*Dxx_issue* does not block. In output mode it processes the buffer and places it in a queue to be rendered. In input mode, it places a buffer in a queue to be filled with data, then returns.

*Dxx_issue* is used in conjunction with *Dxx_reclaim* to operate a stream. The *Dxx_issue* call sends a buffer to a stream, and the *Dxx_reclaim* retrieves a buffer from a stream. *Dxx_issue* performs processing for output streams, and provides empty frames for input streams. The *Dxx_reclaim* recovers empty frames in output streams, retrieves full frames, and performs processing for input streams.

*SIO_issue* calls *Dxx_issue* after placing a new input frame on the device->todevice. If *Dxx_issue* fails, it should return an error code. Before attempting further I/O through the device, the device should be idled, and all pending buffers should be flushed if the device was opened for DEV_OUTPUT.

In a stacking device, *Dxx_issue* must preserve all information in the DEV_Frame object except link and misc. On a device opened for DEV_INPUT, *Dxx_issue* should preserve the size and the arg fields. On a device opened for DEV_OUTPUT, *Dxx_issue* should preserve the buffer data (transformed as necessary), the size (adjusted as appropriate by the transform) and the arg field. The DEV_Frame objects themselves do not need to be preserved, only the information they contain.

*Dxx_issue* must preserve and maintain buffers sent to the device so they can be returned in the order they were received, by a call to *Dxx_reclaim*.

**Constraints and Calling Context**

- device must be bound to a device by a prior call to *Dxx_open*.

**See Also**

- *Dxx_reclaim*
- *SIO_issue*
**Dxx_open**  
*Open device*

**Important:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer’s Guide* (SPRU616).

---

## C Interface

**Syntax**

```c
status = Dxx_open(device, name);
```

**Parameters**

- `DEV_Handle device; /* driver handle */`
- `String name; /* device name */`

**Return Value**

- `Int status; /* result of operation */`

**Description**

`Dxx_open` is called by `SIO_create` to open a device. `Dxx_open` opens a device and returns an error code indicating success (SYS_OK) or failure.

The device parameter points to a `DEV_Obj` whose fields have been initialized by the calling function (that is, `SIO_create`). These fields can be referenced by `Dxx_open` to initialize various device parameters. `Dxx_open` is often used to attach a device-specific object to `device->object`. This object typically contains driver-specific fields that can be referenced in subsequent `Dxx` driver calls.

`name` is the string remaining after the device name has been matched by `SIO_create` using `DEV_match`.

**See Also**

- `Dxx_close`
- `SIO_create`
**Dxx_ready**

*Check if device is ready for I/O*

**Important:** This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer’s Guide* (SPRU616).

### C Interface

**Syntax**

```c
status = Dxx_ready(device, sem);
```

**Parameters**

- `DEV_Handle device; /* device handle */`
- `SEM_Handle sem; /* semaphore to post when ready */`

**Return Value**

- `Bool status; /* TRUE if device is ready */`

**Description**

`Dxx_ready` is called by `SIO_select` and `SIO_ready` to determine if the device is ready for an I/O operation. In this context, ready means a call that retrieves a buffer from a device does not block. If a frame exists, `Dxx_ready` returns `TRUE`, indicating that the next `SIO_get`, `SIO_put`, or `SIO_reclaim` operation on the device does not cause the calling task to block. If there are no frames available, `Dxx_ready` returns `FALSE`. This informs the calling task that a call to `SIO_get`, `SIO_put`, or `SIO_reclaim` for that device would result in blocking.

`Dxx_ready` registers the device’s ready semaphore with the `SIO_select` semaphore `sem`. In cases where `SIO_select` calls `Dxx_ready` for each of several devices, each device registers its own ready semaphore with the unique `SIO_select` semaphore. The first device that becomes ready calls `SEM_post` on the semaphore.

`sio_select` calls `Dxx_ready` twice; the second time, `sem = NULL`. This results in each device’s ready semaphore being set to `NULL`. This information is needed by the `Dxx HWI` that normally calls `SEM_post` on the device’s ready semaphore when I/O is completed; if the device ready semaphore is `NULL`, the semaphore should not be posted.

`sio_ready` calls `Dxx_ready` with `sem = NULL`. This is equivalent to the second `Dxx_ready` call made by `SIO_select`, and the underlying device driver should just return `status` without registering a semaphore.

**See Also**

- `SIO_select`
Dxx_reclaim

Retrieve a buffer from a device

Important: This API will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the DSP/BIOS Driver Developer's Guide (SPRU616).

C Interface

Syntax

status = Dxx_reclaim(device);

Parameters

DEV_Handle device; /* device handle */

Return Value

Int status; /* result of operation */

Description

Dxx_reclaim is used to request a buffer back from a device. Dxx_reclaim does not return until a buffer is available for the client in the device->fromdevice queue. If the device was opened in DEV_INPUT mode then Dxx_reclaim blocks until an input frame has been filled with the number of MADUs requested, then processes the data in the frame and place it on the device->fromdevice queue. If the device was opened in DEV_OUTPUT mode, Dxx_reclaim blocks until an output frame has been emptied, then place the frame on the device->fromdevice queue. In either mode, Dxx_reclaim blocks until it has a frame to place on the device->fromdevice queue, or until the stream's timeout expires, and it returns an error code indicating success (SYS_OK) or failure.

If device->timeout is not equal to SYS_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

If device->timeout is SYS_FOREVER, the task remains suspended until a frame is available on the device's fromdevice queue. If timeout is 0, Dxx_reclaim returns immediately.

If timeout expires before a buffer is available on the device's fromdevice queue, Dxx_reclaim returns SYSETIMEOUT. Otherwise Dxx_reclaim returns SYS_OK for success, or an error code.

If Dxx_reclaim fails due to a time out or any other reason, it does not place a frame on the device->fromdevice queue.

Dxx_reclaim is used in conjunction with Dxx_issue to operate a stream. The Dxx_issue call sends a buffer to a stream, and the Dxx_reclaim retrieves a buffer from a stream. Dxx_issue performs processing for output streams, and provides empty frames for input streams. The Dxx_reclaim recovers empty frames in output streams, and retrieves full frames and performs processing for input streams.

SIO_reclaim calls Dxx_reclaim, then it gets the frame from the device->fromdevice queue.

In a stacking device, Dxx_reclaim must preserve all information in the DEV_Frame object except link and misc. On a device opened for DEV_INPUT, Dxx_reclaim should preserve the buffer data (transformed as necessary), the size (adjusted as appropriate by the transform), and the arg field. On a device opened for DEV_OUTPUT, Dxx_reclaim should preserve the size and the arg field. The DEV_Frame objects themselves do not need to be preserved, only the information they contain.
Dxx_reclaim must preserve buffers sent to the device. Dxx_reclaim should never return a buffer that was not received from the client through the Dxx_issue call. Dxx_reclaim always preserves the ordering of the buffers sent to the device, and returns with the oldest buffer that was issued to the device.

**Constraints and Calling Context**

- device must be bound to a device by a prior call to Dxx_open.

**See Also**

- Dxx_issue
- SIO_issue
- SIO_get
- SIO_put
**DGN Driver**

**Software generator driver**

**Important:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer’s Guide* (SPRU616).

**Description**

The DGN driver manages a class of software devices known as generators, which produce an input stream of data through successive application of some arithmetic function. DGN devices are used to generate sequences of constants, sine waves, random noise, or other streams of data defined by a user function. The number of active generator devices in the system is limited only by the availability of memory.

**Configuring a DGN Device**

To create a DGN device object in a configuration script, use the following syntax:

```javascript
var myDgn = bios.DGN.create("myDgn");
```

See the DGN Object Properties for the device you created.

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DGN Object Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

**Instance Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>device</td>
<td>EnumString</td>
<td>&quot;user&quot; (&quot;sine&quot;, &quot;random&quot;, &quot;constant&quot;, &quot;printHex&quot;, &quot;printInt&quot;)</td>
</tr>
<tr>
<td>useDefaultParam</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>deviceId</td>
<td>Arg</td>
<td>prog.extern(&quot;DGN_USER&quot;, &quot;asm&quot;)</td>
</tr>
<tr>
<td>constant</td>
<td>Numeric</td>
<td>1</td>
</tr>
<tr>
<td>seedValue</td>
<td>Int32</td>
<td>1</td>
</tr>
<tr>
<td>lowerLimit</td>
<td>Numeric</td>
<td>-32767</td>
</tr>
<tr>
<td>upperLimit</td>
<td>Numeric</td>
<td>32767</td>
</tr>
<tr>
<td>gain</td>
<td>Numeric</td>
<td>32767</td>
</tr>
<tr>
<td>frequency</td>
<td>Numeric</td>
<td>1</td>
</tr>
<tr>
<td>phase</td>
<td>Numeric</td>
<td>0</td>
</tr>
<tr>
<td>rate</td>
<td>Int32</td>
<td>256</td>
</tr>
<tr>
<td>fxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>arg</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
</tbody>
</table>
Data Streaming

The DGN driver places no inherent restrictions on the size or memory segment of the data buffers used when streaming from a generator device. Since generators are fabricated entirely in software and do not overlap I/O with computation, no more than one buffer is required to attain maximum performance.

Since DGN generates data “on demand,” tasks do not block when calling SIO_get, SIO_put, or SIO_reclaim on a DGN data stream. High-priority tasks must, therefore, be careful when using these streams since lower- or even equal-priority tasks do not get a chance to run until the high-priority task suspends execution for some other reason.

DGN Driver Properties

There are no global properties for the DGN driver manager.

DGN Object Properties

The following properties can be set for a DGN device on the DGN Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. To create a DGN device object in a script, use the following syntax:

```javascript
var myDgn = bios.DGN.create("myDgn");
```

The Tconf examples assume the myDgn object is created as shown.

- **comment**. Type a comment to identify this object.
  Tconf Name: comment Type: String
  Example: `myDgn.comment = "DGN device";`

- **Device category**. The device category—user, sine, random, constant, printHex, printInt—determines the type of data stream produced by the device. A sine, random, or constant device can be opened for input data streaming only. A printHex or printInt device can be opened for output data streaming only.
  - **user**. Uses custom function to produce/consume a data stream.
  - **sine**. Produce a stream of sine wave samples.
  - **random**. Produces a stream of random values.
  - **constant**. Produces a constant stream of data.
  - **printHex**. Writes the stream data buffers to the trace buffer in hexadecimal format.
  - **printInt**. Writes the stream data buffers to the trace buffer in integer format.

  Tconf Name: device Type: EnumString
  Options: "user", "sine", "random", "constant", "printHex", "printInt"
  Example: `myDgn.device = "user";`

- **Use default parameters**. Set this property to true if you want to use the default parameters for the Device category you selected.
  Tconf Name: useDefaultParam Type: Bool
  Example: `myDgn.useDefaultParam = false;`

- **Device ID**. This property is set automatically when you select a Device category.
  Tconf Name: deviceID Type: Arg
  Example: `myDgn.deviceId = prog.extern("DGN_USER", "asm");`
• **Constant value.** The constant value to be generated if the Device category is constant.
  
  Tconf Name: constant          Type: Numeric
  
  Example: myDgn.constant = 1;

• **Seed value.** The initial seed value used by an internal pseudo-random number generator if the Device category is random. Used to produce a uniformly distributed sequence of numbers ranging between Lower limit and Upper limit.
  
  Tconf Name: seedValue         Type: Int32
  
  Example: myDgn.seedValue = 1;

• **Lower limit.** The lowest value to be generated if the Device category is random.
  
  Tconf Name: lowerLimit        Type: Numeric
  
  Example: myDgn.lowerLimit = -32767;

• **Upper limit.** The highest value to be generated if the Device category is random.
  
  Tconf Name: upperLimit        Type: Numeric
  
  Example: myDgn.upperLimit = 32767;

• **Gain.** The amplitude scaling factor of the generated sine wave if the Device category is sine. This factor is applied to each data point. To improve performance, the sine wave magnitude (maximum and minimum) value is approximated to the nearest power of two. This is done by computing a shift value by which each entry in the table is right-shifted before being copied into the input buffer. For example, if you set the Gain to 100, the sine wave magnitude is 128, the nearest power of two.
  
  Tconf Name: gain              Type: Numeric
  
  Example: myDgn.gain = 32767;

• **Frequency.** The frequency of the generated sine wave (in cycles per second) if the Device category is sine. DGN uses a static (256 word) sine table to approximate a sine wave. Only frequencies that divide evenly into 256 can be represented exactly with DGN. A “step” value is computed at open time for stepping through this table:

  \[
  \text{step} = \left(256 \times \frac{\text{Frequency}}{\text{Rate}}\right)
  \]

  Tconf Name: frequency         Type: Numeric
  
  Example: myDgn.frequency = 1;

• **Phase.** The phase of the generated sine wave (in radians) if the Device category is sine.
  
  Tconf Name: phase             Type: Numeric
  
  Example: myDgn.phase = 0;

• **Sample rate.** The sampling rate of the generated sine wave (in sample points per second) if the Device category is sine.
  
  Tconf Name: rate              Type: Int32
  
  Example: myDgn.rate = 256;

• **User function.** If the Device category is user, specifies the function to be used to compute the successive values of the data sequence in an input device, or to be used to process the data stream, in an output device. If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.
  
  Tconf Name: fxn               Type: Extern
  
  Example: myDgn.fxn = prog.extern("usrFxn");
• **User function argument.** An argument to pass to the User function.

A user function must have the following form:

```
fxn(Arg arg, Ptr buf, Uns nmadus)
```

where `buf` contains the values generated or to be processed. `buf` and `nmadus` correspond to the buffer address and buffer size (in MADUs), respectively, for an SIO_get operation.

- **Tconf Name:** `arg`  
- **Type:** `Arg`  

**Example:**

```
myDgn.arg = prog.extern("myArg");
```
DGS Driver

**Stackable gather/scatter driver**

---

**Important:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

---

**Description**

The DGS driver manages a class of stackable devices which compress or expand a data stream by applying a user-supplied function to each input or output buffer. This driver might be used to pack data buffers before writing them to a disk file or to unpack these same buffers when reading from a disk file. All (un)packing must be completed on frame boundaries as this driver (for efficiency) does not maintain remainders across I/O operations.

On opening a DGS device by name, DGS uses the unmatched portion of the string to recursively open an underlying device.

This driver requires a transform function and a packing/unpacking ratio which are used when packing/unpacking buffers to/from the underlying device.

**Configuring a DGS Device**

To create a DGS device object in a configuration script, use the following syntax:

```javascript
var myDgs = bios.UDEV.create("myDgs");
```

Modify the myDgs properties as follows.

- **init function.** Type 0 (zero).
- **function table ptr.** Type _DGS_FXNS
- **function table type.** DEV_Fxns
- **device id.** Type 0 (zero).
- **device params ptr.** Type 0 (zero) to use the default parameters. To use different values, you must declare a DGS_Params structure (as described after this list) containing the values to use for the parameters.

**DGS_Params** is defined in dgs.h as follows:

```c
/* ======== DGS_Params ======== */
typedef struct DGS_Params {      /* device parameters */
  Fxn   createFxn;
  Fxn   deleteFxn;
  Fxn   transFxn;
  Arg   arg;
  Int   num;
  Int   den;
} DGS_Params;
```
The device parameters are:

- **create function.** Optional, default is NULL. Specifies a function that is called to create and/or initialize a transform specific object. If non-NULL, the create function is called in DGS_open upon creating the stream with argument as its only parameter. The return value of the create function is passed to the transform function.

- **delete function.** Optional, default is NULL. Specifies a function to be called when the device is closed. It should be used to free the object created by the create function.

- **transform function.** Required, default is localcopy. Specifies the transform function that is called before calling the underlying device's output function in output mode and after calling the underlying device's input function in input mode. Your transform function should have the following interface:

  \[
  \text{dstsize} = \text{myTrans(} \text{Arg arg, Void *src, Void *dst, Int srcsize)}
  \]

  where arg is an optional argument (either argument or created by the create function), and *src and *dst specify the source and destination buffers, respectively. srcsize specifies the size of the source buffer and dstsize specifies the size of the resulting transformed buffer (srcsize * numerator/denominator).

- **arg.** Optional argument, default is 0. If the create function is non-NULL, the arg parameter is passed to the create function and the create function's return value is passed as a parameter to the transform function; otherwise, argument is passed to the transform function.

- **num** and **den** (numerator and denominator). Required, default is 1 for both parameters. These parameters specify the size of the transformed buffer. For example, a transformation that compresses two 32-bit words into a single 32-bit word would have numerator = 1 and denominator = 2 since the buffer resulting from the transformation is 1/2 the size of the original buffer.

**Transform Functions**

The following transform functions are already provided with the DGS driver:

- **u32tou8/u8tou32.** These functions provide conversion to/from packed unsigned 8-bit integers to unsigned 32-bit integers. The buffer must contain a multiple of 4 number of 32-bit/8-bit unsigned values.

- **u16tou32/u32tou16.** These functions provide conversion to/from packed unsigned 16-bit integers to unsigned 32-bit integers. The buffer must contain an even number of 16-bit/32-bit unsigned values.

- **i16toi32/i32toi16.** These functions provide conversion to/from packed signed 16-bit integers to signed 32-bit integers. The buffer must contain an even number of 16-bit/32-bit integers.

- **u8toi16/i16tou8.** These functions provide conversion to/from a packed 8-bit format (two 8-bit words in one 16-bit word) to a one word per 16 bit format.

- **i16tof32/f32toi16.** These functions provide conversion to/from packed signed 16-bit integers to 32-bit floating point values. The buffer must contain an even number of 16-bit integers/32-bit floats.

- **localcopy.** This function simply passes the data to the underlying device without packing or compressing it.

**Data Streaming**

DGS devices can be opened for input or output. DGS_open allocates buffers for use by the underlying device. For input devices, the size of these buffers is (bufsize * numerator) / denominator. For output devices, the size of these buffers is (bufsize * denominator) / numerator. Data is transformed into or out of these buffers before or after calling the underlying device's output or input functions respectively.
You can use the same stacking device in more than one stream, provided that the terminating device underneath it is not the same. For example, if u32tou8 is a DGS device, you can create two streams dynamically as follows:

```c
stream = SIO_create("/u32tou8/codec", SIO_INPUT, 128, NULL);
...
stream = SIO_create("/u32tou8/port", SIO_INPUT, 128, NULL);
```

You can also create the streams with Tconf. To do that, add two new SIO objects. Enter /codec (or any other configured terminal device) as the Device Control String for the first stream. Then select the DGS device configured to use u32tou8 in the Device property. For the second stream, enter /port as the Device Control String. Then select the DGS device configured to use u32tou8 in the Device property.

**Example**

The following code example declares DGS_PRMS as a DGS_Params structure:

```c
#include <dgs.h>

DGS_Params DGS_PRMS {
    NULL,    /* optional create function */
    NULL,    /* optional delete function */
    u32tou8, /* required transform function */
    0,       /* optional argument */
    4,       /* numerator */
    1        /* denominator */
}
```

By typing _DGS_PRMS for the Parameters property of a device, the values above are used as the parameters for this device.

**See Also**

DTR Driver
DHL Driver

**Host link driver**

**Important:** This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the *DSP/BIOS Driver Developer's Guide* (SPRU616).

**Description**

The DHL driver manages data streaming between the host and the DSP. Each DHL device has an underlying HST object. The DHL device allows the target program to send and receive data from the host through an HST channel using the SIO streaming API rather than using pipes. The DHL driver copies data between the stream’s buffers and the frames of the pipe in the underlying HST object.

**Configuring a DHL Device**

To add a DHL device you must first create an HST object and make it available to the DHL driver. To do this, use the following syntax:

```javascript
var myHst = bios.HST.create("myHst");
myHst.availableForDHL = true;
```

Also be sure to set the mode property to "output" or "input" as needed by the DHL device. For example:

```javascript
myHst.mode = "output";
```

Once there are HST channels available for DHL, you can create a DHL device object in a configuration script using the following syntax:

```javascript
var myDhl = bios.DHL.create("myDhl");
```

Then, you can set this object’s properties to select which HST channel, of those available for DHL, is used by this DHL device. If you plan to use the DHL device for output to the host, be sure to select an HST channel whose mode is output. Otherwise, select an HST channel with input mode.

Note that once you have selected an HST channel to be used by a DHL device, that channel is now owned by the DHL device and is no longer available to other DHL channels.

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DHL Driver Properties and DHL Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

**Module Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

**Instance Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>hstChannel</td>
<td>Reference</td>
<td>prog.get(&quot;myHST&quot;)</td>
</tr>
<tr>
<td>mode</td>
<td>EnumString</td>
<td>&quot;output&quot; (&quot;input&quot;)</td>
</tr>
</tbody>
</table>
Data Streaming

DHL devices can be opened for input or output data streaming. A DHL device used by a stream created in output mode must be associated with an output HST channel. A DHL device used by a stream created in input mode must be associated with an input HST channel. If these conditions are not met, a SYS_EBADOBJ error is reported in the system log during startup when the BIOS_start routine calls the DHL_open function for the device.

To use a DHL device in a statically-created stream, set the deviceName property of the SIO object to match the name of the DHL device you configured.

```c
mySio.deviceName = prog.get("myDhl");
```

To use a DHL device in a stream created dynamically with SIO_create, use the DHL device name (as it appears in your Tconf script) preceded by "/" (forward slash) as the first parameter of SIO_create:

```c
stream = SIO_create("/dhl0", SIO_INPUT, 128, NULL);
```

To enable data streaming between the target and the host through streams that use DHL devices, you must bind and start the underlying HST channels of the DHL devices from the Host Channels Control in Code Composer Studio, just as you would with other HST objects.

DHL devices copy the data between the frames in the HST channel's pipe and the stream's buffers. In input mode, it is the size of the frame in the HST channel that drives the data transfer. In other words, when all the data in a frame has been transferred to stream buffers, the DHL device returns the current buffer to the stream's fromdevice queue, making it available to the application. (If the stream buffers can hold more data than the HST channel frames, the stream buffers always come back partially full.) In output mode it is the opposite: the size of the buffers in the stream drives the data transfer so that when all the data in a buffer has been transferred to HST channel frames, the DHL device returns the current frame to the channel's pipe. In this situation, if the HST channel's frames can hold more data than the stream's buffers, the frames always return to the HST pipe partially full.

The maximum performance in a DHL device is obtained when you configure the frame size of its HST channel to match the buffer size of the stream that uses the device. The second best alternative is to configure the stream buffer (or HST frame) size to be larger than, and a multiple of, the size of the HST frame (or stream buffer) size for input (or output) devices. Other configuration settings also work since DHL does not impose restrictions on the size of the HST frames or the stream buffers, but performance is reduced.

Constraints

- HST channels used by DHL devices are not available for use with PIP APIs.
- Multiple streams cannot use the same DHL device. If more than one stream attempts to use the same DHL device, a SYS_EBUSY error is reported in the system LOG during startup when the BIOS_start routing calls the DHL_open function for the device.

DHL Driver Properties

The following global property can be set for the DHL - Host Link Driver on the DHL Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script:
• **Object memory.** Enter the memory segment from which to allocate DHL objects. Note that this does not affect the memory segments from where the underlying HST object or its frames are allocated. The memory segment for HST objects and their frames can be set using HST Manager Properties and HST Object Properties.

  Tconf Name: OBJMEMSEG Type: Reference
  Example: DHL.OBJMEMSEG = prog.get("myMEM");

**DHL Object Properties**

The following properties can be set for a DHL device using the DHL Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. To create a DHL device object in a configuration script, use the following syntax:

```javascript
var myDhl = bios.DHL.create("myDhl");
```

The Tconf examples assume the myDhl object has been created as shown.

• **comment.** Type a comment to identify this object.

  Tconf Name: comment Type: String
  Example: myDhl.comment = "DHL device";

• **Underlying HST Channel.** Select the underlying HST channel from the drop-down list. The "Make this channel available for a new DHL device" property in the HST Object Properties must be set to true for that HST object to be known here.

  Tconf Name: hstChannel Type: Reference
  Example: myDhl.hstChannel = prog.get("myHST");

• **Mode.** This informational property shows the mode (input or output) of the underlying HST channel. This becomes the mode of the DHL device.

  Tconf Name: mode Type: EnumString
  Options: "input", "output"
  Example: myDhl.mode = "output";
DIO Adapter  

**SIO Mini-driver adapter**

**Description**

The DIO adapter allows GIO-compliant mini-drivers to be used through SIO module functions. Such mini-drivers are described in the *DSP/BIOS Device Driver Developer’s Guide* (SPRU616).

**Configuring a DIO Device**

To create a DIO device object in a configuration script, first use the following syntax:

```
var myUdev = bios.UDEV.create("myUdev");
```

Set the DEV Object Properties for the device as follows.

- **init function.** Type 0 (zero).
- **function table ptr.** Type _DIO_FXNS
- **function table type.** IOM_Fxns
- **device id.** Type 0 (zero).
- **device params ptr.** Type 0 (zero).

Once there is a UDEV object with the IOM_Fxns function table type in the configuration, you can create a DIO object with the following syntax and then set properties for the object:

```
var myDio = bios.Dio.create("myDio");
```

**DIO Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DIO Driver Properties and DIO Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

**Module Configuration Parameters**

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<tr>
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</tr>
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<tbody>
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<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>STATICCREATE</td>
<td>Bool</td>
<td>false</td>
</tr>
</tbody>
</table>

**Instance Configuration Parameters**

<table>
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<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>useCallBackFxn</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>deviceName</td>
<td>Reference</td>
<td>prog.get(&quot;UDEV0&quot;)</td>
</tr>
<tr>
<td>chanParams</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
</tbody>
</table>
Description

The mini-drivers described in the *DSP/BIOS Device Driver Developer’s Guide* (SPRU616) are intended for use with the GIO module. However, the DIO driver allows them to be used with the SIO module instead of the GIO module.

The following figure summarizes how modules are related in an application that uses the DIO driver and a mini-driver:

![Diagram of module relationships]

**DIO Driver Properties**

The following global properties can be set for the DIO - Class Driver on the DIO Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object memory.** Enter the memory segment from which to allocate DIO objects.
  
  Tconf Name: OBJMEMSEG  
  Type: Reference  
  Example: bios.DIO.OBJMEMSEG = prog.get("myMEM");

- **Create All DIO Objects Statically.** Set this property to true if you want DIO objects to be created completely statically. If this property is false (the default), MEM_calloc is used internally to allocate space for DIO objects. If this property is true, you must create all SIO and DIO objects using the DSP/BIOS Configuration Tool or Tconf. Any calls to SIO_create fail. Setting this property to true reduces the application’s code size (so long as the application does not call MEM_alloc or its related functions elsewhere).
  
  Tconf Name: STATICCREATE  
  Type: Bool  
  Example: bios.DIO.STATICCREATE = false;
DIO Object Properties

The following properties can be set for a DIO device using the DIO Object Properties dialog in the DSP/BiOS Configuration Tool or in a Tconf script. To create a DIO device object in a configuration script, use the following syntax:

```javascript
var myDio = bios.DIO.create("myDio");
```

The Tconf examples assume the myDio object has been created as shown.

- **comment.** Type a comment to identify this object.
  Tconf Name: comment Type: String
  Example: `myDio.comment = "DIO device";`

- **use callback version of DIO function table.** Set this property to true if you want to use DIO with a callback function. Typically, the callback function is SWI_andnHook or a similar function that posts a SWI. Do not set this property to true if you want to use DIO with a TSK thread.
  Tconf Name: useCallBackFxn Type: Bool
  Example: `myDio.useCallBackFxn = false;`

- **fxnsTable.** This informational property shows the DIO function table used as a result of the settings in the "use callback version of DIO function table" and "Create ALL DIO Objects Statically" properties. The four possible setting combinations of these two properties correspond to the four function tables: DIO_tskDynamicFxns, DIO_tskStaticFxns, DIO_cbDynamicFxns, and DIO_cbStaticFxns.
  Tconf Name: N/A

- **device name.** Name of the device to use with this DIO object.
  Tconf Name: deviceName Type: Reference
  Example: `myDio.deviceName = prog.get("UDEV0");`

- **channel parameters.** This property allows you to pass an optional argument to the mini-driver create function. See the chanParams parameter of the GIO_create function.
  Tconf Name: chanParams Type: Arg
  Example: `myDio.chanParams = 0x00000000;`
DNL Driver

Null driver

Important: This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the DSP/BIOS Driver Developer’s Guide (SPRU616).

Description

The DNL driver manages “empty” devices which nondestructively produce or consume data streams. The number of empty devices in the system is limited only by the availability of memory; DNL instantiates a new object representing an empty device on opening, and frees this object when the device is closed.

The DNL driver does not define device ID values or a params structure which can be associated with the name used when opening an empty device. The driver also ignores any unmatched portion of the name declared in the system configuration file when opening a device.

Configuring a DNL Device

To create a DNL device object in a configuration script, use the following syntax:

```javascript
var myDnl = bios.UDEV.create("myDnl");
```

Set DEV Object Properties for the device you created as follows.

- **init function.** Type 0 (zero).
- **function table ptr.** Type _DNL_FXNS
- **function table type.** DEV_Fxns
- **device id.** Type 0 (zero).
- **device params ptr.** Type 0 (zero).

Data Streaming

DNL devices can be opened for input or output data streaming. Note that these devices return buffers of undefined data when used for input.

The DNL driver places no inherent restrictions on the size or memory segment of the data buffers used when streaming to or from an empty device. Since DNL devices are fabricated entirely in software and do not overlap I/O with computation, no more that one buffer is required to attain maximum performance.

Tasks do not block when using SIO_get, SIO_put, or SIO_reclaim with a DNL data stream.
DOV Driver

Stackable overlap driver

Important: This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the DSP/BIOS Driver Developer’s Guide (SPRU616).

Description

The DOV driver manages a class of stackable devices that generate an overlapped stream by retaining the last N minimum addressable data units (MADUs) of each buffer input from an underlying device. These N points become the first N points of the next input buffer. MADUs are equivalent to a 16-bit word in the data address space of the processor on C54x and C55x platforms.

Configuring a DOV Device

To create a DOV device object in a configuration script, use the following syntax:

```javascript
var myDov = bios.UDEV.create("myDov");
```

Set the DEV Object Properties for the device you created as follows.

- **init function.** Type 0 (zero).
- **function table ptr.** Type _DOV_FXNS
- **function table type.** DEV_Fxns
- **device id.** Type 0 (zero).
- **device params ptr.** Type 0 (zero) or the length of the overlap as described after this list.

If you enter 0 for the Device ID, you need to specify the length of the overlap when you create the stream with SIO_create by appending the length of the overlap to the device name. If you statically create the stream (with Tconf) instead, enter the length of the overlap in the Device Control String for the stream.

For example, if you statically create a device called overlap, and use 0 as its Device ID, you can open a stream with:

```c
stream = SIO_create("/overlap16/codec", SIO_INPUT, 128, NULL);
```

This causes SIO to open a stack of two devices. /overlap16 designates the device called overlap, and 16 tells the driver to use the last 16 MADUs of the previous frame as the first 16 MADUs of the next frame. codec specifies the name of the physical device which corresponds to the actual source for the data.

If, on the other hand you add a device called overlap and enter 16 as its Device ID, you can open the stream with:

```c
stream = SIO_create("/overlap/codec", SIO_INPUT, 128, NULL);
```

This causes the SIO Module to open a stack of two devices. /overlap designates the device called overlap, which you have configured to use the last 16 MADUs of the previous frame as the first 16 MADUs of the next frame. As in the previous example, codec specifies the name of the physical device that corresponds to the actual source for the data.

If you create the stream statically and enter 16 as the Device ID property, leave the Device Control String blank.
In addition to the configuration properties, you need to specify the value that DOV uses for the first overlap, as in the example:

```c
#include <dov.h>

static DOV_Config DOV_CONFIG = {
    (Char) 0
}
DOV_Config *DOV = &DOV_CONFIG;
```

If floating point 0.0 is required, the initial value should be set to (Char) 0.0.

**Data Streaming**

DOV devices can only be opened for input. The overlap size, specified in the string passed to SIO_create, must be greater than 0 and less than the size of the actual input buffers.

DOV does not support any control calls. All SIO_ctrl calls are passed to the underlying device.

You can use the same stacking device in more than one stream, provided that the terminating device underneath it is not the same. For example, if overlap is a DOV device with a Device ID of 0:

```c
stream = SIO_create("/overlap16/codec", SIO_INPUT, 128, NULL);
...  
stream = SIO_create("/overlap4/port", SIO_INPUT, 128, NULL);
```

or if overlap is a DOV device with positive Device ID:

```c
stream = SIO_create("/overlap/codec", SIO_INPUT, 128, NULL);
...  
stream = SIO_create("/overlap/port", SIO_INPUT, 128, NULL);
```

To create the same streams statically (rather than dynamically with SIO_create), add SIO objects with Tconf. Enter the string that identifies the terminating device preceded by "/" (forward slash) in the SIO object’s Device Control Strings (for example, /codec, /port). Then select the stacking device (overlap, overlapio) from the Device property.

**See Also**

DTR Driver  
DGS Driver
DPI Driver

Pipe driver

Important: This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the DSP/BIOS Driver Developer's Guide (SPRU616).

Description

The DPI driver is a software device used to stream data between tasks on a single processor. It provides a mechanism similar to that of UNIX named pipes; a reader and a writer task can open a named pipe device and stream data to/from the device. Thus, a pipe simply provides a mechanism by which two tasks can exchange data buffers.

Any stacking driver can be stacked on top of DPI. DPI can have only one reader and one writer task.

It is possible to delete one end of a pipe with SIO_delete and recreate that end with SIO_create without deleting the other end.

Configuring a DPI Device

To add a DPI device, right-click on the DPI - Pipe Driver folder, and select Insert DPI. From the Object menu, choose Rename and type a new name for the DPI device.

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the DPI Object Properties heading. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
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</tr>
<tr>
<td>allowVirtual</td>
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<td>false</td>
</tr>
</tbody>
</table>

Data Streaming

After adding a DPI device called pipe0 in the configuration, you can use it to establish a communication pipe between two tasks. You can do this dynamically, by calling in the function for one task:

```c
inStr = SIO_create("/pipe0", SIO_INPUT, bufsize, NULL);
...
SIO_get(inStr, bufp);
```

And in the function for the other task:

```c
outStr = SIO_create("/pipe0", SIO_OUTPUT, bufsize, NULL);
...
SIO_put(outStr, bufp, nmadus);
```
or by adding with Tconf two streams that use pipe0, one in output mode (outStream) and the other one in input mode(inStream). Then, from the reader task call:

```c
extern SIO_Obj inStream;
SIO_handle inStr = &inStream
...
SIO_get(inStr, bufp);
```

and from the writer task call:

```c
extern SIO_Obj outStream;
SIO_handle outStr = &outStream
...
SIO_put(outStr, bufp, nmadus);
```

The DPI driver places no inherent restrictions on the size or memory segments of the data buffers used when streaming to or from a pipe device, other than the usual requirement that all buffers be the same size.

Tasks block within DPI when using SIO_get, SIO_put, or SIO_reclaim if a buffer is not available. SIO_select can be used to guarantee that a call to one of these functions do not block. SIO_select can be called simultaneously by both the input and the output sides.

**DPI and the SIO_ISSUERECLAIM Streaming Model**

In the SIO_ISSUERECLAIM streaming model, an application reclaims buffers from a stream in the same order as they were previously issued. To preserve this mechanism of exchanging buffers with the stream, the default implementation of the DPI driver for ISSUERECLAIM copies the full buffers issued by the writer to the empty buffers issued by the reader.

A more efficient version of the driver that exchanges the buffers across both sides of the stream, rather than copying them, is also provided. To use this variant of the pipe driver for ISSUERECLAIM, edit the C source file dpi.c provided in the `<bios_install_dir>\packages\ti\bios\src\drivers` folder. Comment out the following line:

```c
#define COPYBUFS
```

Rebuild dpi.c. Link your application with this version of dpi.obj instead of the default one. To do this, add this version of dpi.obj to your project explicitly. This buffer exchange alters the way in which the streaming mechanism works. When using this version of the DPI driver, the writer reclaims first the buffers issued by the reader rather than its own issued buffers, and vice versa.

This version of the pipe driver is not suitable for applications in which buffers are broadcasted from a writer to several readers. In this situation it is necessary to preserve the ISSUERECLAIM model original mechanism, so that the buffers reclaimed on each side of a stream are the same that were issued on that side of the stream, and so that they are reclaimed in the same order that they were issued. Otherwise, the writer reclaims two or more different buffers from two or more readers, when the number of buffers it issued was only one.

**Converting a Single Processor Application to a Multiprocessor Application**

It is trivial to convert a single-processor application using tasks and pipes into a multiprocessor application using tasks and communication devices. If using SIO_create, the calls in the source code would change to use the names of the communication devices instead of pipes. (If the communication devices were given names like /pipe0, there would be no source change at all.) If the streams were
created statically with Tconf instead, you would need to change the Device property for the stream in the configuration template, save and rebuild your application for the new configuration. No source change would be necessary.

**Constraints**

Only one reader and one writer can open the same pipe.

**DPI Driver Properties**

There are no global properties for the DPI driver manager.

**DPI Object Properties**

The following property can be set for a DPI device in the DPI Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script. To create a DPI device object in a configuration script, use the following syntax:

```javascript
var myDpi = bios.DPI.create("myDpi");
```

The Tconf examples assume the myDpi object has been created as shown.

- **comment.** Type a comment to identify this object.
  
  Tconf Name: `comment` Type: `String`
  
  Example: `myDpi.comment = "DPI device";`

- **Allow virtual instances of this device.** Set this property to true if you want to be able to use SIO_create to dynamically create multiple streams to use this DPI device. DPI devices are used by SIO stream objects, which you create with Tconf or the SIO_create function.

  If this property is set to true, when you use SIO_create, you can create multiple streams that use the same DPI driver by appending numbers to the end of the name. For example, if the DPI object is named "pipe", you can call SIO_create to create pipe0, pipe1, and pipe2. Only integer numbers can be appended to the name.

  If this property is set to false, when you use SIO_create, the name of the SIO object must exactly match the name of the DPI object. As a result, only one open stream can use the DPI object. For example, if the DPI object is named "pipe", an attempt to use SIO_create to create pipe0 fails.

  Tconf Name: `allowVirtual` Type: `Bool`
  
  Example: `myDpi.allowVirtual = false;`
DST Driver

Stackable split driver

Important: This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the DSP/BIOS Driver Developer’s Guide (SPRU616).

Description

This stacking driver can be used to input or output buffers that are larger than the physical device can actually handle. For output, a single (large) buffer is split into multiple smaller buffers which are then sent to the underlying device. For input, multiple (small) input buffers are read from the device and copied into a single (large) buffer.

Configuring a DST Device

To create a DST device object in a configuration script, use the following syntax:

```javascript
var myDst = bios.UDEV.create("myDst");
```

Set the DEV Object Properties for the device you created as follows.

- **init function.** Type 0 (zero).
- **function table ptr.** Type _DST_FXNS
- **function table type.** DEV_Fxns
- **device id.** Type 0 (zero) or the number of small buffers corresponding to a large buffer as described after this list.
- **device params ptr.** Type 0 (zero).

If you enter 0 for the Device ID, you need to specify the number of small buffers corresponding to a large buffer when you create the stream with SIO_create, by appending it to the device name.

Example 1:

For example, if you create a user-defined device called split with Tconf, and enter 0 as its Device ID property, you can open a stream with:

```javascript
stream = SIO_create("/split4/codec", SIO_INPUT, 1024, NULL);
```

This causes SIO to open a stack of two devices: /split4 designates the device called split, and 4 tells the driver to read four 256-word buffers from the codec device and copy the data into 1024-word buffers for your application. codec specifies the name of the physical device which corresponds to the actual source for the data.

Alternatively, you can create the stream with Tconf (rather than by calling SIO_create at run-time). To do so, first create and configure two user-defined devices called split and codec. Then, create an SIO object. Type 4/codec as the Device Control String. Select split from the Device list.
Example 2:

Conversely, you can open an output stream that accepts 1024-word buffers, but breaks them into 256-word buffers before passing them to /codec, as follows:

```c
stream = SIO_create("/split4/codec", SIO_OUTPUT, 1024, NULL);
```

To create this output stream with Tconf, you would follow the steps for example 1, but would select output for the Mode property of the SIO object.

Example 3:

If, on the other hand, you add a device called split and enter 4 as its Device ID, you need to open the stream with:

```c
stream = SIO_create("/split/codec", SIO_INPUT, 1024, NULL);
```

This causes SIO to open a stack of two devices: /split designates the device called split, which you have configured to read four buffers from the codec device and copy the data into a larger buffer for your application. As in the previous example, codec specifies the name of the physical device that corresponds to the actual source for the data.

When you type 4 as the Device ID, you do not need to type 4 in the Device Control String for an SIO object created with Tconf. Type only/codec for the Device Control String.

Data Streaming

DST stacking devices can be opened for input or output data streaming.

Constraints

- The size of the application buffers must be an integer multiple of the size of the underlying buffers.
- This driver does not support any SIO_ctrl calls.
DTR Driver

Stackable streaming transformer driver

Important: This driver will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the IOM driver interface instead. See the DSP/BIOS Driver Developer’s Guide (SPRU616).

Description

The DTR driver manages a class of stackable devices known as transformers, which modify a data stream by applying a function to each point produced or consumed by an underlying device. The number of active transformer devices in the system is limited only by the availability of memory; DTR instantiates a new transformer on opening a device, and frees this object when the device is closed.

Buffers are read from the device and copied into a single (large) buffer.

Configuring a DTR Device

To create a DTR device object in a configuration script, use the following syntax:

```javascript
var myDtr = bios.UDEV.create("myDtr");
```

Set the DEV Object Properties for the device you created as follows.

- init function. Type 0 (zero).
- function table ptr. Type _DTR_FXNS
- function table type. DEV_Fxns
- device id. Type 0 (zero), _DTR_multiply, or _DTR_multiplyInt16.

If you type 0, you need to supply a user function in the device parameters. This function is called by the driver as follows to perform the transformation on the data stream:

```c
if (user.fxn != NULL) {
    (*user.fxn)(user.arg, buffer, size);
}
```

If you type _DTR_multiply, a built-in data scaling operation is performed on the data stream to multiply the contents of the buffer by the scale.value of the device parameters.

If you type _DTR_multiplyInt16, a built-in data scaling operation is performed on the data stream to multiply the contents of the buffer by the scale.value of the device parameters. The data stream is assumed to contain values of type Int16.

- device params ptr. Enter the name of a DTR_Params structure declared in your C application code. See the information following this list for details.
The DTR_Params structure is defined in dtr.h as follows:

```c
/* ======== DTR_Params ======== */
typedef struct {
    /* device parameters */
    struct {
        DTR_Scale value; /* scaling factor */
    } scale;
    struct {
        Arg arg;     /* user-defined argument */
        Fxn fxn;     /* user-defined function */
    } user;
} DTR_Params;
```

In the following code example, DTR_PRMS is declared as a DTR_Params structure:

```c
#include <dtr.h>
...
struct DTR_Params DTR_PRMS = {
    10.0,
    NULL,
    NULL
};
```

By typing _DTR_PRMS as the Parameters property of a DTR device, the values above are used as the parameters for this device.

You can also use the default values that the driver assigns to these parameters by entering _DTR_PARAMS for this property. The default values are:

```c
DTR_Params DTR_PARAMS = {
    { 1 },            /* scale.value */
    { (Arg)NULL,     /* user.arg */
        (Fxn)NULL },  /* user.fxns */
};
```

scale.value is a floating-point quantity multiplied with each data point in the input or output stream.

If you do not configure one of the built-in scaling functions for the device ID, use user.fxns and user.arg in the DTR_Params structure to define a transformation that is applied to inbound or outbound blocks of data, where buffer is the address of a data block containing size points; if the value of user.fxns is NULL, no transformation is performed at all.

```c
if (user.fxns != NULL) {
    (*user.fxns)(user.arg, buffer, size);
}
```

### Data Streaming

DTR transformer devices can be opened for input or output and use the same mode of I/O with the underlying streaming device. If a transformer is used as a data source, it inputs a buffer from the underlying streaming device and then transforms this data in place. If the transformer is used as a data sink, it outputs a given buffer to the underlying device after transforming this data in place.

The DTR driver places no inherent restrictions on the size or memory segment of the data buffers used when streaming to or from a transformer device; such restrictions, if any, would be imposed by the underlying streaming device.

Tasks do not block within DTR when using the SIO Module. A task can, of course, block as required by the underlying device.
2.6 GBL Module

This module is the global settings manager.

Functions

- **GBL_getClkin.** Gets configured value of board input clock in KHz.
- **GBL_getFrequency.** Gets current frequency of the CPU in KHz.
- **GBL_getProcId.** Gets configured processor ID used by MSGQ.
- **GBL_getVersion.** Gets DSP/BIOS version information.
- **GBL_setFrequency.** Set frequency of CPU in KHz for DSP/BIOS.
- **GBL_setProcId.** Set configured value of processor ID.

Configuration Properties

The following list shows the properties for this module that can be configured in a Tconf script, along with their types and default values. For details, see the GBL Module Properties heading. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>C55x Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>BOARDNAME</td>
<td>String</td>
<td>&quot;c55xx&quot;</td>
</tr>
<tr>
<td>PROCID</td>
<td>Int16</td>
<td>0</td>
</tr>
<tr>
<td>CLKIN</td>
<td>Uint32</td>
<td>20000 KHz</td>
</tr>
<tr>
<td>CLKOUT</td>
<td>Int16</td>
<td>'C5502, etc: 300 'C5510, etc: 140 'C5561: 60 'C59xx: 12 '1x10 (1510, 1610, and 1710): 12 OMAP 2320/2420: 12</td>
</tr>
<tr>
<td>SPECIFYRTSLIB</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>RTSLIB</td>
<td>String</td>
<td>==</td>
</tr>
<tr>
<td>MEMORYMODEL</td>
<td>EnumString</td>
<td>&quot;LARGE&quot; (&quot;HUGE&quot;)</td>
</tr>
<tr>
<td>CALLUSERINITFXN</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>USERINITFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>ENABLEINST</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>INSTRUMENTED</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>ENABLEALLTRC</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>DCRPOSTEDERITE</td>
<td>Bool</td>
<td>true (OMAP 2320/2420 only)</td>
</tr>
</tbody>
</table>

Description

This module does not manage any individual objects, but rather allows you to control global or system-wide settings used by other modules.
GBL Module Properties

The following Global Settings can be made:

- **Target Board Name.** The name of the board or board family.
  
  **Tconf Name:** BOARDNAME  
  **Type:** String  
  **Example:** bios.GBL.BOARDNAME = "c55xx";

- **Processor ID (PROCID).** ID used to communicate with other processors using the MSGQ Module. The procId is also defined in the MSGQ_TransportObj array that is part of the MSGQ_Config structure. This value can be obtained with GBL_getProcId and modified by GBL_setProcId (but only within the User Init Function).
  
  **Tconf Name:** PROCID  
  **Type:** Int16  
  **Example:** bios.GBL.PROCID = 0;

- **Board Clock In KHz (Informational Only).** Frequency of the input clock in KHz. You should set this property to match the actual board clock rate. This property does not change the rate of the board; it is informational only. The configured value can be obtained at run-time using the GBL_getClkin API. This property is used on the 'C5503 to compute the USB PLL settings. The default value is 20000 KHz.
  
  **Tconf Name:** CLKin  
  **Type:** Uint32  
  **Example:** bios.GBL.CLKin = 20000;

- **DSP Speed In MHz (CLKOUT).** This number, times 1000000, is the number of instructions the processor can execute in 1 second. You should set this property to match the actual rate. This property does not change the rate of the board. This value is used by the CLK manager to calculate register settings for the on-device timers.
  
  **Tconf Name:** CLKin  
  **Type:** Int16  
  **Example:** bios.GBL.CLKin = 100.0000;

- **Specify RTS Library.** Determines whether a user can specify the run-time support library to which the application is linked. The RTS library contains the printf, malloc, and other standard C library functions. For information about using this library, see "std.h and stdlib.h functions" on page 482. If you do not choose to specify a library, the default library for your platform is used.
  
  **Tconf Name:** SPECIFYRTSLIB  
  **Type:** Bool  
  **Example:** bios.GBL.SPECIFYRTSLIB = false;

- **Run-Time Support Library.** The name of the run-time support (RTS) library to which the application is linked. These libraries are located in the appropriate <ccs_install_dir>\ccsv5\tools\compiler\<target>\lib folder for your target. The library you select is used in the linker command file generated from the Tconf script when you build your application.
  
  **Tconf Name:** RTSLIB  
  **Type:** String  
  **Example:** bios.GBL.RTSLIB = "";

- **Modify CLKMD.** Set this property to true if you want to modify the value of the Clock Mode Register, which is used to program the PLL (phase-locked loop).
  
  **Tconf Name:** MODIFYCLKMD  
  **Type:** Bool  
  **Example:** bios.GBL.MODIFYCLKMD = false;

- **CLKMD - (PLL) Clock Mode Register.** The value of the Clock Mode Register.
  
  **Tconf Name:** CLKMd  
  **Type:** Numeric  
  **Example:** bios.GBL.CLKMD = 0x0000;
• **Memory Model.** This specifies the address reach within the 'C55x program. The options are large and huge. In the large and huge models, data addressing uses the full 23-bit range. Program space addressing always uses the full 24-bit range.

Both the large and huge models support the same address range. However, the huge model allows buffers to cross 64K page boundaries. For the large model, size_t is 16 bits (64K). For the huge model, size_t is 23 bits, which requires 32 bits of storage since the minimum storage unit is 16 bits.

Tconf Name: MEMORYMODEL Type: EnumString
Options: "LARGE", "HUGE"
Example: bios.GBL.MEMORYMODEL = "LARGE";

• **Call User Init Function.** Set this property to true if you want an initialization function to be called early during program initialization, after .cinit processing and before the main() function.

Tconf Name: CALLUSERINITFXN Type: Bool
Example: bios.GBL.CALLUSERINITFXN = false;

• **User Init Function.** Type the name of the initialization function. This function runs early in the initialization process and is intended to be used to perform hardware setup that needs to run before DSP/BIOS is initialized. The code in this function should not use any DSP/BIOS API calls, unless otherwise specified for that API, since a number of DSP/BIOS modules have not been initialized when this function runs. In contrast, the Initialization function that may be specified for HOOK Module objects runs later and is intended for use in setting up data structures used by other functions of the same HOOK object.

Tconf Name: USERINITFXN Type: Extern
Example: bios.GBL.USERINITFXN = prog.extern("FXN_F_nop");

• **Enable Real Time Analysis.** If this property is true, target-to-host communication is enabled by the addition of IDL objects to run the IDL_cpuLoad, LNK_dataPump, and RTA_dispatch functions. If this property is false, these IDL objects are removed and target-to-host communications are not supported. As a result, support for DSP/BIOS implicit instrumentation is removed.

Tconf Name: ENABLEINST Type: Bool
Example: bios.GBL.ENABLEINST = true;

• **Use Instrumented BIOS Library.** Specifies whether to link with the instrumented or non-instrumented version of the DSP/BIOS library. The non-instrumented versions are somewhat smaller but do not provide support for LOG, STS, and TRC instrumentation. The libraries are located in appropriate `<ccs_install_dir>\ccsv5\tools\compiler\<target>\lib` folder for your target. By default, the instrumented version of the library for your platform is used.

Tconf Name: INSTRUMENTED Type: Bool
Example: bios.GBL.INSTRUMENTED = true;

• **Enable All TRC Trace Event Classes.** Set this property to false if you want all types of tracing to be initially disabled when the program is loaded. If you disable tracing, you can still use the RTA Control Panel or the TRC_enable function to enable tracing at run-time.

Tconf Name: ENABLEALLTRC Type: Bool
Example: bios.GBL.ENABLEALLTRC = true;

• **DPORT write in posted mode.** D-port write operations are set to posted or non-posted mode via the data port configuration register DCR.WPE bit. The default for this parameter is true, and all D-port writes are posted. Set this parameter to false if you want the D-port operations to be non-posted. (OMAP 2320/2420 only)

Tconf Name: DCRPOSTEDERITE Type: Bool
Example: bios.GBL.DCRPOSTEDERITE = true;
GBL_getClkin

Get configured value of board input clock in KHz

C Interface

Syntax

clkin = GBL_getClkin(Void);

Parameters

Void

Return Value

Uint32 clkin; /* CLKIN frequency */

Reentrant

yes

Description

Returns the configured value of the board input clock (CLKIN) frequency in KHz. For example, on the 'C5509, CLKIN is used to compute the settings of the USB PLL.

See Also

CLK_countspms
CLK_getprd
**GBL_getFrequency**  
*Get current frequency of the CPU in KHz*

**C Interface**

Syntax

```c
frequency = GBL_getFrequency(Void);
```

Parameters

- Void

Return Value

- Uint32 frequency; /* CPU frequency in KHz */

**Reentrant**

yes

**Description**

Returns the current frequency of the DSP CPU in an integer number of KHz. This is the frequency set by GBL_setFrequency, which must also be an integer. The default value is the value of the CLKOUT property, which is configured as one of the GBL Module Properties.

**See Also**

- GBL_getClkin
- GBL_setFrequency
GBL_getProcId  Get configured value of processor ID

C Interface

Syntax
    procid = GBL_getProcId(Void);

Parameters
    Void

Return Value
    Uint16 procid; /* processor ID */

Reentrant
    yes

Description
    Returns the configured value of the processor ID (PROCID) for this processor. This numeric ID value is used by the MSGQ module when determining which processor to communicate with.

    The procId is also defined in the MSGQ_TransportObj array that is part of the MSGQ_Config structure. The same processor ID should be defined for this processor in both locations.

    During the User Init Function, the application may modify the statically configured processor ID by calling GBL_setProcId. In this case, the User Init Function may need to call GBL_getProcId first to get the statically configured processor ID.

See Also
    MSGQ Module: Static Configuration
    GBL_setProcId
**GBL_getVersion**  Get DSP/BIOS version information

**C Interface**

Syntax

```c
version = GBL_getVersion(Void);
```

Parameters

**Void**

Return Value

```
Uint16 version;    /* version data */
```

**Reentrant**

yes

**Description**

Returns DSP/BIOS kernel version information as a 4-digit hex number. For example: 0x5100. Note that the kernel version is different from the DSP/BIOS product version.

When comparing versions, compare the highest digits that are different. The digits in the version information are as follows:

<table>
<thead>
<tr>
<th>Bits</th>
<th>Compatibility with Older DSP/BIOS Versions</th>
</tr>
</thead>
<tbody>
<tr>
<td>12-15 (first hex digit)</td>
<td>Not compatible. Changes to application C, assembly, or configuration (Tconf) code may be required. For example, moving from 0x5100 to 0x6100 may require code changes.</td>
</tr>
<tr>
<td>8-11 (second hex digit)</td>
<td>No code changes required but you should recompile. For example, moving from 0x5100 to 0x5200 requires recompilation.</td>
</tr>
<tr>
<td>0-7 (third and fourth hex digits)</td>
<td>No code changes or recompile required. You should re-link if either of these digits are different. For example, moving from 0x5100 to 0x5102 requires re-linking.</td>
</tr>
</tbody>
</table>

The version returned by GBL_getVersion matches the version in the DSP/BIOS header files. (For example, tsk.h.) If the header file version is as follows, GBL_getVersion returns 0x5001. If there are three items, the last item uses two digits (for example, 01) in the returned hex number.

* @(#) DSP/BIOS_Kernel 5,0,1 05-30-2004 (cuda-106)
**GBL_setFrequency**  Set frequency of the CPU in KHz

**C Interface**

Syntax

```c
GBL_setFrequency( frequency );
```

Parameters

- **frequency**: Uint32 /* CPU frequency in KHz */

Return Value

- Void

Reentrant

- yes

Description

This function sets the value of the CPU frequency known to DSP/BIOS.

Note that GBL_setFrequency does not affect the PLL, and therefore has no effect on the actual frequency at which the DSP is running. It is used only to make DSP/BIOS aware of the DSP frequency you are using.

If you call GBL_setFrequency to update the CPU frequency known to DSP/BIOS, you should follow the sequence shown in the CLK_reconfig topic to reconfigure the timer.

The frequency must be an integer number of KHz.

If you enable the PWRM module, do not call GBL_setFrequency. When you use frequency scaling, the PWRM module internally calls this API to update the value known to DSP/BIOS.

**Constraints and Calling Context**

- If you change the frequency known to DSP/BIOS, you should also reconfigure the timer (with CLK_reconfig) so that the actual frequency is the same as the frequency known to DSP/BIOS.
- Do not call this function if you use the PWRM module.

See Also

- CLK_reconfig
- GBL_getClkin
- GBL_getFrequency
- PWRM_changeSetpoint
**GBL_setProcId**  
*Set configured value of processor ID*

**C Interface**

**Syntax**

GBL_setProcId( procId );

**Parameters**

- Uint16 procId; /* processor ID */

**Return Value**

Void

**Reentrant**

no

**Description**

Sets the processor ID (PROCID) for this processor. This numeric ID value is used by the MSGQ module to determine which processor to communicate with.

The procId is also defined in the MSGQ_TransportObj array that is part of the MSGQ_Config structure.

This function can only be called in the User Init Function configured as part of the GBL Module Properties. That is, this function may only be called at the beginning of DSP/BIOS initialization.

The application may determine the true processor ID for the device during the User Init Function and call GBL_setProcId with the correct processor ID. This is useful in applications that run a single binary image on multiple DSP processors.

How the application determines the correct processor ID is application- or board-specific. For example, you might use GPIO. You can call GBL_getProcId from the User Init Function to get the statically configured processor ID.

**Constraints and Calling Context**

- This function can only be called in the User Init Function configured as part of the GBL Module Properties.

**See Also**

- MSGQ Manager Properties
- GBL_getProcId
2.7 GIO Module

The GIO module is the Input/Output Module used with IOM mini-drivers as described in DSP/BIOS Device Driver Developer's Guide (SPRU616).

Functions

• GIO_abort. Abort all pending input and output.
• GIO_control. Device specific control call.
• GIO_create. Allocate and initialize a GIO object.
• GIO_delete. Delete underlying mini-drivers and free up the GIO object and any associated IOM packet structures.
• GIO_flush. Drain output buffers and discard any pending input.
• GIO_new. Initialize a GIO object using pre-allocated memory.
• GIO_read. Synchronous read command.
• GIO_submit. Submits a packet to the mini-driver.
• GIO_write. Synchronous write command.

Constants, Types, and Structures

/* Modes for GIO_create */
#define IOM_INPUT 0x0001
#define IOM_OUTPUT 0x0002
#define IOM_INOUT (IOM_INPUT | IOM_OUTPUT)

/* IOM Status and Error Codes */
#define IOM_COMPLETED SYS_OK /* I/O successful */
#define IOM_PENDING 1 /* I/O queued and pending */
#define IOM_FLUSHED 2 /* I/O request flushed */
#define IOM_ABORTED 3 /* I/O aborted */
#define IOM_EBADMODE -7 /* illegal device mode */
#define IOM_EOF -8 /* end-of-file encountered */
#define IOM_ENOTIMPL -9 /* operation not supported */
#define IOM_EBADARGS -10 /* illegal arguments used */
#define IOM_EALLOC -5 /* unable to alloc resource */
#define IOM_EABORT -6 /* I/O aborted uncompleted*/
#define IOM_ENOPACKETS -3 /* no packets available */
#define IOM_EFREE -4 /* unable to free resources */
#define IOM_EALLOC -5 /* unable to alloc resource */
#define IOM_EBADMODE -7 /* illegal device mode */
#define IOM_EFLUSHED -2 /* I/O flushed */
#define IOM_EUSER 128 /* 0-127 reserved for system */

/* Command codes for IOM_Packet */
#define IOM_READ   0
#define IOM_WRITE  1
#define IOM_ABORT  2
#define IOM_FLUSH  3
#define IOM_USER   128 /* 0-127 reserved for system */
/* Command codes reserved for control */
define IOM_CHAN_RESET 0 /* reset channel only */
define IOM_CHAN_TIMEDOUT 1
    /* channel timeout occurred */
define IOM_DEVICE_RESET 2 /* reset entire device */
define IOM_CNTL_USER 128
    /* 0-127 reserved for system */

/* Structure passed to GIO_create */
typedef struct GIO_Attrs {
    Int nPackets; /* number of asynch I/O packets */
    Uns timeout; /* for blocking (SYS_FOREVER) */
} GIO_Attrs;

/* Struct passed to GIO_submit for synchronous use*/
typedef struct GIO_AppCallback {
    GIO_TappCallback   fxn;
    Ptr                  arg;
} GIO_AppCallback;

typedef struct GIO_Obj {
    IOM_Fxns   *fxns; /* ptr to function table */
    Uns        mode; /* create mode */
    Uns        timeout; /* timeout for blocking */
    IOM_Packet syncPacket; /* for synchronous use */
    QUE_Obj    freeList; /* frames for asynch I/O */
    Ptr        syncObj; /* ptr to synchron. obj */
    Ptr        mdChan; /* ptr to channel obj */
} GIO_Obj, *GIO_Handle;

typedef struct IOM_Fxns {
    IOM_TmdBindDev   mdBindDev;
    IOM_TmdUnBindDev mdUnBindDev;
    IOM_TmdControlChan mdControlChan;
    IOM_TmdCreateChan mdCreateChan;
    IOM_TmdDeleteChan mdDeleteChan;
    IOM_TmdSubmitChan mdSubmitChan;
} IOM_Fxns;

typedef struct IOM_Packet { /* frame object */
    QUE_Elem   link; /* queue link */
    Ptr        addr; /* buffer address */
    size_t     size; /* buffer size */
    Arg        misc; /* reserved for driver */
    Arg        arg; /* user argument */
    Uns        cmd; /* mini-driver command */
    Int        status; /* status of command */
} IOM_Packet;

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the GIO Manager Properties heading. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.
The GIO module provides a standard interface to mini-drivers for devices such as UARTs, codecs, and video capture/display devices. The creation of such mini-drivers is not covered in this manual; it is described in *DSP/BIOS Device Driver Developer’s Guide* (SPRU616).

The GIO module is independent of the actual mini-driver being used. It allows the application to use a common interface for I/O requests. It also handles response synchronization. It is intended as common "glue" to bind applications to device drivers.

The following figure shows how modules are related in an application that uses the GIO module and an IOM mini-driver:

The GIO module is the basis of communication between applications and mini-drivers. The DEV module is responsible for maintaining the table of device drivers that are present in the system. The GIO module obtains device information by using functions such as DEV_match.

**GIO Manager Properties**

The following global properties can be set for the GIO module in the GIO Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Enable General Input/Output Manager.** Set this property to true to enable use of the GIO module. If your application does not use GIO, you should leave it disabled to prevent additional modules (such as SEM) from being linked into your application.
  
  Tconf Name: ENABLEGIO  
  Type: Bool  
  Example: bios.GIO.ENABLEGIO = false;
• **Create Function.** The function the GIO module should use to create a synchronization object. This function is typically SEM_create. If you use another function, that function should have a prototype that matches that of SEM_create: `Ptr CREATEFXN(Int count, Ptr attrs);

  Tconf Name: CREATEFXN Type: Extern
  Example: bios.GIO.CREATEFXN = prog.extern("SEM_create");

• **Delete Function.** The function the GIO module should use to delete a synchronization object. This function is typically SEM_delete. If you use another function, that function should have a prototype that matches that of SEM_delete: `Void DELETEFXN(Ptr semHandle);

  Tconf Name: DELETEFXN Type: Extern
  Example: bios.GIO.DELETEFXN = prog.extern("SEM_delete");

• **Pend Function.** The function the GIO module should use to pend on a synchronization object. This function is typically SEM_pend. If you use another function, that function should have a prototype that matches that of SEM_pend: `Bool PENDFXN(Ptr semHandle, Uns timeout);

  Tconf Name: PENDFXN Type: Extern
  Example: bios.GIO.PENDFXN = prog.extern("SEM_pend");

• **Post Function.** The function the GIO module should use to post a synchronization object. This function is typically SEM_post. If you use another function, that function should have a prototype that matches that of SEM_post: `Void POSTFXN(Ptr semHandle);

  Tconf Name: POSTFXN Type: Extern
  Example: bios.GIO.POSTFXN = prog.extern("SEM_post");

**GIO Object Properties**

GIO objects cannot be created statically. In order to create a GIO object, the application should call GIO_create or GIO_new.
**GIO_abort**  
Abort all pending input and output

C Interface

Syntax

```c
status = GIO_abort(gioChan);
```

Parameters

- **GIO_Handle gioChan;** /* handle to an instance of the device */

Return Value

- **Int status;** /* returns IOM_COMPLETED if successful */

Description

An application calls GIO_abort to abort all input and output from the device. When this call is made, all pending calls are completed with a status of GIO_ABORTED. An application uses this call to return the device to its initial state. Usually this is done in response to an unrecoverable error at the device level.

GIO_abort returns IOM_COMPLETED upon successfully aborting all input and output requests. If an error occurs, the device returns a negative value. For a list of error values, see “Constants, Types, and Structures” on page 128.

A call to GIO_abort results in a call to the mdSubmit function of the associated mini-driver. The IOM_ABORT command is passed to the mdSubmit function. The mdSubmit call is typically a blocking call, so calling GIO_abort can result in the thread blocking.

Constraints and Calling Context

- This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to GIO_create or GIO_new.
- GIO_abort cannot be called from a SWI or HWI unless the underlying mini-driver is a non-blocking driver and the GIO Manager properties are set to use non-blocking synchronization methods.

Example

```c
/* abort all I/O requests given to the device*/
gioStatus = GIO_abort(gioChan);
```
### GIO_control

**Device specific control call**

#### C Interface

**Syntax**

```c
status = GIO_control(gioChan, cmd, args);
```

**Parameters**

- `GIO_Handle gioChan; /* handle to an instance of the device */`
- `Int cmd; /* control functionality to perform */`
- `Ptr args; /* data structure to pass control information */`

**Return Value**

- `Int status; /* returns IOM_COMPLETED if successful */`

#### Description

An application calls `GIO_control` to configure or perform control functionality on the communication channel.

The `cmd` parameter may be one of the command code constants listed in “Constants, Types, and Structures” on page 128. A mini-driver may add command codes for additional functionality.

The `args` parameter points to a data structure defined by the device to allow control information to be passed between the device and the application. This structure can be generic across a domain or specific to a mini-driver. In some cases, this argument may point directly to a buffer holding control data. In other cases, there may be a level of indirection if the mini-driver expects a data structure to package many components of data required for the control operation. In the simple case where no data is required, this parameter may just be a predefined command value.

`GIO_control` returns `IOM_COMPLETED` upon success. If an error occurs, the device returns a negative value. For a list of error values, see “Constants, Types, and Structures” on page 128.

A call to `GIO_control` results in a call to the `mdControl` function of the associated mini-driver. The `mdControl` call is typically a blocking call, so calling `GIO_control` can result in blocking.

#### Constraints and Calling Context

- This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to `GIO_create` or `GIO_new`.
- `GIO_control` cannot be called from a SWI or HWI unless the underlying mini-driver is a non-blocking driver and the GIO Manager properties are set to use non-blocking synchronization methods.

#### Example

```c
/* Carry out control/configuration on the device*/
gioStatus = GIO_control(gioChan, XXX_RESET, &args);
```
allocate and initialize a Gio object

C Interface

Syntax

GIO_Handle gioChan = GIO_create(name, mode, *status, chanParams, *attrs);

Parameters

String name /* name of the device to open */
Int mode /* mode in which the device is to be opened */
Int *status /* address to place driver return status */
Ptr chanParams /* optional */
GIO_Attrs *attrs /* pointer to a GIO_Attrs structure */

Return Value

GIO_Handle gioChan; /* handle to an instance of the device */

Description

An application calls GIO_create to create a GIO_Obj object and open a communication channel. This function initializes the I/O channel and opens the lower-level device driver channel. The GIO_create call also creates the synchronization objects it uses and stores them in the GIO_Obj object.

The name argument is the name specified for the device when it was created in the configuration or at runtime.

The mode argument specifies the mode in which the device is to be opened. This may be IOM_INPUT, IOM_OUTPUT, or IOM_INOUT.

If the status returned by the device is non-NULL, a status value is placed at the address specified by the status parameter.

The chanParams parameter is a pointer that may be used to pass device or domain-specific arguments to the mini-driver. The contents at the specified address are interpreted by the mini-driver in a device-specific manner.

The attrs parameter is a pointer to a structure of type GIO_Attrs.

typedef struct GIO_Attrs {
  Int nPackets; /* number of async I/O packets */
  Uns timeout; /* for blocking calls (SYS_FOREVER) */
} GIO_Attrs;

If attrs is NULL, a default set of attributes is used. The default for nPackets is 2. The default for timeout is SYS_FOREVER.

The GIO_create call allocates a list of IOM_Packet items as specified by the nPackets member of the GIO_Attrs structure and stores them in the GIO_Obj object it creates.

GIO_create returns a handle to the GIO_Obj object created upon a successful open. The handle returned by this call should be used by the application in subsequent calls to GIO functions. This function returns a NULL handle if the device could not be opened. For example, if a device is opened in a mode not supported by the device, this call returns a NULL handle.

A call to GIO_create results in a call to the mdCreateChan function of the associated mini-driver.
Constraints and Calling Context

- A GIO stream can only be used by one task simultaneously. Catastrophic failure can result if more than one task calls GIO_read on the same input stream, or more than one task calls GIO_write on the same output stream.
- GIO_create cannot be called from the context of a SWI or HWI thread.
- This function can be called only after the device has been loaded and initialized.

Example

```c
/* Create a device instance */
gioAttrs = GIO_ATTRS;
gioChan = GIO_create("\Codec0", IOM_INPUT, NULL, NULL,
   &gioAttrs);
GIO_new
```
**GIO_delete**  
*Delete underlying mini-drivers and free GIO object and its structures*

## C Interface

**Syntax**

```c
status = GIO_delete(gioChan);
```

**Parameters**

- **GIO_Handle** gioChan; /* handle to device instance to be closed */

**Return Value**

- **Int** status; /* returns IOM_COMPLETED if successful */

## Description

An application calls GIO_delete to close a communication channel opened prior to this call with GIO_create. This function deallocates all memory allocated for this channel and closes the underlying device. All pending input and output are cancelled and the corresponding interrupts are disabled.

The gioChan parameter is the handle returned by GIO_create or GIO_new.

This function returns IOM_COMPLETED if the channel is successfully closed. If an error occurs, the device returns a negative value. For a list of error values, see “Constants, Types, and Structures” on page 128.

A call to GIO_delete results in a call to the mdDelete function of the associated mini-driver.

## Constraints and Calling Context

- This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to GIO_create or GIO_new.

## Example

```c
/* close the device instance */
GIO_delete(gioChan);
```
GIO_flush

Drain output buffers and discard any pending input

C Interface

Syntax

    status = GIO_flush(gioChan);

Parameters

GIO_Handle gioChan; /* handle to an instance of the device */

Return Value

Int status; /* returns IOM_COMPLETED if successful */

Description

An application calls GIO_flush to flush the input and output channels of the device. All input data is discarded; all pending output requests are completed. When this call is made, all pending input calls are completed with a status of IOM_FLUSHED, and all output calls are completed routinely.

The gioChan parameter is the handle returned by GIO_create or GIO_new.

This call returns IOM_COMPLETED upon successfully flushing all input and output. If an error occurs, the device returns a negative value. For a list of error values, see "Constants, Types, and Structures" on page 128.

A call to GIO_flush results in a call to the mdSubmit function of the associated mini-driver. The IOM_FLUSH command is passed to the mdSubmit function. The mdSubmit call is typically a blocking call, so calling GIO_flush can result in the thread blocking while waiting for output calls to be completed.

Constraints and Calling Context

• This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to GIO_create or GIO_new.
• GIO_flush cannot be called from a SWI or HWI unless the underlying mini-driver is a non-blocking driver and the GIO Manager properties are set to use non-blocking synchronization methods.

Example

    /* Flush all I/O given to the device*/
    GIO_flush(gioChan);
**GIO_new**  
*Initialize a GIO object with pre-allocated memory*

**C Interface**

**Syntax**
```
gioChan = GIO_new(gioChan, name, mode, *status, optArgs,  
packetBuf[], syncObject, *attrs);
```

**Parameters**
- `GIO_Handle gioChan /* Handle to GIO Obj */`
- `String name /* name of the device to open */`
- `Int mode /* mode in which the device is to be opened */`
- `Int *status /* address to place driver return status */`
- `Ptr optArgs /* optional args to mdCreateChan */`
- `IOM_packet packetBuf[] /* to be initialized to zero */`
- `Ptr syncObject /* sync Object */`
- `GIO_Attrs *attrs /* pointer to a GIO_Attrs structure */`

**Return Value**
```
GIO_Handle gioChan; /* handle to the initialized GIO object */
```

**Description**
An application calls GIO_new to initialize a GIO_Obj object and open a communication channel. This function initializes the I/O channel and opens the lower-level device driver channel. The GIO_new call does not allocate any memory. It requires pre-allocated memory.

The "gioChan" parameter is a handle to a structure of type GIO_Obj that your program has declared. GIO_new initializes this structure.

typedef struct GIO_Obj {
   IOM_Fxns   *fxns;      /* ptr to function table */
   Uns        mode;       /* create mode */
   Uns        timeout;    /* timeout for blocking */
   IOM_Packet syncPacket; /* for synchronous use */
   QUE_Obj    freeList;   /* frames for asynch I/O */
   Ptr        syncObj;    /* ptr to synchro. obj */
   Ptr        mdChan;     /* ptr to channel obj */
} GIO_Obj, *GIO_Handle;

The "name" parameter is the name previously specified for the device. It is used to find a matching name in the device table.

The "mode" parameter specifies the mode in which the device is to be opened. This may be IOM_INPUT, IOM_OUTPUT, or IOM_INOUT.

If the status returned by the device is non-NULL, a status value is placed at the address specified by the "status" parameter.

The "optArgs" parameter is a pointer that may be used to pass device or domain-specific arguments to the mini-driver. The contents at the specified address are interpreted by the mini-driver in a device-specific manner.

Use the "packetBuf[]" array to pass a list of IOM_Packet items. The number of items should match thenPackets member of the GIO_Attrs structure passed to the "attrs" parameter. GIO_new initializes these IOM_Packet items.
The "syncObject" parameter is usually a SEM handle.

The "attrs" parameter is a pointer to a structure of type GIO_Attrs.

```c
typedef struct GIO_Attrs {
    Int nPackets; /* number of asynch I/O packets */
    Uns timeout; /* for blocking calls (SYS_FOREVER) */
} GIO_Attrs;
```

If `attrs` is NULL, a default set of attributes is used. The default for `nPackets` is 2. The default for `timeout` is `SYS_FOREVER`. `GIO_new` initializes the packets, but does not allocate them.

`GIO_new` returns the non-NULL handle to the `GIO_Obj` when initialization is successful. The handle returned by this call should be used by the application in subsequent calls to `GIO` functions. Usually, this is the same handle passed to `GIO_new`. However, `GIO_new` returns a NULL handle if the device could not be initialized. For example, if a device is opened in a mode not supported by the device, this call returns a NULL handle.

A call to `GIO_new` results in a call to the `mdCreateChan` function of the associated mini-driver.

**Constraints and Calling Context**

- This function can be called only after the device has been loaded and initialized.

**Example**

```c
/* Initialize a device object */
output = GIO_new(&outObj, "printf", IOM_OUTPUT,
                 &status, NULL, outPacketBuf, outSem, &attrs);
GIO_create
```
C Interface

Syntax

status = GIO_read(gioChan, bufp, *pSize);

Parameters

GIO_Handle gioChan; /* handle to an instance of the device */
Ptr bufp /* pointer to data structure for buffer data */
size_t *pSize /* pointer to size of bufp structure */

Return Value

Int status; /* returns IOM_COMPLETED if successful */

Description

An application calls GIO_read to read a specified number of MADUs (minimum addressable data units) from the communication channel.

The gioChan parameter is the handle returned by GIO_create or GIO_new.

The bufp parameter points to a device-defined data structure for passing buffer data between the device and the application. This structure may be generic across a domain or specific to a single mini-driver. In some cases, this parameter may point directly to a buffer that holds the read data. In other cases, this parameter may point to a structure that packages buffer information, size, offset to be read from, and other device-dependent data. For example, for video capture devices this structure may contain pointers to RGB buffers, their sizes, video format, and a host of data required for reading a frame from a video capture device. Upon a successful read, this argument points to the returned data.

The pSize parameter points to the size of the buffer or data structure pointed to by the bufp parameter. When the function returns, this parameter points to the number of MADUs read from the device. This parameter is relevant only if the bufp parameter points to a raw data buffer. In cases where it points to a device-defined structure it is redundant—the size of the structure is known to the mini-driver and the application. At most, it can be used for error checking.

GIO_read returns IOM_COMPLETED upon successfully reading the requested number of MADUs from the device. If an error occurs, the device returns a negative value. For a list of error values, see "Constants, Types, and Structures" on page 128.

A call to GIO_read results in a call to the mdSubmit function of the associated mini-driver. The IOM_READ command is passed to the mdSubmit function. The mdSubmit call is typically a blocking call, so calling GIO_read can result in the thread blocking.

Constraints and Calling Context

- This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to GIO_create or GIO_new.
- GIO_read cannot be called from a SWI, HWI, or main() unless the underlying mini-driver is a non-blocking driver and the GIO Manager properties are set to use non-blocking synchronization methods.

Example

/* Read from the device */
size = sizeof(readStruct);
status = GIO_read(gioChan, &readStruct, &size);
Submit a GIO packet to the mini-driver

C Interface

Syntax

status = GIO_submit(gioChan, cmd, bufp, *pSize, *appCallback);

Parameters

- GIO_Handle gioChan; /* handle to an instance of the device */
- Uns cmd /* specified mini-driver command */
- Ptr bufp /* pointer to data structure for buffer data */
- size_t *pSize /* pointer to size of bufp structure */
- GIO_AppCallback *appCallback /* pointer to callback structure */

Return Value

- Int status; /* returns IOM_Completed if successful */

Description

GIO_submit is not typically called by applications. Instead, it is used internally and for user-defined extensions to the GIO module.

GIO_read and GIO_write are macros that call GIO_submit with appCallback set to NULL. This causes GIO to complete the I/O request synchronously using its internal synchronization object (by default, a semaphore). If appCallback is non-NULL, the specified callback is called without blocking. This API is provided to extend GIO functionality for use with SWI threads without changing the GIO implementation.

The gioChan parameter is the handle returned by GIO_create or GIO_new.

The cmd parameter is one of the command code constants listed in “Constants, Types, and Structures” on page 128. A mini-driver may add command codes for additional functionality.

The bufp parameter points to a device-defined data structure for passing buffer data between the device and the application. This structure may be generic across a domain or specific to a single mini-driver. In some cases, this parameter may point directly to a buffer that holds the data. In other cases, this parameter may point to a structure that packages buffer information, size, offset to be read from, and other device-dependent data.

The pSize parameter points to the size of the buffer or data structure pointed to by the bufp parameter. When the function returns, this parameter points to the number of MADUs transferred to or from the device. This parameter is relevant only if the bufp parameter points to a raw data buffer. In cases where it points to a device-defined structure it is redundant—the size of the structure is known to the mini-driver and the application. At most, it can be used for error checking.

The appCallback parameter points to either a callback structure that contains the callback function to be called when the request completes, or it points to NULL, which causes the call to be synchronous. When a queued request is completed, the callback routine (if specified) is invoked (i.e. blocking).

GIO_submit returns IOM_Completed upon successfully carrying out the requested functionality. If the request is queued, then a status of IOM_PENDING is returned. If an error occurs, the device returns a negative value. For a list of error values, see “Constants, Types, and Structures” on page 128.

A call to GIO_submit results in a call to the mdSubmit function of the associated mini-driver. The specified command is passed to the mdSubmit function.
**Constraints and Calling Context**

- This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to `GIO_create` or `GIO_new`.
- This function can be called within the program’s main() function only if the GIO channel is asynchronous (non-blocking).

**Example**

```c
/* write asynchronously to the device */
size = sizeof(userStruct);
status = GIO_submit(gioChan, IOM_WRITE, &userStruct,
                     &size, &callbackStruct);

/* write synchronously to the device */
size = sizeof(userStruct);
status = GIO_submit(gioChan, IOM_WRITE, &userStruct,
                     &size, NULL);
```
**GIO_write**

*Synchronous write command*

**C Interface**

**Syntax**

```c
status = GIO_write(gioChan, bufp, *pSize);
```

**Parameters**

- `GIO_Handle gioChan; /* handle to an instance of the device */`
- `Ptr bufp /* pointer to data structure for buffer data */`
- `size_t *pSize /* pointer to size of bufp structure */`

**Return Value**

```c
Int status; /* returns IOM_COMPLETED if successful */
```

**Description**

The application uses this function to write a specified number of MADUs to the communication channel.

The `gioChan` parameter is the handle returned by `GIO_create` or `GIO_new`.

The `bufp` parameter points to a device-defined data structure for passing buffer data between the device and the application. This structure may be generic across a domain or specific to a single mini-driver. In some cases, this parameter may point directly to a buffer that holds the write data. In other cases, this parameter may point to a structure that packages buffer information, size, offset to be written to, and other device-dependent data. For example, for video capture devices this structure may contain pointers to RGB buffers, their sizes, video format, and a host of data required for reading a frame from a video capture device. Upon a successful read, this argument points to the returned data.

The `pSize` parameter points to the size of the buffer or data structure pointed to by the `bufp` parameter.

When the function returns, this parameter points to the number of MADUs written to the device. This parameter is relevant only if the `bufp` parameter points to a raw data buffer. In cases where it points to a device-defined structure it is redundant—the size of the structure is known to the mini-driver and the application. At most, it can be used for error checking.

`GIO_write` returns `IOM_COMPLETED` upon successfully writing the requested number of MADUs to the device. If an error occurs, the device returns a negative value. For a list of error values, see “Constants, Types, and Structures” on page 128.

A call to `GIO_write` results in a call to the `mdSubmit` function of the associated mini-driver. The `IOM_WRITE` command is passed to the `mdSubmit` function. The `mdSubmit` call is typically a blocking call, so calling `GIO_write` can result in blocking.

**Constraints and Calling Context**

- This function can be called only after the device has been loaded and initialized. The handle supplied should have been obtained with a prior call to `GIO_create` or `GIO_new`.
- This function can be called within the program’s `main()` function only if the GIO channel is asynchronous (non-blocking).
- `GIO_write` cannot be called from a SWI or HWI unless the underlying mini-driver is a non-blocking driver and the GIO Manager properties are set to use non-blocking synchronization methods.

**Example**

```c
/* write synchronously to the device*/
size = sizeof(writeStruct);
status = GIO_write(gioChan, &writeStrct, &size);
```
2.8 HOOK Module

The HOOK module is the Hook Function manager.

Functions

- HOOK_getenv. Get environment pointer for a given HOOK and TSK combination.
- HOOK_setenv. Set environment pointer for a given HOOK and TSK combination.

Constants, Types, and Structures

define Int HOOK_Id; /* HOOK instance id */

define Void (*HOOK_InitFxn)(HOOK_Id id);
define Void (*HOOK_CreateFxn)(TSK_Handle task);
define Void (*HOOK_DeleteFxn)(TSK_Handle task);
define Void (*HOOK_ExitFxn)(Void);
define Void (*HOOK_ReadyFxn)(TSK_Handle task);
define Void (*HOOK_SwitchFxn)(TSK_Handle prev, TSK_Handle next);

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the HOOK Object Properties heading. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>initFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>createFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>deleteFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>exitFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>callSwitchFxn</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>switchFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>callReadyFxn</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>readyFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>order</td>
<td>Int16</td>
<td>2</td>
</tr>
</tbody>
</table>

Description

The HOOK module is an extension to the TSK function hooks defined in the TSK Manager Properties. It allows multiple sets of hook functions to be performed at key execution points. For example, an application that integrates third-party software may need to perform both its own hook functions and the hook functions required by the third-party software.

In addition, each HOOK object can maintain private data environments for each task for use by its hook functions.

The key execution points at which hook functions can be executed are during program initialization and at several TSK execution points.
The HOOK module manages objects that reference a set of hook functions. Each HOOK object is assigned a numeric identifier during DSP/BIOS initialization. If your program calls HOOK API functions, you must implement an initialization function for the HOOK instance that records the identifier in a variable of type HOOK_Id. DSP/BIOS passes the HOOK object’s ID to the initialization function as the lone parameter.

The following function, myInit, could be configured as the Initialization function for a HOOK object using Tconf.

```c
#include <hook.h>
HOOK_Id myId;

Void myInit(HOOK_Id id)
{
    myId = id;
}
```

The HOOK_setenv function allows you to associate an environment pointer to any data structure with a particular HOOK object and TSK object combination.

There is no limit to the number of HOOK objects that can be created. However, each object requires a small amount of memory in the .bss section to contain the object.

A HOOK object initially has all of its functions set to FXN_F_nop. You can set some hook functions and use this no-op function for the remaining events. Since the switch and ready events occur frequently during real-time processing, a separate property controls whether any function is called.

When you create a HOOK object, any TSK module hook functions you have specified are automatically placed in a HOOK object called HOOK_KNL. To set any properties of this object other than the Initialization function, use the TSK module. To set the Initialization function property of the HOOK_KNL object, use the HOOK module.

When an event occurs, all HOOK functions for that event are called in the order set by the order property in the configuration. When you select the HOOK manager in the DSP/BIOS Configuration Tool, you can change the execution order by dragging objects within the ordered list.

HOOK Manager Properties

There are no global properties for the HOOK manager. HOOK objects are placed in the C Variables Section (.bss).

HOOK Object Properties

The following properties can be set for a HOOK object in the DPI Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script. To create a HOOK object in a configuration script, use the following syntax:

```c
var myHook = bios.HOOK.create("myHook");
```

The Tconf examples that follow assume the object has been created as shown.

- **comment**. A comment to identify this HOOK object.
  - Tconf Name: comment Type: String
  - Example: myHook.comment = "HOOK funcs";

- **Initialization function**. The name of a function to call during program initialization. Such functions run during the BIOS_init portion of application startup, which runs before the program’s main() function. Initialization functions can call most functions that can be called from the main() function.
However, they should not call TSK module functions, because the TSK module is initialized after initialization functions run. In addition to code specific to the module hook, this function should be used to record the object’s ID, if it is needed in a subsequent hook function. This initialization function is intended for use in setting up data structures used by other functions of the same HOOK object. In contrast, the User Init Function property of the GBL Module Properties runs early in the initialization process and is intended to be used to perform hardware setup that needs to run before DSP/BIOS is initialized.

Tconf Name: initFxn Type: Extern
Example: myHook.initFxn = prog.extern("myInit");

- **Create function.** The name of a function to call when any task is created. This includes tasks that are created statically and those created dynamically using TSK_create. The TSK_create topic describes the prototype required for the Create function. If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.

  Tconf Name: createFxn Type: Extern
  Example: myHook.createFxn = prog.extern("myCreate");

- **Delete function.** The name of a function to call when any task is deleted at run-time with TSK_delete.

  Tconf Name: deleteFxn Type: Extern
  Example: myHook.deleteFxn = prog.extern("myDelete");

- **Exit function.** The name of a function to call when any task exits. The TSK_exit topic describes the Exit function.

  Tconf Name: exitFxn Type: Extern
  Example: myHook.exitFxn = prog.extern("myExit");

- **Call switch function.** Set this property to true if you want a function to be called when any task switch occurs.

  Tconf Name: callSwitchFxn Type: Bool
  Example: myHook.callSwitchFxn = false;

- **Switch function.** The name of a function to call when any task switch occurs. This function can give the application access to both the current and next task handles. The TSK Module topic describes the Switch function.

  Tconf Name: switchFxn Type: Extern
  Example: myHook.switchFxn = prog.extern("mySwitch");

- **Call ready function.** Set this property to true if you want a function to be called when any task becomes ready to run.

  Tconf Name: callReadyFxn Type: Bool
  Example: myHook.callReadyFxn = false;

- **Ready function.** The name of a function to call when any task becomes ready to run. The TSK Module topic describes the Ready function.

  Tconf Name: readyFxn Type: Extern
  Example: myHook.readyFxn = prog.extern("myReady");

- **order.** Set this property for all HOOK function objects match the order in which HOOK functions should be executed.

  Tconf Name: order Type: Int16
  Example: myHook.order = 2;
HOOK_getenv  
Get environment pointer for a given HOOK and TSK combination

C Interface

Syntax

```c
environ = HOOK_getenv(task, id);
```

Parameters

- `TSK_Handle task;` /* task object handle */
- `HOOK_Id id;` /* HOOK instance id */

Return Value

- `Ptr environ;` /* environment pointer */

Reentrant

- yes

Description

HOOK_getenv returns the environment pointer associated with the specified HOOK and TSK objects. The environment pointer, `environ`, references the data structure specified in a previous call to `HOOK_setenv`.

See Also

- HOOK_setenv
- TSK_getenv
**HOOK_setenv**

Set environment pointer for a given HOOK and TSK combination

**C Interface**

**Syntax**

```c
HOOK_setenv(task, id, environ);
```

**Parameters**

- `TSK_Handle task; /* task object handle */`
- `HOOK_Id id; /* HOOK instance id */`
- `Ptr environ; /* environment pointer */`

**Return Value**

```c
Void
```

**Reentrant**

```c
yes
```

**Description**

HOOK_setenv sets the environment pointer associated with the specified HOOK and TSK objects to environ. The environment pointer, environ, should reference an data structure to be used by the hook functions for a task or tasks.

Each HOOK object may have a separate environment pointer for each task. A HOOK object may also point to the same data structure for all tasks, depending on its data sharing needs.

The HOOK_getenv function can be used to get the environ pointer for a particular HOOK and TSK object combination.

**See Also**

- `HOOK_getenv`
- `TSK_setenv`
2.9 HST Module

**Important:** This module is being deprecated and will no longer be supported in the next major release of DSP/BIOS.

The HST module is the host channel manager.

**Functions**

- HST_getpipe. Get corresponding pipe object

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the HST Manager Properties and HST Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

**Module Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>HOSTLINKTYPE</td>
<td>EnumString</td>
<td>&quot;RTDX&quot; (&quot;NONE&quot;)</td>
</tr>
</tbody>
</table>

**Instance Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>mode</td>
<td>EnumString</td>
<td>&quot;output&quot; (&quot;input&quot;)</td>
</tr>
<tr>
<td>bufSeg</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>bufAlign</td>
<td>Int16</td>
<td>4</td>
</tr>
<tr>
<td>frameSize</td>
<td>Int16</td>
<td>128</td>
</tr>
<tr>
<td>numFrames</td>
<td>Int16</td>
<td>2</td>
</tr>
<tr>
<td>statistics</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>availableForDHL</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>notifyFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>arg0</td>
<td>Arg</td>
<td>3</td>
</tr>
</tbody>
</table>

**Description**

The HST module manages host channel objects, which allow an application to stream data between the target and the host. Host channels are statically configured for input or output. Input channels (also called the source) read data from the host to the target. Output channels (also called the sink) transfer data from the target to the host.

**Note:** HST channel names cannot begin with a leading underscore ( _ ).
Each host channel is internally implemented using a data pipe (PIP) object. To use a particular host channel, the program uses HST_getpipe to get the corresponding pipe object and then transfers data by calling the PIP_get and PIP_free operations (for input) or PIP_alloc and PIP_put operations (for output).

During early development, especially when testing SWI processing algorithms, programs can use host channels to input canned data sets and to output the results. Once the algorithm appears sound, you can replace these host channel objects with I/O drivers for production hardware built around DSP/BIOS pipe objects. By attaching host channels as probes to these pipes, you can selectively capture the I/O channels in real time for off-line and field-testing analysis.

The notify function is called in the context of the code that calls PIP_free or PIP_put. This function can be written in C or assembly. The code that calls PIP_free or PIP_put should preserve any necessary registers.

The other end of the host channel is managed by the LNK_dataPump IDL object. Thus, a channel can only be used when some CPU capacity is available for IDL thread execution.

HST Manager Properties

The following global properties can be set for the HST module in the HST Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment containing HST objects.
  
  Tconf Name: OBJMEMSEG Type: Reference
  
  Example: bios.HST.OBJMEMSEG = prog.get("myMEM");

- **Host Link Type.** The underlying physical link to be used for host-target data transfer. If None is selected, no instrumentation or host channel data is transferred between the target and host in real time. The Analysis Tool windows are updated only when the target is halted (for example, at a breakpoint). The program code size is smaller when the Host Link Type is set to None because RTDX code is not included in the program.

  Tconf Name: HOSTLINKTYPE Type: EnumString
  
  Options: "RTDX", "NONE"
  
  Example: bios.HST.HOSTLINKTYPE = "RTDX";

HST Object Properties

A host channel maintains a buffer partitioned into a fixed number of fixed length frames. All I/O operations on these channels deal with one frame at a time; although each frame has a fixed length, the application can put a variable amount of data in each frame.

The following properties can be set for a host file object in the HST Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script. To create an HST object in a configuration script, use the following syntax:

```plaintext
var myHst = bios.HST.create("myHst");
```

The Tconf examples that follow assume the object has been created as shown.

- **comment.** A comment to identify this HST object.

  Tconf Name: comment Type: String
  
  Example: myHst.comment = "my HST";
• **mode.** The type of channel: input or output. Input channels are used by the target to read data from the host; output channels are used by the target to transfer data from the target to the host.

  Tconf Name: mode
  Type: EnumString
  Options: "output", "input"
  Example: myHst.mode = "output";

• **bufseg.** The memory segment from which the buffer is allocated; all frames are allocated from a single contiguous buffer (of size framesize x numframes).

  Tconf Name: bufSeg
  Type: Reference
  Example: myHst.bufSeg = prog.get("myMEM");

• **bufalign.** The alignment (in words) of the buffer allocated within the specified memory segment.

  Tconf Name: bufAlign
  Type: Int16
  Options: must be >= 4 and a power of 2
  Example: myHst.bufAlign = 4;

• **framesize.** The length of each frame (in words)

  Tconf Name: frameSize
  Type: Int16
  Example: myHst.frameSize = 128;

• **numframes.** The number of frames

  Tconf Name: numFrames
  Type: Int16
  Example: myHst.numFrames = 2;

• **statistics.** Set this property to true if you want to monitor this channel with an STS object. You can display the STS object for this channel to see a count of the number of frames transferred with the Statistics View Analysis Tool.

  Tconf Name: statistics
  Type: Bool
  Example: myHst.statistics = false;

• **Make this channel available for a new DHL device.** Set this property to true if you want to use this HST object with a DHL device. DHL devices allow you to manage data I/O between the host and target using the SIO module, rather than the PIP module. See the DHL Driver topic for more details.

  Tconf Name: availableForDHL
  Type: Bool
  Example: myHst.availableForDHL = false;

• **notify.** The function to execute when a frame of data for an input channel (or free space for an output channel) is available. To avoid problems with recursion, this function should not directly call any of the PIP module functions for this HST object.

  Tconf Name: notifyFxn
  Type: Extern
  Example: myHst.notifyFxn = prog.extern("hstNotify");

• **arg0, arg1.** Two Arg type arguments passed to the notify function.

  Tconf Name: arg0
  Type: Arg
  Tconf Name: arg1
  Type: Arg
  Example: myHst.arg0 = 3;
HST_getpipe

Get corresponding pipe object

Important: This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS.

C Interface

Syntax

```
pipe = HST_getpipe(hst);
```

Parameters

<table>
<thead>
<tr>
<th>Parameter Type</th>
<th>Parameter Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>HST_Handle</td>
<td>hst</td>
<td>/* host object handle */</td>
</tr>
</tbody>
</table>

Return Value

<table>
<thead>
<tr>
<th>Parameter Type</th>
<th>Parameter Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>PIP_Handle</td>
<td>pip</td>
<td>/* pipe object handle */</td>
</tr>
</tbody>
</table>

Reentrant

yes

Description

HST_getpipe gets the address of the pipe object for the specified host channel object.

Example

```
Void copy(HST_Obj *input, HST_Obj *output)
{
    PIP_Obj *in, *out;
    Uns *src, *dst;
    Uns size;

    in = HST_getpipe(input);
    out = HST_getpipe(output);
    if (PIP_getReaderNumFrames == 0 || PIP_getWriterNumFrames == 0) {
        error;
    }

    /* get input data and allocate output frame */
    PIP_get(in);
    PIP_alloc(out);

    /* copy input data to output frame */
    src = PIP_getReaderAddr(in);
    dst = PIP_getWriterAddr(out);
    size = PIP_getReaderSize();
    out->writerSize = size;
    for (; size > 0; size--) {
        *dst++ = *src++;
    }

    /* output copied data and free input frame */
    PIP_put(out);
    PIP_free(in);
}
```

See Also

PIP_alloc
2.10 HWI Module

The HWI module is the hardware interrupt manager.

Functions

- HWI_disable. Disable hardware interrupts
- HWI_dispatchPlug. Plug the HWI dispatcher
- HWI_enable. Enable hardware interrupts
- HWI_enter. Hardware ISR prolog
- HWI_exit. Hardware ISR epilog
- HWI_isHWI. Check current thread calling context.
- HWI_restore. Restore hardware interrupt state

Constants, Types, and Structures

typedef struct HWI_Attrs {
    Uns ier0mask;    /* IER0 bitmask */
    Uns ier1mask;    /* IER1 bitmask */
    Arg arg;         /* fxn arg (default = 0) */
    LgUns mirmask;    /* OMAP 2320/2420 only */
    LgUns mir1mask;   /* OMAP 2320 only */
} HWI_Attrs;

HWI_Attrs HWI_ATTRS = {
    1,           /* IER0 mask (1 => self) */
    1,           /* IER1 mask (1 => self) */
    0            /* argument to ISR */
};

/* If ier0mask and ier1mask are both '1',
   mask to disable "self" is created. */

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the HWI Manager Properties and HWI Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>C55x Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>STACKMODE</td>
<td>EnumString</td>
<td>&quot;C54X_STK&quot; (&quot;USE_RETA&quot;, &quot;NO_RETA&quot;)</td>
</tr>
<tr>
<td>INTC_BASE</td>
<td>Numeric</td>
<td>0x7e4800 (OMAP 2320/2420 only)</td>
</tr>
</tbody>
</table>
Instance Configuration Parameters

HWI instances are provided as a default part of the configuration and cannot be created. In the items that follow, HWI_INT* may be any provided instance. Default values for many HWI properties are different for each instance.

<table>
<thead>
<tr>
<th>C55x Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>fxn</td>
<td>Extern</td>
<td>prog.extern(&quot;HWI_unused&quot;, &quot;asm&quot;)</td>
</tr>
<tr>
<td>monitor</td>
<td>EnumString</td>
<td>&quot;Nothing&quot; (&quot;Data Value&quot;, &quot;xsp&quot;, &quot;ac0g&quot;, &quot;ac0h&quot;, &quot;ac0f&quot;, &quot;ac1g&quot;, &quot;ac1h&quot;, &quot;ac1f&quot;, &quot;ac2g&quot;, &quot;ac2h&quot;, &quot;ac2f&quot;, &quot;ac3g&quot;, &quot;ac3h&quot;, &quot;ac3f&quot;, &quot;xar0&quot;, &quot;xar1&quot;, &quot;xar2&quot;, &quot;xar3&quot;, &quot;xar4&quot;, &quot;xar5&quot;, &quot;xar6&quot;, &quot;xar7&quot;, &quot;t0&quot;, &quot;t1&quot;, &quot;t2&quot;, &quot;t3&quot;, &quot;xsxp&quot;, &quot;tim&quot;, &quot;st0_55&quot;, &quot;st1_55&quot;, &quot;st2_55&quot;, &quot;st3_55&quot;, &quot;trn0&quot;, &quot;bk03&quot;, &quot;brc0&quot;, &quot;xdp&quot;, &quot;xcdp&quot;, &quot;dph&quot;, &quot;mdp05&quot;, &quot;mdp67&quot;, &quot;pdp&quot;, &quot;bk47&quot;, &quot;bkc&quot;, &quot;bsa01&quot;, &quot;bsa23&quot;, &quot;bsa45&quot;, &quot;bsa67&quot;, &quot;bsac&quot;, &quot;trn1&quot;, &quot;brc1&quot;, &quot;csr&quot;, &quot;rptc&quot;)</td>
</tr>
<tr>
<td>addr</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>dataType</td>
<td>EnumString</td>
<td>&quot;signed&quot; (&quot;unsigned&quot;)</td>
</tr>
<tr>
<td>operation</td>
<td>EnumString</td>
<td>&quot;STS_add(*addr)&quot; (&quot;STS_delta(*addr)&quot;, &quot;STS_add(-*addr)&quot;, &quot;STS_delta(-*addr)&quot;, &quot;STS_add(*addr)&quot;, &quot;STS_delta(*addr)&quot;&quot;)</td>
</tr>
<tr>
<td>useDispatcher</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>arg</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>interruptMask0</td>
<td>EnumString</td>
<td>&quot;self&quot; (&quot;all&quot;, &quot;none&quot;, &quot;bitmask&quot;)</td>
</tr>
<tr>
<td>interruptMask1</td>
<td>EnumString</td>
<td>&quot;self&quot; (&quot;all&quot;, &quot;none&quot;, &quot;bitmask&quot;)</td>
</tr>
<tr>
<td>interruptBitMask0</td>
<td>Numeric</td>
<td>0x0010 *</td>
</tr>
<tr>
<td>interruptBitMask1</td>
<td>Numeric</td>
<td>0x0010 *</td>
</tr>
<tr>
<td>iMirMask</td>
<td>EnumString</td>
<td>&quot;self&quot; (&quot;all&quot;, &quot;none&quot;, &quot;bitmask&quot;) (OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>mirmask</td>
<td>Numeric</td>
<td>0x00000000 * (OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>mirMask</td>
<td>Numeric</td>
<td>0x00000000 * (OMAP 2320 only)</td>
</tr>
<tr>
<td>priority</td>
<td>Numeric</td>
<td>0 (0-31 or 0-63) (OMAP 2320/2420 only)</td>
</tr>
</tbody>
</table>

* Depends on interrupt ID

Description

The HWI module manages hardware interrupts. Using Tconf, you can assign routines that run when specific hardware interrupts occur. Some routines are assigned to interrupts automatically by the HWI module. For example, the interrupt for the timer that you select for the CLK global properties is automatically configured to run a function that increments the low-resolution time. See the CLK Module for more details.

You can also dynamically assign routines to interrupts at run-time using the HWI_dispatchPlug function or the C55_plug function.

Interrupt routines can be written completely in assembly, completely in C, or in a mix of assembly and C. In order to support interrupt routines written completely in C, an HWI dispatcher is provided that performs the requisite prolog and epilog for an interrupt routine.
Note: **RTS Functions Callable from TSK Threads Only.** Many runtime support (RTS) functions use lock and unlock functions to prevent reentrancy. However, DSP/BIOS SWI and HWI threads cannot call LCK_pend and LCK_post. As a result, RTS functions that call LCK_pend or LCK_post must not be called in the context of a SWI or HWI thread. For a list or RTS functions that should not be called from a SWI or an HWI function, see “LCK_pend” on page 181.

The C++ "new" operator calls malloc, which in turn calls LCK_pend. As a result, the "new" operator cannot be used in the context of a SWI or HWI thread.

**HWI Dispatcher vs. HWIEnter/exit**

The HWI dispatcher is the preferred method for handling an interrupt.

When an HWI object does not use the dispatcher, the HWI_enter assembly macro must be called prior to any DSP/BIOS API calls that affect other DSP/BIOS objects, such as posting a SWI or a semaphore, and the HWI_exit assembly macro must be called at the very end of the function’s code.

When an HWI object is configured to use the dispatcher, the dispatcher handles the HWI_enter prolog and HWI_exit epilog, and the HWI function can be completely written in C. It would, in fact, cause a system crash for the dispatcher to call a function that contains the HWI_enter/HWI_exit macro pair. Using the dispatcher allows you to save code space by including only one instance of the HWI_enter/HWI_exit code.

Note: CLK functions should not call HWI_enter and HWI_exit as these are called internally by DSP/BIOS when it runs CLK_F_isr. Additionally, CLK functions should **not** use the interrupt keyword or the INTERRUPT pragma in C functions.

**Notes**

In the following notes, references to the usage of HWI_enter/HWI_exit also apply to usage of the HWI dispatcher since, in effect, the dispatcher calls HWI_enter/HWI_exit.

- Do not call SWI_disable or SWI_enable within an HWI function.
- Do not call HWI_enter, HWI_exit, or any other DSP/BIOS functions from a non-maskable interrupt (NMI) service routine. In addition, the HWI dispatcher cannot be used with the NMI service routine.
- Do not call HWI_enter/HWI_exit from a HWI function that is invoked by the dispatcher.
- The DSP/BIOS API calls that require an HWI function to use HWI_enter and HWI_exit are:
  - SWI_andn
  - SWI_andnHook
  - SWI_dec
  - SWI_inc
  - SWI_or
  - SWI_orHook
  - SWI_post
  - PIP_alloc
  - PIP_free
  - PIP_get
  - PIP_put
  - PRD_tick
Any PIP API call can cause the pipe’s notifyReader or notifyWriter function to run. If an HWI function calls a PIP function, the notification functions run as part of the HWI function.

An HWI function must use HWI_enter and HWI_exit or must be dispatched by the HWI dispatcher if it indirectly runs a function containing any of the API calls listed above.

If your HWI function and the functions it calls do not call any of these API operations, you do not need to disable SWI scheduling by calling HWI_enter and HWI_exit.

DSP/BIOS and NMI Support

You should use the NMI interrupt only if tasking is disabled (that is, in a SWI-only system) or if tasking is enabled but all the task stacks and the ISR stack are in the same memory page. This is because it is not possible to atomically modify SP, SSP, and the page register such that the whole operation is protected from an NMI (non-maskable interrupt). When tasking is enabled, DSP/BIOS modifies these registers whenever an interrupt occurs, whenever a SWI is executed, and whenever a task context switch takes place. Thus it is possible for an NMI to occur when the state of these registers is not internally consistent. This could result in unpredictable behavior when the DSP tries to push the processor state onto the stack on its way to the NMI vector.

Registers and Stack

Whether a hardware interrupt is dispatched by the HWI dispatcher or handled with the HWI_enter/HWI_exit macros, a common interrupt stack (called the system stack) is used for the duration of the HWI. This same stack is also used by all SWI routines.

The register mask argument to HWI_enter and HWI_exit allows you to save and restore registers used within the function. Other arguments, for example, allow the HWI to control the settings of the IMR or, in the case of the C55x device, the IER0[IER1].

Note: By using HWI_enter and HWI_exit as an HWI function’s prolog and epilog, an HWI function can be interrupted; that is, a hardware interrupt can interrupt another interrupt. For the c55x device, you can use the IER0DISABLEMASK and IER1DISABLEMASK parameters to prevent this from occurring.

HWI Manager Properties

DSP/BIOS manages the hardware interrupt vector table and provides basic hardware interrupt control functions; for example, enabling and disabling the execution of hardware interrupts.

The following global properties can be set for the HWI module in the HWI Manager Properties dialog of Gconf or in a Tconf script:

• Stack Mode. Select the Stack Mode used for the application: C54X_STK, USE_RETA or NO_RETA. The stack mode selected here takes effect only if the program address 0xffff00 (the hardware reset vector location) is programmable and the linker is configured to place the vector table (.hwi_vec
section) at address 0xffff00. If this address is located in ROM space, it is not programmable.

DSP/BIOS does not report an error if it is unable to modify the value at this address to set the
specified stack mode.

Tconf Name: STACKMODE Type: EnumString
Options: "C54X_STK", "USE_RETA", "NO_RETA"
Example: bios.HWI.STACKMODE = "C54X_STK";

To set the 'C55x stackmode, perform all of the following steps:

— Set the stackmode configuration property to the mode you want to use in your configuration using
a statement similar to the preceding example.

— Add the following arguments to your linker command line. These arguments force a soft reset
using the RAM-based interrupt vector table.

-u C55_c_int00 -e C55_c_int00

— Make sure the .hwi_vec memory section (the interrupt vector table) is located in RAM. By default,
this section is automatically located at the top of RAM.

• Interrupt Controller Base. By default, the OMAP 2420 Level 2 Interrupt Controller (L2IC) resides at
data memory address 0x7e4800. This coincides with the reset IOMA value of 0x3f. For OMAP 2320,
the default base address is 0x7c4800, which coincides with the reset IOMA value of 0x3e. The IO
MAP (IOMA) base address is the page index used to access DSP I/O space addresses from DSP
memory space. If you modify IOMA for any reason, you need to use this property to tell DSP/BIOS
the new base address for the L2IC. (OMAP 2320/2420 only)

Tconf Name: INTC_BASE Type: Numeric
Example: bios.HWI.INTC_BASE = 0x7e4800;

HWI Object Properties

The following properties can be set for an HWI object in the HWI Object Properties dialog of the
DSP/BIOS Configuration Tool or in a Tconf script. The HWI objects for the platform are provided in the
default configuration and cannot be created.

• comment. A comment is provided to identify each HWI object.

Tconf Name: comment Type: String
Example: bios.HWI_INT2.comment = "myISR";

• function. The function to execute. Interrupt routines that use the dispatcher can be written
completely in C or any combination of assembly and C but must not call the HWI_enter/HWI_exit
macro pair. Interrupt routines that don’t use the dispatcher must be written at least partially in
assembly language. Within an HWI function that does not use the dispatcher, the HWI_enter
assembly macro must be called prior to any DSP/BIOS API calls that affect other DSP/BIOS objects,
such as posting a SWI or a semaphore. HWI functions can post SWIs, but they do not run until your
HWI function (or the dispatcher) calls the HWI_exit assembly macro, which must be the last
statement in any HWI function that calls HWI_enter.

Tconf Name: fxn Type: Extern
Example: bios.HWI_INT2.fxn = prog.extern("myHWI", "asm");

• monitor. If set to anything other than Nothing, an STS object is created for this HWI that is passed
the specified value on every invocation of the HWI function. The STS update occurs just before
entering the HWI routine.
Be aware that when the monitor property is enabled for a particular HWI object, a code preamble is inserted into the HWI routine to make this monitoring possible. The overhead for monitoring is 20 to 30 instructions per interrupt, per HWI object monitored. Leaving this instrumentation turned on after debugging is not recommended, since HWI processing is the most time-critical part of the system.

Options:  "Nothing", "Data Value", "xsp", "ac0g", "ac0h", "ac0l", "ac1g", "ac1h", "ac1l", "ac2g", "ac2h", "ac2l", "ac3g", "ac3h", "ac3l", "xar0", "xar1", "xar2", "xar3", "xar4", "xar5", "xar6", "xar7", "t0", "t1", "t2", "t3", "xssp", "tim", "st0_55", "st1_55", "st2_55", "st3_55", "tm0", "bk03", "brc0", "xdp", "xcdp", "dph", "mdp05", "mdp67", "pdp", "bk47", "bkc", "bsa01", "bsa23", "bsa45", "bsa67", "bsac", "trn1", "brc1", "csr", "rptc"

Example:  bios.HWI_INT2.monitor = "Nothing";

•  **addr.** If the monitor property above is set to Data Address, this property lets you specify a data memory address to be read; the word-sized value is read and passed to the STS object associated with this HWI object.

Tconf Name:  addr  Type:  Arg

Example:  bios.HWI_INT2.addr = 0x00000000;

•  **type.** The type of the value to be monitored: unsigned or signed. Signed quantities are sign extended when loaded into the accumulator; unsigned quantities are treated as word-sized positive values.

Tconf Name:  dataType  Type:  EnumString

Options:  "signed", "unsigned"

Example:  bios.HWI_INT2.dataType = "signed";

•  **operation.** The operation to be performed on the value monitored. You can choose one of several STS operations.

Tconf Name:  operation  Type:  EnumString

Options:  "STS_add(*addr)", "STS_delta(*addr)", "STS_add(-*addr)", "STS_delta(-*addr)", "STS_add(|*addr|)", "STS_delta(|*addr|)"

Example:  bios.HWI_INT2.operation = "STS_add(*addr)";

•  **Use Dispatcher.** A check box that controls whether the HWI dispatcher is used. The HWI dispatcher cannot be used for the non-maskable interrupt (NMI) service routine.

Tconf Name:  useDispatcher  Type:  Bool

Example:  bios.HWI_INT2.useDispatcher = false;

•  **Arg.** This argument is passed to the function as its only parameter. You can use either a literal integer or a symbol defined by the application. This property is available only when using the HWI dispatcher.

Tconf Name:  arg  Type:  Arg

Example:  bios.HWI_INT2.arg = 3;

•  **Interrupt Mask.** Specifies which interrupts the dispatcher should disable before calling the function. This property is available only when using the HWI dispatcher.

—  The "self" option causes the dispatcher to disable only the current interrupt and causes the appropriate interruptBitMask0, interruptBitMask1, and mirmask/mir1mask values to be generated for the interrupt being configured. When using "self", set both interruptMask0 and interruptMask1 (and iMirMask if the platform is OMAP 2320/2420) to "self".

—  The "all" option disables all interrupts.

—  The "none" option disables no interrupts.

—  The "bitmask" option causes the interruptBitMask[0/1] property to be used to specify which interrupts to disable.
(For 'C55x, separate interruptMasks are provided for IER0 and IER1.) (For OMAP 2320/2420, these properties control only the level 1 interrupts. The iMirMask property controls the level 2 interrupts.)

**Interrupt Bit Mask.** An integer property that is writable when the interrupt mask is set to "bitmask". This should be a hexadecimal integer bitmask specifying the interrupts to disable. (For 'C55x, separate properties are provided for IER0 and IER1.) For OMAP 2320/2420, these properties disable only level 1 interrupts. The mirmask property (and mir1mask for OMAP 2320) controls the level 2 interrupts.

- **Tconf Name:** interruptBitMask0  **Type:** Numeric
- **Tconf Name:** interruptBitMask1  **Type:** Numeric

**Example:**
```
bios.HWI_INT2.interruptBitMask0 = 0x0010;
```

- **L2 Interrupt Mask MIR (and MIR1).** This property is valid for both level 1 and 2 interrupts. It specifies which level 2 interrupts the dispatcher should disable before calling this HWI function. This property is writeable only if the useDispatcher property is set to true.
  - The "self" option causes the dispatcher to disable only the current interrupt and causes the appropriate interruptBitMask0, interruptBitMask1, mirmask, and mir1mask values to be generated for the interrupt being configured. When using "self", set all of interruptMask0, interruptMask1, and iMirMask to "self".
  - The "all" option disables all level 2 interrupts.
  - The "none" option disables no level 2 interrupts.
  - The "bitmask" option causes the mirmask (and mir1mask for OMAP 2320) property to be used to specify which level 2 interrupts to disable.

This property is similar to interruptMask0 and interruptMask1, which deal with level 1 interrupts. (OMAP 2320/2420 only)

- **Tconf Name:** iMirMask  **Type:** EnumString

**Example:**
```
bios.HWI_INT2.iMirMask = "self";
```

- **L2 Interrupt Bit Mask MIR.** This property is valid for both level 1 and 2 interrupts. It defines a bitmask of level 2 interrupts 0-31 to be disabled by the DSP/BIOS HWI dispatcher when executing this HWI function. This property is writeable only when the useDispatcher property is set to true and iMirMask is set to "bitmask". This property is similar to interruptBitMask0 and interruptBitMask1, which mask level 1 interrupts. The default value is to disable only the current level 2 interrupt. (OMAP 2320/2420 only)

- **Tconf Name:** mirmask  **Type:** Numeric

**Example:**
```
bios.HWI_INT2.mirmask = 0x00000000;
```

- **L2 Interrupt Bit Mask MIR1.** This property is similar to the previous one, except that it defines a bitmask of level 2 interrupts 32-63 for OMAP 2320 only.

- **Tconf Name:** mir1mask  **Type:** Numeric

**Example:**
```
bios.HWI_INT2.mir1mask = 0x00000000;
```
**L2 Interrupt Priority.** For OMAP 2320, sets a priority from 0 to 63 for a level 2 interrupt. For OMAP 2420, sets a priority from 0 to 31 for a level 2 interrupt. Zero is the highest priority. The default priority for a level 2 interrupt matches its interrupt number. Although this field exists for all HWI interrupt objects, it cannot be configured for level 1 interrupts. You can change the priority at run-time using the C55_I2SetIntPriority API. (OMAP 2320/2420 only)

```
Tconf Name: priority Type: Numeric
Example: bios.HWI_INT2.priority = 0;
```

Although it is not possible to create new HWI objects, most interrupts supported by the device architecture have a precreated HWI object. Your application can require that you select interrupt sources other than the default values in order to rearrange interrupt priorities or to select previously unused interrupt sources.

In addition to the precreated HWI objects, some HWI objects are preconfigured for use by certain DSP/BIOS modules. For example, the CLK module configures an HWI object.

Table 2-3 list these precreated objects and their default interrupt sources. The HWI object names are the same as the interrupt names.

### Table 2-3: HWI interrupts for the `C55x`

<table>
<thead>
<tr>
<th>Name</th>
<th>Interrupt Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>HWI_RESET</td>
<td>Reset interrupt.</td>
</tr>
<tr>
<td>HWI_NMI</td>
<td>Non-maskable interrupt. (See page 2–156)</td>
</tr>
<tr>
<td>HWI_INT2</td>
<td>Maskable (IER0, bit2) hardware interrupt.</td>
</tr>
<tr>
<td>HWI_INT3</td>
<td>Maskable (IER0, bit3) hardware interrupt.</td>
</tr>
<tr>
<td>HWI_TINT</td>
<td>Timer interrupt. (IER, bit4)</td>
</tr>
<tr>
<td>HWI_INT5 through HWI_INT15</td>
<td>Maskable (IER0, bit5) hardware interrupt through Maskable (IER0, bit15) hardware interrupt.</td>
</tr>
<tr>
<td>HWI_INT16 through HWI_INT23</td>
<td>Maskable (IER1, bit0) hardware interrupt through Maskable (IER1, bit7) hardware interrupt.</td>
</tr>
<tr>
<td>HWI_BERR</td>
<td>Maskable (IER1, bit8) bus error interrupt.</td>
</tr>
<tr>
<td>HWI_DLOG</td>
<td>Maskable (IER1, bit9) data log interrupt.</td>
</tr>
<tr>
<td>HWI_RTOS</td>
<td>Maskable (IER1, bit10) RTOS interrupt.</td>
</tr>
<tr>
<td>HWI_SINT27 through HWI_SINT31</td>
<td>Non-maskable software interrupt.</td>
</tr>
<tr>
<td>HWI_L2_INT0 through HWI_L2_INT31</td>
<td>Level 2 interrupts (OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>HWI_L2_INT32 through HWI_L2_INT63</td>
<td>Level 2 interrupts (OMAP 2320 only)</td>
</tr>
</tbody>
</table>
HWI_disable

Disable hardware interrupts

C Interface

Syntax
oldST1 = HWI_disable();

Parameters
Void

Return Value
Uns oldST1;

Reentrant
yes

Description
HWI_disable disables hardware interrupts by setting the intm bit in the status register. Call HWI_disable before a portion of a function that needs to run without interruption. When critical processing is complete, call HWI_restore or HWI_enable to reenable hardware interrupts.

Interrupts that occur while interrupts are disabled are postponed until interrupts are reenabled. However, if the same type of interrupt occurs several times while interrupts are disabled, the interrupt’s function is executed only once when interrupts are reenabled.

A context switch can occur when calling HWI_enable or HWI_restore if an enabled interrupt occurred while interrupts are disabled.

HWI_disable may be called from main(). However, since HWI interrupts are already disabled in main(), such a call has no effect.

Example
old = HWI_disable();
    'do some critical operation'
HWI_restore(old);

See Also
HWI_enable
HWI_restore
SWI_disable
SWI_enable
HWI_dispatchPlug  Plug the HWI dispatcher

C Interface

Syntax

HWI_dispatchPlug(vecid, fxn, attrs);

Parameters

Int vecid; /* interrupt id */
Fxn fxn; /* pointer to HWI function */
HWI_Attrs *attrs /*pointer to HWI dispatcher attributes */

Return Value

Void

Reentrant

yes

Description

HWI_dispatchPlug fills the HWI dispatcher table with the function specified by the fxn parameter and the
attributes specified by the attrs parameter.

HWI_dispatchPlug also writes four instruction words into the Interrupt-Vector Table, at the address
corresponding to vecid. The instructions written in the Interrupt-Vector Table create a call to the HWI
dispatcher.

HWI_dispatchPlug does not enable the interrupt. Use C54_enableIMR or
C55_enableIER0/C55_enableIER1 to enable specific interrupts.

If attrs is NULL, the HWI's dispatcher properties are assigned a default set of attributes. Otherwise, the
HWI's dispatcher properties are specified by a structure of type HWI_Attrs defined as follows.

typedef struct HWI_Attrs {
    Uns ier0mask; /* IER0 bitmask */
    Uns ier1mask; /* IER1 bitmask */
    Arg arg; /* fxn arg (default = 0) */
    LgUns mirmask; /* OMAP 2320/2420 only */
    LgUns mir1mask; /* OMAP 2320 only */
} HWI_Attrs;

The ier0mask is a bitmask that specifies the ier0 interrupts to mask while executing the HWI. The bit
positions in ier0mask correspond to those of IER0.

The ier1mask is a bitmask that specifies the ier1 interrupts to mask while executing the HWI. The bit
positions in ier1mask correspond to those of IER1. If ier0mask and ier1mask are both 1, then a mask to
disable "self" is created.

The mirmask is a bitmask that specifies which level 2 interrupts to mask while executing the HWI. This
field contains a 32-bit mask in which each bit corresponds to level 2 interrupts 0-31. The default value for
each interrupt is to mask only the current level 2 interrupt. (OMAP 2320/2420 only)

The mir1mask is a bitmask that specifies which level 2 interrupts to mask while executing the HWI. This
field contains a 32-bit mask in which each bit corresponds to level 2 interrupts 32-63. The default value
for each interrupt is to mask only the current level 2 interrupt. (OMAP 2320 only)
The default values are defined as follows:

```
HWI_Attrs HWI_ATTRS = {
    1,   /* IER0 mask (1 => self) */
    1,   /* IER1 mask (1 => self) */
    0    /* argument to ISR */
};
```

The arg element is a generic argument that is passed to the plugged function as its only parameter. The default value is 0.

**Constraints and Calling Context**

- vecid must be a valid interrupt ID in the range of 0-31 (0-95 for OMAP 2320, 0-63 for OMAP 2420).

**See Also**

- HWI_enable
- HWI_restore
- SWI_disable
- SWI_enable
**HWI_enable**  
*Enable interrupts*

**C Interface**

**Syntax**

```c
HWI_enable();
```

**Parameters**

- Void

**Return Value**

- Void

**Reentrant**

Yes

**Description**

HWI_enable enables hardware interrupts by clearing the intm bit in the status register.

Hardware interrupts are enabled unless a call to HWI_disable disables them. DSP/BIOS enables hardware interrupts after the program’s main() function runs. Your main() function can enable individual interrupt mask bits, but it should not call HWI_enable to globally enable interrupts.

Interrupts that occur while interrupts are disabled are postponed until interrupts are reenabled. However, if the same type of interrupt occurs several times while interrupts are disabled, the interrupt’s function is executed only once when interrupts are reenabled. A context switch can occur when calling HWI_enable/HWI_restore if an enabled interrupt occurs while interrupts are disabled.

Any call to HWI_enable enables interrupts, even if HWI_disable has been called several times.

**Constraints and Calling Context**

- HWI_enable cannot be called from the program’s main() function.

**Example**

```c
HWI_disable();
"critical processing takes place"
HWI_enable();
"non-critical processing"
```

**See Also**

- HWI_disable
- HWI_restore
- SWI_disable
- SWI_enable
**H威尔**

*Hardware ISR prolog*

**C Interface**

**Syntax**

none

**Parameters**

none

**Return Value**

none

**Assembly Interface**

**Syntax**

HWI enter C55_AR_DR_X_MASK, C55_ACC_X_MASK, \ 
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK, \ 
IER0DISABLEMASK, IER1DISABLEMASK

**OMAP 2320 only:**

HWI enter C55_AR_DR_X_MASK, C55_ACC_X_MASK, \ 
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK, \ 
IER0DISABLEMASK, IER1DISABLEMASK, MIRDISABLEMASK, \ 
MIRDISABLEMASK

**OMAP 2420 only:**

HWI enter C55_AR_DR_X_MASK, C55_ACC_X_MASK, \ 
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK, \ 
IER0DISABLEMASK, IER1DISABLEMASK

**Preconditions**

intm = 1

**Postconditions**

intm=0, braf=0, cpl=1, m40=0, satd=0, sxmd=0, c16=0, frct=0, c54m=0, arms=1, rdm=0, cdplc=0, \ 
ar[0...7]=c0, sat=0, smul=0, sst=0

Both the user stack pointer (XSP and the system stack pointer (XSSP) are left aligned to even address boundaries in compliance with standard C conventions.

**Modifies**

xar0, xar1, ac0g, ac0h, ier0, ier1, ac1, ac2

**Reentrant**

yes

**Description**

HWI enter is an API (assembly macro) used to save the appropriate context for a DSP/BIOS hardware interrupt (HWI).

The arguments to HWI enter are bitmasks that define the set of registers to be saved and bitmasks that define which interrupts are to be masked during the execution of the HWI.

HWI enter is used by HWIs that are user-dispatched, as opposed to HWIs that are handled by the HWI dispatcher. HWI enter must not be issued by HWIs that are handled by the HWI dispatcher.
If the HWI dispatcher is not used by an HWI object, HWI_enter must be used in the HWI before any DSP/BIOS API calls that could trigger other DSP/BIOS objects, such as posting a SWI or semaphore. HWI_enter is used in tandem with HWI_exit to ensure that the DSP/BIOS SWI or TSK manager is called at the appropriate time. Normally, HWI_enter and HWI_exit must surround all statements in any DSP/BIOS assembly language HWIs that call C functions.

The following list shows the mask families available for the HWI_enter and HWI_exit API syntax. For each family, several masks are defined where the "X" indicates which registers are saved. (That is, "X" can be SAVE_BY_CALLER, SAVE_BY_CALLEE, or BIOS_CONTEXT). For example, the "C55_ACC_SAVE_BY_CALLEE_MASK" is in the C55_ACC_X_MASK family. See the c55.h55 file for a complete list of masks and the example later in this section for a clearer understanding. Typically "SAVE_BY_CALLER" is used for ISRs written in C.

- **C55_AR_DR_X_MASK.** Mask of registers belonging to ar0-7, t0-3, sp-ssp
- **C55_ACC_X_MASK.** Mask of registers belonging to ac0-3
- **C55_MISC1_X_MASK.** Mask of registers ier0, ier1, ifr, dbier0, dbier1, st0, st1, st2, st3, tm0, bk03, brc0
- **C55_MISC2_X_MASK.** Mask of registers dp, cdp, mdp05, mdp67, pdp, bk47, bkc, bof01, bof23, bof45, bof67, bofc, ivpd, ivph, tm1
- **C55_MISC3_X_MASK.** Mask of registers brc1, csr, rsa0_h_addr, rsa0, rea0_h_addr, rea0, rsa1_h_addr, rsa1, rea1_h_addr, rea1, rtpc
- **IER0DISABLEMASK / IER0RESTOREMASK.** The IER0 and IER1 masks define which interrupts are to be masked while the HWI is executing and restored at the end of execution. These arguments mask ier0 bits to turn off (and to restore).
- **IER1DISABLEMASK / IER1RESTOREMASK.** These arguments mask ier1 bits to turn off (and to restore).
- **MIRDISABLEMASK / MIRRESTOREMASK.** These arguments mask level 2 interrupt bits (0-31) to turn off (and to restore). (OMAP 2320/2420 only)
- **MIR1DISABLEMASK / MIR1RESTOREMASK.** These arguments mask level 2 interrupt bits (32-63) to turn off (and to restore). (OMAP 2320 only)

See c55.h55 for constants defined for working with these masks. If your HWI is coded in C, it is recommended that you use the SAVE_BY_CALLER masks provided in c55.h55.

**Note:** The C55_saveCcontext, C55_restoreCcontext C55_saveBiosContext and C55_restoreBiosContext macros preserve processor register context per C and DSP/BIOS requirements, respectively.

**Constraints and Calling Context**

- This API should not be used in the NMI HWI function.
- This API must not be called if the HWI object that runs this function uses the HWI dispatcher.
- This API cannot be called from the program’s main() function.
- This API cannot be called from a SWI, TSK, or IDL function.
- This API cannot be called from a CLK function.
• Unless the HWI dispatcher is used, this API must be called within any hardware interrupt function (except NMI’s HWI function) before the first operation in an HWI that uses any DSP/BIOS API calls that might post or affect a SWI or semaphore. Such functions must be written in assembly language. Alternatively, the HWI dispatcher can be used instead of this API, allowing the function to be written completely in C and allowing you to reduce code size.

• If an interrupt function calls HWI_enter, it must end by calling HWI_exit.

• Do not use the interrupt keyword or the INTERRUPT pragma in C functions that run in the context of an HWI.

Examples

Example #1:
Calling a C function from within an HWI_enter/HWI_exit block. Specify all registers in the C convention class, save-by-caller. Use the appropriate register save masks with the HWI_enter macro. See the c55.h55 file for definitions of the masks used in this example.

```
HWI_enter C55_AR_DR_SAVE_BY_CALLER_MASK, \\
C55_ACC_SAVE_BY_CALLER_MASK, \\
C55_MISC1_SAVE_BY_CALLER_MASK, \\
C55_MISC2_SAVE_BY_CALLER_MASK, \\
C55_MISC3_SAVE_BY_CALLER_MASK, \\
user_ier0_mask, user_ier1_mask
```

The HWI_enter macro:

• preserves the specified set of registers that are being declared as trashable by the called function

• places the processor status register bit settings as required by C compiler conventions

• aligns stack pointers to even address boundaries, as well as remembering any such adjustments made to SP and SSP registers

• masks those interrupts defined by the interrupt masks

• enables interrupts

The user’s C function must have a leading underscore as in this example:

```
call _myCfunction;
```

When exiting the hardware interrupt, you need to call HWI_exit with the following macro:

```
HWI_exit C55_AR_DR_SAVE_BY_CALLER_MASK, \\
C55_ACC_SAVE_BY_CALLER_MASK, \\
C55_MISC1_SAVE_BY_CALLER_MASK, \\
C55_MISC2_SAVE_BY_CALLER_MASK, \\
C55_MISC3_SAVE_BY_CALLER_MASK, \\
user_ier0_mask, user_ier1_mask
```

The HWI_exit macro restores the CPU state that was originally set by the HWI_enter macro. It alerts the SWI scheduler to attend to any kernel scheduling activity that is required.

See Also

HWI_exit
HWI_exit

Hardware ISR epilog

C Interface

Syntax
none

Parameters
none

Return Value
none

Assembly Interface

Syntax
HWI_exit C55_AR_DR_X_MASK, C55_ACC_X_MASK, \ 
C55_MISC1_X_MASK, C55_MISC2_X_MASK, \ 
C55_MISC3_X_MASK, \ 
IER0RESTOREMASK, IER1RESTOREMASK

OMAP 2320 only:
HWI_enter C55_AR_DR_X_MASK, C55_ACC_X_MASK, \ 
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK, \ 
IER0RESTOREMASK, IER1RESTOREMASK, MIRRESTOREMASK, \ 
MIR1RESTOREMASK

OMAP 2420 only:
HWI_enter C55_AR_DR_X_MASK, C55_ACC_X_MASK, \ 
C55_MISC1_X_MASK, C55_MISC2_X_MASK, C55_MISC3_X_MASK, \ 
IER0RESTOREMASK, IER1RESTOREMASK, MIRRESTOREMASK

Preconditions
none

Postconditions
intm=0

Modifies
Restores all registers saved with the HWI_enter mask

Reentrant
yes

Description
HWI_exit is an API (assembly macro) which is used to restore the context that existed before a
DSP/BIOS hardware interrupt (HWI) was invoked.

HWI_exit is used by HWIs that are user-dispatched, as opposed to HWIs that are handled by the HWI
dispatcher. HWI_exit must not be issued by HWIs that are handled by the HWI dispatcher.
If the HWI dispatcher is not used by an HWI object, HWI_exit must be the last statement in an HWI that uses DSP/BIOS API calls which could trigger other DSP/BIOS objects, such as posting a SWI or semaphore.

HWI_exit restores the registers specified by C55_AR_DR_X_MASK, C55_ACC_X_MASK, C55_MISC1_X_MASK, C55_MISC2_X_MASK, and C55_MISC3_X_MASK. These masks are used to specify the set of registers that were saved by HWI_enter.

HWI进入和HWI_exit必须包围任何DSP/BIOS汇编语言HWIs中使用的C函数。对于HWI进入/退出区域的任何中断，DSP/BIOS SWI管理器服务所有未处理的SWI管理器（函数）。

Of the interrupts in IER0[IER1]RESTOREMASK, HWI_exit only restores those that were disabled upon entering the HWI. HWI_exit does not affect the status of interrupt bits that are not in IER0[IER1]RESTOREMASK.

• If upon exiting an HWI you do not want to restore an interrupt that was disabled with HWI_enter, do not set that interrupt bit in the IER0[IER1]RESTOREMASK in HWI_exit.
• If upon exiting an HWI you do want to enable an interrupt that was disabled upon entering the HWI, set the corresponding bit in IER0[IER1]RESTOREMASK before calling HWI_exit. (Setting bits in IER0[IER1]RESTOREMASK passed to HWI_exit does not enable the corresponding interrupts if they were not originally disabled by the HWI_enter macro.)

This same logic applies to the OMAP 2320/2420 MIRRESTOREMASK argument and the OMAP 2320 MIR1RESTOREMASK.

For a list of parameters and constants available for use with HWI_exit, see the description of HWI_enter. In addition, see the c55.h55 file.

Constraints and Calling Context
• This API should not be used for the NMI HWI function.
• This API must not be called if the HWI object that runs the function uses the HWI dispatcher.
• If the HWI dispatcher is not used, this API must be the last operation in an HWI that uses any DSP/BIOS API calls that might post or affect a SWI or semaphore. The HWI dispatcher can be used instead of this API, allowing the function to be written completely in C and allowing you to reduce code size.
• For 'C55x, the C55_AR_DR_X_MASK, C55_ACC_X_MASK, C55_MISC1_X_MASK, C55_MISC2_X_MASK, and C55_MISC3_X_MASK parameters must match the corresponding parameters used for HWI_enter.
• This API cannot be called from the program's main() function.
• This API cannot be called from a SWI, TSK, or IDL function.
• This API cannot be called from a CLK function.

Examples
Example #1:
Calling a C function from within an HWI_enter/HWI_exit:
Specify all registers in the C convention class, save-by-caller. Use the appropriate register save masks with the HWI_enter macro:

```
HWI_enter C55_AR_DRSAVE_BY_CALLER_MASK, \nC55_ACC_SAVE_BY_CALLER_MASK, \nC55_MISC1_SAVE_BY_CALLER_MASK, \nC55_MISC2_SAVE_BY_CALLER_MASK, \nC55_MISC3_SAVE_BY_CALLER_MASK, \nuser_ier0_mask, user_ier1_mask
```

The HWI_enter macro:

- preserves the specified set of registers that are being declared as trashable by the called function
- places the processor status register bit settings as required by C compiler conventions
- aligns stack pointers to even address boundaries, as well as remembering any such adjustments made to SP and SSP registers

The user’s C function must have a leading underscore as in this example:

```
call _myCfunction;
```

When exiting the hardware interrupt, you need to call HWI_exit with the following macro:

```
HWI_exit C55_AR_DR_SAVE_BY_CALLER_MASK, \nC55_ACC_SAVE_BY_CALLER_MASK, \nC55_MISC1_SAVE_BY_CALLER_MASK, \nC55_MISC2_SAVE_BY_CALLER_MASK, \nC55_MISC3_SAVE_BY_CALLER_MASK, \nuser_ier0_mask, user_ier1_mask
```

The HWI_exit macro restores the CPU state that was originally set by the HWI_enter macro. It alerts the SWI scheduler to attend to any kernel scheduling activity that is required.

See Also

- HWI_enter
HWI_isHWI  
Check to see if called in the context of an HWI

C Interface

Syntax
result = HWI_isHWI(Void);

Parameters
Void

Return Value
Bool  
result;  /* TRUE if in HWI context, FALSE otherwise */

Reentrant
yes

Description
This macro returns TRUE when it is called within the context of an HWI or CLK function. This macro returns FALSE in all other contexts.

In previous versions of DSP/BIOS, calling HWI_isHWI() from main() resulted in TRUE. This is no longer the case; main() is identified as part of the TSK context.

See Also

SWI_isSWI
TSK_isTSK
HWI_restore

Restore global interrupt enable state

C Interface

Syntax

HWI_restore(oldST1);

Parameters

Uns oldST1;

Returns

Void

Reentrant
yes

Description

HWI_restore sets the intm bit in the st1 register using bit 11 of the oldst1 parameter. If bit 11 is 1, the intm bit is not modified. If bit 11 is 0, the intm bit is set to 0, which enables interrupts.

When you call HWI_disable, the previous contents of the st1 register are returned. You can use this returned value with HWI_restore.

A context switch may occur when calling HWI_restore if HWI_restore reenables interrupts and if a higher-priority HWI occurred while interrupts were disabled.

HWI_restore may be called from main(). However, since HWI_enable cannot be called from main(), interrupts are always disabled in main(), and a call to HWI_restore has no effect.

Constraints and Calling Context

• HWI_restore must be called with interrupts disabled. The parameter passed to HWI_restore must be the value returned by HWI_disable.

Example

oldST1 = HWI_disable(); /* disable interrupts */
'do some critical operation'
HWI_restore(oldST1);
/* re-enable interrupts if they
were enabled at the start of the
critical section */

See Also

HWI_enable
HWI_disable
2.11 IDL Module

The IDL module is the idle thread manager.

Functions

- IDL_run. Make one pass through idle functions.

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the IDL Manager Properties and IDL Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>AUTOCALCULATE</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>LOOPINSTCOUNT</td>
<td>Int32</td>
<td>1000</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>fxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>calibration</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>order</td>
<td>Int16</td>
<td>0</td>
</tr>
</tbody>
</table>

Description

The IDL module manages the lowest-level threads in the application. In addition to user-created functions, the IDL module executes DSP/BIOS functions that handle host communication and CPU load calculation.

There are four kinds of threads that can be executed by DSP/BIOS programs: hardware interrupts (HWI Module), software interrupts (SWI Module), tasks (TSK Module), and background threads (IDL module). Background threads have the lowest priority, and execute only if no hardware interrupts, software interrupts, or tasks need to run.

An application’s main() function must return before any DSP/BIOS threads can run. After the return, DSP/BIOS runs the idle loop. Once an application is in this loop, HWI hardware interrupts, SWI software interrupts, PRD periodic functions, TSK task functions, and IDL background threads are all enabled.

The functions for IDL objects registered with the configuration are run in sequence each time the idle loop runs. IDL functions are called from the IDL context. IDL functions can be written in C or assembly and must follow the C calling conventions described in the compiler manual.

When RTA is enabled (see page 2–121), an application contains an IDL_cpuLoad object, which runs a function that provides data about the CPU utilization of the application. In addition, the LNK_dataPump function handles host I/O in the background, and the RTA_dispatch function handles run-time analysis communication.

The IDL Function Manager allows you to insert additional functions that are executed in a loop whenever no other processing (such as HWIs or higher-priority tasks) is required.
IDL Manager Properties

The following global properties can be set for the IDL module in the IDL Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the IDL objects.
  
  **Tconf Name:** OBJMEMSEG  
  **Type:** Reference  
  **Example:**  
  ```  
  bios.IDL.OBJMEMSEG = prog.get("myMEM");  
  ```

- **Auto calculate idle loop instruction count.** When this property is set to true, the program runs the IDL functions one or more times at system startup to get an approximate value for the idle loop instruction count. This value, saved in the global variable CLK_D_idletime, is read by the host and used in the CPU load calculation. By default, the instruction count includes all IDL functions, not just LNK_dataPump, RTA_dispatcher, and IDL_cpuLoad. You can remove an IDL function from the calculation by setting the "Include in CPU load calibration" property for an IDL object to false.

  Remember that functions included in the calibration are run before the main() function runs. These functions should not access data structures that are not initialized before the main() function runs. In particular, functions that perform any of the following actions should not be included in the idle loop calibration:
  - enabling hardware interrupts or the SWI or TSK schedulers
  - using CLK APIs to get the time
  - accessing PIP objects
  - blocking tasks
  - creating dynamic objects

  **Tconf Name:** AUTOCALCULATE  
  **Type:** Bool  
  **Example:**  
  ```  
  bios.IDL.AUTOCALCULATE = true;  
  ```

- **Idle Loop Instruction Count.** This is the number of instruction cycles required to perform the IDL loop and the default IDL functions (LNK_dataPump, RTA_dispatcher, and IDL_cpuLoad) that communicate with the host. Since these functions are performed whenever no other processing is needed, background processing is subtracted from the CPU load before it is displayed.

  **Tconf Name:** LOOPINSTCOUNT  
  **Type:** Int32  
  **Example:**  
  ```  
  bios.IDL.LOOPINSTCOUNT = 1000;  
  ```

IDL Object Properties

Each idle function runs to completion before another idle function can run. It is important, therefore, to ensure that each idle function completes (that is, returns) in a timely manner.

To create an IDL object in a configuration script, use the following syntax. The Tconf examples assume the object is created as shown here.

```  
var myIdl = bios.IDL.create("myIdl");  
```  

The following properties can be set for an IDL object:

- **comment.** Type a comment to identify this IDL object.

  **Tconf Name:**  
  **Type:** String  
  **Example:**  
  ```  
  myIdl.comment = "IDL function";  
  ```
• **function.** The function to execute. If this function is written in C and you use the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. (The DSP/BIOS Configuration Tool generates assembly code, which must use leading underscores when referencing C functions or labels.) If you use Tconf, do not add an underscore before the function name; Tconf adds the underscore to call a C function from assembly internally.

  Tconf Name: fxn  
  Type: Extern

  Example: myIdl.fxn = prog.extern("myIDL");

• **Include in CPU load calibration.** You can remove an individual IDL function from the CPU load calculation by setting this property to false. The CPU load calibration is performed only if the "Auto calculate idle loop instruction count" property is true in the IDL Manager Properties. You should remove a function from the calculation if it blocks or depends on variables or structures that are not initialized until the main() function runs.

  Tconf Name: calibration  
  Type: Bool

  Example: myIdl.calibration = true;

• **order.** Set this property for all IDL objects so that the numbers match the sequence in which IDL functions should be executed.

  Tconf Name: order  
  Type: Int16

  Example: myIdl.order = 2;
IDL_run

Make one pass through idle functions

C Interface

Syntax

IDL_run();

Parameters

Void

Return Value

Void

Description

IDL_run makes one pass through the list of configured IDL objects, calling one function after the next. IDL_run returns after all IDL functions have been executed one time. IDL_run is not used by most DSP/BIOS applications since the IDL functions are executed in a loop when the application returns from main. IDL_run is provided to allow easy integration of the real-time analysis features of DSP/BIOS (for example, LOG and STS) into existing applications.

IDL_run must be called to transfer the real-time analysis data to and from the host computer. Though not required, this is usually done during idle time when no HWI or SWI threads are running.

 Note: BIOS_init and BIOS_start must be called before IDL_run to ensure that DSP/BIOS has been initialized. For example, the DSP/BIOS boot file contains the following system calls around the call to main:

```c
BIOS_init(); /* initialize DSP/BIOS */
main();
BIOS_start(); /* start DSP/BIOS */
IDL_loop(); /* call IDL_run in an infinite loop */
```

Constraints and Calling Context

- IDL_run cannot be called by an HWI or SWI function.
2.12 LCK Module

The LCK module is the resource lock manager.

Functions

- LCK_create. Create a resource lock
- LCK_delete. Delete a resource lock
- LCK_pend. Acquire ownership of a resource lock
- LCK_post. Relinquish ownership of a resource lock

Constants, Types, and Structures

typedef struct LCK_Obj *LCK_Handle; /* resource handle */

/* lock object */
typedef struct LCK_Attrs LCK_Attrs;

struct LCK_Attrs {
    Int dummy;
};

LCK_Attrs LCK_ATTRS = {0}; /* default attribute values */

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the LCK Manager Properties and LCK Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameter.

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

Description

The lock module makes available a set of functions that manipulate lock objects accessed through handles of type LCK_Handle. Each lock implicitly corresponds to a shared global resource, and is used to arbitrate access to this resource among several competing tasks.

The LCK module contains a pair of functions for acquiring and relinquishing ownership of resource locks on a per-task basis. These functions are used to bracket sections of code requiring mutually exclusive access to a particular resource.

LCK lock objects are semaphores that potentially cause the current task to suspend execution when acquiring a lock.

LCK Manager Properties

The following global property can be set for the LCK module on the LCK Manager Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the LCK objects.
  
  Tconf Name: OBJMEMSEG Type: Reference
  
  Example: bios.LCK.OBJMEMSEG = prog.get("myMEM");
LCK Object Properties

To create a LCK object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```javascript
var myLck = bios.LCK.create("myLck");
```

The following property can be set for a LCK object in the LCK Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment**. Type a comment to identify this LCK object.
  
  **Tconf Name:** comment  
  **Type:** String  
  **Example:** myLck.comment = "LCK object";
**LCK_create**  
*Create a resource lock*

**C Interface**

Syntax

```c
lock = LCK_create(attrs);
```

Parameters

- **LCK_Attrs** attrs; /* pointer to lock attributes */

Return Value

- **LCK_Handle** lock; /* handle for new lock object */

**Description**

LCK_create creates a new lock object and returns its handle. The lock has no current owner and its corresponding resource is available for acquisition through LCK_pend.

If attrs is NULL, the new lock is assigned a default set of attributes. Otherwise the lock's attributes are specified through a structure of type LCK_Attrs.

---

**Note:** At present, no attributes are supported for lock objects.

---

All default attribute values are contained in the constant LCK_ATR, which can be assigned to a variable of type LCK_Attrs prior to calling LCK_create.

LCK_create calls MEM_alloc to dynamically create the object's data structure. MEM_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2–204.

**Constraints and Calling Context**

- LCK_create cannot be called from a SWI or HWI.
- You can reduce the size of your application program by creating objects with Tconf rather than using the XXX_create functions.

**See Also**

- LCK_delete
- LCK_pend
- LCK_post
**LCK_delete**  
*Delete a resource lock*

**C Interface**

Syntax

```c
LCK_delete(lock);
```

Parameters

- `LCK_Handle lock;` /* lock handle */

Return Value

`Void`

**Description**

`LCK_delete` uses `MEM_free` to free the lock referenced by `lock`.

`LCK_delete` calls `MEM_free` to delete the LCK object. `MEM_free` must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- `LCK_delete` cannot be called from a SWI or HWI.
- No task should be awaiting ownership of the lock.
- No check is performed to prevent `LCK_delete` from being used on a statically-created object. If a program attempts to delete a lock object that was created using `Tconf`, `SYS_error` is called.

**See Also**

- `LCK_create`
- `LCK_pend`
- `LCK_post`
**LCK_pend**

Acquire ownership of a resource lock

**C Interface**

Syntax

```c
status = LCK_pend(lock, timeout);
```

Parameters

- `LCK_Handle lock; /* lock handle */`
- `Uns timeout; /* return after this many system clock ticks */`

Return Value

- `Bool status; /* TRUE if successful, FALSE if timeout */`

**Description**

LCK_pend acquires ownership of lock, which grants the current task exclusive access to the corresponding resource. If lock is already owned by another task, LCK_pend suspends execution of the current task until the resource becomes available.

The task owning lock can call LCK_pend any number of times without risk of blocking, although relinquishing ownership of the lock requires a balancing number of calls to LCK_post.

LCK_pend results in a context switch if this LCK timeout is greater than 0 and the lock is already held by another thread.

LCK_pend returns TRUE if it successfully acquires ownership of lock, returns FALSE if a timeout occurs before it can acquire ownership. LCK_pend returns FALSE if it is called from the context of a SWI or HWI, even if the timeout is zero.

---

**Note:** **RTS functions callable from TSK threads only.** Many run-time support (RTS) functions use lock and unlock functions to prevent reentrancy. However, DSP/BiOS SWI and HWI threads cannot call LCK_pend and LCK_post. As a result, RTS functions that call LCK_pend or LCK_post must not be called in the context of a SWI or HWI.

To determine whether a particular RTS function uses LCK_pend or LCK_post, refer to the source code for that function shipped with Code Composer Studio. The following table lists some RTS functions that call LCK_pend and LCK_post in certain versions of Code Composer Studio:

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>fprintf</td>
<td>Print format string</td>
</tr>
<tr>
<td>printf</td>
<td>Print format string</td>
</tr>
<tr>
<td>vfprintf</td>
<td>Variable print format string</td>
</tr>
<tr>
<td>vsprintf</td>
<td>Variable string print function</td>
</tr>
<tr>
<td>clock</td>
<td>Get current time</td>
</tr>
<tr>
<td>strftime</td>
<td>Format date and time string</td>
</tr>
<tr>
<td>malloc</td>
<td>Allocate memory</td>
</tr>
<tr>
<td>realloc</td>
<td>Reallocate memory</td>
</tr>
<tr>
<td>free</td>
<td>Free memory</td>
</tr>
<tr>
<td>getenv</td>
<td>Get environment variable string</td>
</tr>
<tr>
<td>calloc</td>
<td>Allocate memory (C++)</td>
</tr>
<tr>
<td>rand</td>
<td>Random number generator</td>
</tr>
<tr>
<td>srand</td>
<td>Seed random number generator</td>
</tr>
</tbody>
</table>

The C++ new operator calls malloc, which in turn calls LCK_pend. As a result, the new operator cannot be used in the context of a SWI or HWI thread.

**Constraints and Calling Context**

- The lock must be a handle for a resource lock object created through a prior call to LCK_create.
- LCK_pend should not be called from a SWI or HWI thread.
- LCK_pend should not be called from main().

**See Also**

- LCK_create
- LCK_delete
- LCK_post
LCK_post  Relinquish ownership of a resource LCK

C Interface

Syntax

LCK_post(lock);

Parameters

LCK_Handle lock;  /* lock handle */

Return Value

Void

Description

LCK_post relinquishes ownership of lock, and resumes execution of the first task (if any) awaiting availability of the corresponding resource. If the current task calls LCK_pend more than once with lock, ownership remains with the current task until LCK_post is called an equal number of times.

LCK_post results in a context switch if a higher priority thread is currently pending on the lock.

Constraints and Calling Context

- lock must be a handle for a resource lock object created through a prior call to LCK_create.
- LCK_post should not be called from a SWI or HWI thread.
- LCK_post should not be called from main().

See Also

LCK_create
LCK_delete
LCK_pend
2.13 LOG Module

The LOG module captures events in real time.

Functions

- LOG_disable. Disable the system log.
- LOG_enable. Enable the system log.
- LOG_error. Write a user error event to the system log.
- LOG_event. Append unformatted message to message log.
- LOG_message. Write a user message event to the system log.
- LOG_printf. Append formatted message to message log.
- LOG_reset. Reset the system log.

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the LOG Manager Properties and LOG Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>bufSeg</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>bufLen</td>
<td>EnumInt</td>
<td>64 (0, 8, 16, 32, 64, ..., 32768)</td>
</tr>
<tr>
<td>logType</td>
<td>EnumString</td>
<td>&quot;circular&quot; (&quot;fixed)</td>
</tr>
<tr>
<td>dataType</td>
<td>EnumString</td>
<td>&quot;printf&quot; (&quot;raw data&quot;)</td>
</tr>
<tr>
<td>format</td>
<td>String</td>
<td>&quot;0x%x, 0x%x, 0x%x&quot;</td>
</tr>
</tbody>
</table>

Description

The Event Log is used to capture events in real time while the target program executes. You can use the system log, or create user-defined logs. If the logtype is circular, the log buffer of size buflen contains the last buflen elements. If the logtype is fixed, the log buffer contains the first buflen elements.

The system log stores messages about system events for the types of log tracing you have enabled. See the TRC Module, page 2–442, for a list of events that can be traced in the system log.

You can add messages to user logs or the system log by using LOG_printf or LOG_event. To reduce execution time, log data is always formatted on the host.

LOG_error writes a user error event to the system log. This operation is not affected by any TRC trace bits; an error event is always written to the system log. LOG_message writes a user message event to the system log, provided that both TRC_GBLHOST and TRC_GBLTARG (the host and target trace bits, respectively) traces are enabled.
When a problem is detected on the target, it is valuable to put a message in the system log. This allows you to correlate the occurrence of the detected event with the other system events in time. LOG_error and LOG_message can be used for this purpose.

Log buffers are of a fixed size and reside in data memory. Each log event buffer uses eight words in both the large and huge memory models. Individual events hold four elements (two words per element) in the log’s buffer. The first element holds a sequence number that allows the Event Log to display logs in the correct order. The remaining three elements contain data specified by the call that wrote the message to the log.

See the Code Composer Studio online tutorial for examples of how to use the LOG Manager.

LOG Manager Properties

The following global property can be set for the LOG module in the LOG Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the LOG objects.
  
  **Tconf Name:** OBJMEMSEG
  
  **Type:** Reference
  
  **Example:**
  
  bios.LOG.OBJMEMSEG = prog.get("myMEM");

LOG Object Properties

To create a LOG object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var myLog = bios.LOG.create("myLog");
```

The following properties can be set for a log object on the LOG Object Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this LOG object.
  
  **Tconf Name:** comment
  
  **Type:** String
  
  **Example:**
  
  myLog.comment = "trace LOG";

- **bufseg.** The name of a memory segment to contain the log buffer.
  
  **Tconf Name:** bufSeg
  
  **Type:** Reference
  
  **Example:**
  
  myLog.bufSeg = prog.get("myMEM");

- **buflen.** The length of the log buffer (in words).
  
  **Tconf Name:** buflen
  
  **Options:** 0, 8, 16, 32, 64, ..., 32768
  
  **Example:**
  
  myLog.bufLen = 64;

- **logtype.** The type of the log: circular or fixed. Events added to a full circular log overwrite the oldest event in the buffer, whereas events added to a full fixed log are dropped.
  
  — **Fixed.** The log stores the first messages it receives and stops accepting messages when its message buffer is full.
  
  — **Circular.** The log automatically overwrites earlier messages when its buffer is full. As a result, a circular log stores the last events that occur.

  **Tconf Name:** logType
  
  **Options:** "circular", "fixed"
  
  **Example:**
  
  myLog.logType = "circular";
• **datatype.** Choose printf if you use LOG_printf to write to this log and provide a format string.

  Choose raw data if you want to use LOG_event to write to this log and have the Event Log apply a printf-style format string to all records in the log.

  Tconf Name: `dataType`  
  Type: EnumString  
  Options: "printf", "raw data"  
  Example: `myLog.dataType = "printf";`

• **format.** If you choose raw data as the datatype, type a printf-style format string for this property.

  Provide up to three (3) conversion characters (such as %d) to format words two, three, and four in all records in the log. Do not put quotes around the format string. The format string can use %d, %u, %x, %o, %s, %r, and %p conversion characters; it cannot use other types of conversion characters.


  Tconf Name: `format`  
  Type: String  
  Example: `myLog.format = "0x%x, 0x%x, 0x%x";`
# LOG_disable

Disables a message log

## C Interface

**Syntax**

```c
LOG_disable(log);
```

**Parameters**

- `LOG_Handle log; /* log object handle */`

**Return Value**

Void

**Reentrant**

No

**Description**

`LOG_disable` disables the logging mechanism and prevents the log buffer from being modified.

**Example**

```c
LOG_disable(&trace);
```

**See Also**

- `LOG_enable`
- `LOG_reset`
LOG_enable

Enable a message log

C Interface

Syntax

    LOG_enable(log);

Parameters

    LOG_Handle log; /* log object handle */

Return Value

    Void

Reentrant

    no

Description

    LOG_enable enables the logging mechanism and allows the log buffer to be modified.

Example

    LOG_enable(&trace);

See Also

    LOG_disable
    LOG_reset
LOG_error

Write an error message to the system log

C Interface

Syntax
LOG_error(format, arg0);

Parameters
String format; /* printf-style format string */
Arg arg0; /* copied to second word of log record */

Return Value
Void

Reentrant
yes

Description
LOG_error writes a program-supplied error message to the system log, which is defined in the default configuration by the LOG_system object. LOG_error is not affected by any TRC bits; an error event is always written to the system log.

The format argument can contain any of the conversion characters supported for LOG_printf. See LOG_printf for details.

Example
Void UTL_doError(String s, Int errno)
{
    LOG_error("SYS_error called: error id = 0x%x", errno);
    LOG_error("SYS_error called: string = '%s'", s);
}

See Also
LOG_event
LOG_message
LOG_printf
TRC_disable
TRC_enable
**LOG_event**

Append an unformatted message to a message log

**C Interface**

Syntax

```c
LOG_event(log, arg0, arg1, arg2);
```

Parameters

- **LOG_Handle** `log;` /* log object handle */
- **Arg** `arg0;` /* copied to second word of log record */
- **Arg** `arg1;` /* copied to third word of log record */
- **Arg** `arg2;` /* copied to fourth word of log record */

Return Value

**Void**

**Reentrant**

**yes**

**Description**

LOG_event copies a sequence number and three arguments to the specified log buffer. Each log message uses four words (eight words for 'C55x large and huge models). The contents of the four words written by LOG_event are shown here:

```
LOG_event
```

<table>
<thead>
<tr>
<th>Sequence #</th>
<th>arg0</th>
<th>arg1</th>
<th>arg2</th>
</tr>
</thead>
</table>

You can format the log by using LOG_printf instead of LOG_event.

If you want the Event Log to apply the same printf-style format string to all records in the log, use Tconf to choose raw data for the datatype property and type a format string for the format property (see “LOG Object Properties” on page 184).

If the logtype is circular, the log buffer of size buflen contains the last buflen elements. If the logtype is fixed, the log buffer contains the first buflen elements.

Any combination of threads can write to the same log. Internally, hardware interrupts are temporarily disabled during a call to LOG_event. Log messages are never lost due to thread preemption.

**Example**

```c
LOG_event(&trace, (Arg)value1, (Arg)value2,
          (Arg)CLK_gettime());
```

**See Also**

- LOG_error
- LOG_printf
- TRC_disable
- TRC_enable
LOG_message  Write a program-supplied message to the system log

C Interface

Syntax

    LOG_message(format, arg0);

Parameters

String          format;  /* printf-style format string */
Arg             arg0;     /* copied to second word of log record */

Return Value

Void

Reentrant

yes

Description

LOG_message writes a program-supplied message to the system log, provided that both the host and
target trace bits are enabled.

The format argument passed to LOG_message can contain any of the conversion characters supported
for LOG_printf. See LOG_printf, page 2–191, for details.

Example

    Void UTL_doMessage(String s, Int errno)
    {
        LOG_message("SYS_error called: error id = 0x%x", errno);
        LOG_message("SYS_error called: string = '%s'", s);
    }

See Also

    LOG_error
    LOG_event
    LOG_printf
    TRC_disable
    TRC_enable
**LOG_printf**

*Append a formatted message to a message log*

**C Interface**

**Syntax**

```c
LOG_printf(log, format);
```

or

```c
LOG_printf(log, format, arg0);
```

or

```c
LOG_printf(log, format, arg0, arg1);
```

**Parameters**

- **LOG_Handle**
  - log; /* log object handle */
- **String**
  - format; /* printf format string */
- **Arg**
  - arg0; /* value for first format string token */
  - arg1; /* value for second format string token */

**Return Value**

Void

**Reentrant**

yes

**Description**

As a convenience for C (as well as assembly language) programmers, the LOG module provides a variation of the ever-popular printf. LOG_printf copies a sequence number, the format address, and two arguments to the specified log buffer.

To reduce execution time, log data is always formatted on the host. The format string is stored on the host and accessed by the Event Log.

The arguments passed to LOG_printf must be integers, strings, or a pointer (if the special %r or %p conversion character is used).

Casting arg0 and arg1 using the Arg type causes an erroneous value to be printed. To print the value correctly, do not cast these parameters. This constraint applies even though the LOG_printf function defines arg0 and arg1 as Arg type.

The format string can use any conversion character found in Table Table 2-4.

<table>
<thead>
<tr>
<th>Conversion Character</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>%d</td>
<td>Signed integer</td>
</tr>
<tr>
<td>%u</td>
<td>Unsigned integer</td>
</tr>
<tr>
<td>%x</td>
<td>Unsigned hexadecimal integer</td>
</tr>
<tr>
<td>%o</td>
<td>Unsigned octal integer</td>
</tr>
</tbody>
</table>
LOG_printf does not provide a conversion character for code pointers. If you are using the 'C55x large model, you can use the %p character to print code pointers. For example, the following is supported:

```c
char *msg = "Hello world!";
LOG_printf(&trace, "%s", msg);
```

However, the following example is not supported:

```c
char msg[100];
strcpy(msg, "Hello world!");
LOG_printf(&trace, "%s", msg);
```

If the string appears in the COFF file and a pointer to the string is passed to LOG_printf, then the string in the COFF file is used by the Event Log to generate the output.

If the string can not be found in the COFF file, the format string is replaced with *** ERROR: 0x%x 0x%x ***\n, which displays all arguments in hexadecimal.

### %s Character string

This character can only be used with constant string pointers. That is, the string must appear in the source and be passed to LOG_printf. For example, the following is supported:

```c
char *msg = "Hello world!";
LOG_printf(&trace, "%s", msg);
```

However, the following example is not supported:

```c
char msg[100];
strcpy(msg, "Hello world!");
LOG_printf(&trace, "%s", msg);
```

If the string appears in the COFF file and a pointer to the string is passed to LOG_printf, then the string in the COFF file is used by the Event Log to generate the output.

If the string can not be found in the COFF file, the format string is replaced with *** ERROR: 0x%x 0x%x ***\n, which displays all arguments in hexadecimal.

### %r Symbol from symbol table

This is an extension of the standard printf format tokens. This character treats its parameter as a pointer to be looked up in the symbol table of the executable and displayed. That is, %r displays the symbol (defined in the executable) whose value matches the value passed to %r. For example:

```c
Int testval = 17;
LOG_printf("%r = %d", &testval, testval);
```

displays:

```
testval = 17
```

If no symbol is found for the value passed to %r, the Event Log uses the string <unknown symbol>.

### %p data pointer

LOG_printf does not provide a conversion character for code pointers. If you are using the 'C55x large model, you can use the %p character to print code pointers.

Since LOG_printf does not provide a conversion character for long integers, you may want to use 0x%p instead. Another solution is to use bitwise shifting and ANDing to break a 32-bit number into its 16-bit counterparts. In following example, (Int)(maincount >> 16) is the upper 16 bits of maincount shifted into the 16-bits of an Int. And, (Int)(maincount & 0xffff) is the lower 16 bits of maincount.

```c
LOG_printf(&trace, "total count = 0x%04x%04x",
    (Int)(maincount >> 16),
    (Int)(maincount & 0xffff));
```

The 0x%04x%04x format string used in this example causes a literal string of "0x" to precede the value to indicate that it is a hex value. Then, each %04x tells LOG_printf to display the value as hex, padding to 4 characters with leading zeros.

If you want the Event Log to apply the same printf-style format string to all records in the log, use Tconf to choose raw data for the datatype property of this LOG object and typing a format string for the format property.
Each log message uses words (eight words for ‘C55x large and huge models). The contents of the message written by LOG_printf are shown here:

<table>
<thead>
<tr>
<th>LOG_printf</th>
<th>Sequence #</th>
<th>arg0</th>
<th>arg1</th>
<th>Format address</th>
</tr>
</thead>
</table>

You configure the characteristics of a log in Tconf. If the logtype is circular, the log buffer of size buflen contains the last buflen elements. If the logtype is fixed, the log buffer contains the first buflen elements.

Any combination of threads can write to the same log. Internally, hardware interrupts are temporarily disabled during a call to LOG_printf. Log messages are never lost due to thread preemption.

**Constraints and Calling Context**

- LOG_printf supports only 0, 1, or 2 arguments after the format string.
- No compilation error is reported if a call to LOG_printf casts an parameter as Arg or attempts to print a code pointer using a single parameter. These actions cause erroneous output on ‘C55x.

**Example**

```c
LOG_printf(&trace, "hello world");
LOG_printf(&trace, "Size of Int is: %d", sizeof(Int));
```

**See Also**

LOG_error
LOG_event
TRC_disable
TRC_enable
**LOG_reset**  
*Reset a message log*

**C Interface**

**Syntax**

```
LOG_reset(log);
```

**Parameters**

- `LOG_Handle    log        /* log object handle */`

**Return Value**

*Void*

**Reentrant**

*no*

**Description**

`LOG_reset` enables the logging mechanism and allows the log buffer to be modified starting from the beginning of the buffer, with sequence number starting from 0.

`LOG_reset` does not disable interrupts or otherwise protect the log from being modified by an HWI or other thread. It is therefore possible for the log to contain inconsistent data if `LOG_reset` is preempted by an HWI or other thread that uses the same log.

**Example**

```
LOG_reset(&trace);
```

**See Also**

- `LOG_disable`
- `LOG_enable`
2.14 MBX Module

The MBX module is the mailbox manager.

Functions

- MBX_create. Create a mailbox
- MBX_delete. Delete a mailbox
- MBX_pend. Wait for a message from mailbox
- MBX_post. Post a message to mailbox

Constants, Types, and Structures

```c
typedef struct MBX_Obj *MBX_Handle; /* handle for mailbox object */

struct MBX_Attrs { /* mailbox attributes */
    Int segid;
};

MBX_Attrs MBX_ATTRS = {/* default attribute values */
    0,
};
```

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the MBX Manager Properties and MBX Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>messageSize</td>
<td>Int16</td>
<td>1</td>
</tr>
<tr>
<td>length</td>
<td>Int16</td>
<td>1</td>
</tr>
<tr>
<td>elementSeg</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

Description

The MBX module makes available a set of functions that manipulate mailbox objects accessed through handles of type MBX_Handle. Mailboxes can hold up to the number of messages specified by the Mailbox Length property in Tconf.

MBX_pend waits for a message from a mailbox. Its timeout parameter allows the task to wait until a timeout. A timeout value of SYS_FOREVER causes the calling task to wait indefinitely for a message. A timeout value of zero (0) causes MBX_pend to return immediately. MBX_pend’s return value indicates whether the mailbox was signaled successfully.
MBX_post is used to send a message to a mailbox. The timeout parameter to MBX_post specifies the amount of time the calling task waits if the mailbox is full. If a task is waiting at the mailbox, MBX_post removes the task from the queue and puts it on the ready queue. If no task is waiting and the mailbox is not full, MBX_post simply deposits the message and returns.

**MBX Manager Properties**

The following global property can be set for the MBX module on the MBX Manager Properties dialog in the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the MBX objects created with Tconf.
  - Tconf Name: OBJMEMSEG
  - Type: Reference
  - Example: `bios.MBX.OBJMEMSEG = prog.get("myMEM");`

**MBX Object Properties**

To create an MBX object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```
var myMbx = bios.MBX.create("myMbx");
```

The following properties can be set for an MBX object in the MBX Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this MBX object.
  - Tconf Name: comment
  - Type: String
  - Example: `myMbx.comment = "my MBX";`

- **Message Size.** The size (in MADUs) of the messages this mailbox can contain.
  - Tconf Name: messageSize
  - Type: Int16
  - Example: `myMbx.messageSize = 1;`

- **Mailbox Length.** The number of messages this mailbox can contain.
  - Tconf Name: length
  - Type: Int16
  - Example: `myMbx.length = 1;`

- **Element memory segment.** The memory segment to contain the mailbox data buffers.
  - Tconf Name: elementSeg
  - Type: Reference
  - Example: `myMbx.elementSeg = prog.get("myMEM");`
MBX_create

Create a mailbox

C Interface

Syntax

```c
mbx = MBX_create(msgsize, mbxlength, attrs);
```

Parameters

- `size_t msgsize; /* size of message */`
- `Uns mbxlength; /* length of mailbox */`
- `MBX_Attrs *attrs; /* pointer to mailbox attributes */`

Return Value

- `MBX_Handle mbx; /* mailbox object handle */`

Description

MBX_create creates a mailbox object which is initialized to contain up to mbxlength messages of size msgsize. If successful, MBX_create returns the handle of the new mailbox object. If unsuccessful, MBX_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS_error, and SYS_error causes an abort).

If attrs is NULL, the new mailbox is assigned a default set of attributes. Otherwise, the mailbox’s attributes are specified through a structure of type MBX_Attrs.

All default attribute values are contained in the constant MBX_ATTRS, which can be assigned to a variable of type MBX_Attrs prior to calling MBX_create.

MBX_create calls MEM_alloc to dynamically create the object’s data structure. MEM_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2–204.

Constraints and Calling Context

- MBX_create cannot be called from a SWI or HWI.
- You can reduce the size of your application program by creating objects with Tconf rather than using the XXX_create functions.

See Also

- MBX_delete
- SYS_error
MBX_delete  
*Delete a mailbox*

**C Interface**

**Syntax**

```c
MBX_delete(mbx);
```

**Parameters**

- `MBX_Handle mbx; /* mailbox object handle */`

**Return Value**

`Void`

**Description**

`MBX_delete` frees the mailbox object referenced by `mbx`.

`MBX_delete` calls `MEM_free` to delete the MBX object. `MEM_free` must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- No tasks should be pending on `mbx` when `MBX_delete` is called.
- `MBX_delete` cannot be called from a SWI or HWI.
- No check is performed to prevent `MBX_delete` from being used on a statically-created object. If a program attempts to delete a mailbox object that was created using `Tconf`, `SYS_error` is called.

**See Also**

- `MBX_create`
### MBX_pend

**Wait for a message from mailbox**

**C Interface**

**Syntax**

```c
status = MBX_pend(mbx, msg, timeout);
```

**Parameters**

- `MBX_Handle mbx; /* mailbox object handle */`
- `Ptr msg; /* message pointer */`
- `Uns timeout; /* return after this many system clock ticks */`

**Return Value**

- `Bool status; /* TRUE if successful, FALSE if timeout */`

**Description**

If the mailbox is not empty, `MBX_pend` copies the first message into `msg` and returns TRUE. Otherwise, `MBX_pend` suspends the execution of the current task until `MBX_post` is called or the timeout expires. The actual time of task suspension can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

If timeout is `SYS_FOREVER`, the task remains suspended until `MBX_post` is called on this mailbox. If timeout is 0, `MBX_pend` returns immediately.

If timeout expires (or timeout is 0) before the mailbox is available, `MBX_pend` returns FALSE. Otherwise `MBX_pend` returns TRUE.

A task switch occurs when calling `MBX_pend` if the mailbox is empty and timeout is not 0, or if a higher priority task is blocked on `MBX_post`.

**Constraints and Calling Context**

- This API can be called from a TSK with any timeout value, but if called from an HWI or SWI the timeout must be 0.
- If you need to call `MBX_pend` within a TSK_disable/TSK_enable block, you must use a timeout of 0.
- `MBX_pend` cannot be called from the program’s main() function.

**See Also**

- `MBX_post`
MBX_post

Post a message to mailbox

C Interface

Syntax

\[
\text{status} = \text{MBX\_post}(\text{mbx}, \text{msg}, \text{timeout});
\]

Parameters

- `MBX\_Handle mbx; /* mailbox object handle */`
- `Ptr msg; /* message pointer */`
- `Uns timeout; /* return after this many system clock ticks */`

Return Value

- `Bool status; /* TRUE if successful, FALSE if timeout */`

Description

MBX_post checks to see if there are any free message slots before copying msg into the mailbox. MBX_post readies the first task (if any) waiting on mbx.

If the mailbox is full and timeout is SYS\_FOREVER, the task remains suspended until MBX\_pend is called on this mailbox. If timeout is 0, MBX_post returns immediately. Otherwise, the task is suspended for timeout system clock ticks. The actual time of task suspension can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

If timeout expires (or timeout is 0) before the mailbox is available, MBX_post returns FALSE. Otherwise MBX_post returns TRUE.

A task switch occurs when calling MBX_post if a higher priority task is made ready to run, or if there are no free message slots and timeout is not 0.

Constraints and Calling Context

- If you need to call MBX_post within a TSK\_disable/TSK\_enable block, you must use a timeout of 0.
- This API can be called from a TSK with any timeout value, but if called from an HWI or SWI the timeout must be 0.
- MBX_post can be called from the program’s main() function. However, the number of calls should not be greater than the number of messages the mailbox can hold. Additional calls have no effect.

See Also

- MBX\_pend
2.15 MEM Module

The MEM module is the memory segment manager.

Functions

- MEM_alloc. Allocate from a memory segment.
- MEMcalloc. Allocate and initialize to 0.
- MEM_define. Define a new memory segment.
- MEM_free. Free a block of memory.
- MEM_getBaseAddress. Get base address of memory heap.
- MEM_increaseTableSize. Increase the internal MEM table size.
- MEM_redifine. Redefine an existing memory segment.
- MEM_stat. Return the status of a memory segment.
- MEM_undefine. Undefine an existing memory segment.
- MEM_valloc. Allocate and initialize to a value.

Constants, Types, and Structures

```
MEM->MALLOCSEG = 0;    /* segid for malloc, free */
#define MEM_HEADERSIZE /* free block header size */
#define MEM_HEADERMASK /* mask to align on MEM_HEADERSIZE */
#define MEM_ILLEGAL    /* illegal memory address */
MEM_Attrs MEM_ATTRS ={ /* default attribute values */
    0
};
typedef struct MEM_Segment {
    Ptr       base;     /* base of the segment */
    MEM_sizep length;   /* size of the segment */
    Uns       space;    /* memory space */
} MEM_Segment;

typedef struct MEM_Stat {
    MEM_sizep   size;   /* original size of segment */
    MEM_sizep   used;   /* MADUs used in segment */
    size_t      length; /* largest contiguous block */
} MEM_Stat;

typedef unsigned long MEM_sizep;
```

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the MEM Manager Properties and MEM Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>C55x Name</th>
<th>Type</th>
<th>Default</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>REUSECODESPACE</td>
<td>Bool</td>
<td>false</td>
<td></td>
</tr>
<tr>
<td>ARGSSIZE</td>
<td>Numeric</td>
<td>x0008</td>
<td></td>
</tr>
<tr>
<td>STACKSIZE</td>
<td>Numeric</td>
<td>0x0400</td>
<td></td>
</tr>
<tr>
<td>C55x Name</td>
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<td>prog.get(&quot;SARAM&quot;)</td>
<td></td>
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<tr>
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<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
<td></td>
</tr>
<tr>
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<tr>
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<tr>
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<td>HWSEG</td>
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<td>TEXTSEG</td>
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<td>Reference</td>
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<td>CONSTSEG</td>
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<td>Reference</td>
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<td>LOADBIOSSEG</td>
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<td>LOADSYSNITSEG</td>
<td>Reference</td>
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<td></td>
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<td>LOADPINITSEG</td>
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<td>LOADCONSTSEG</td>
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<td>LOADHWSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
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<td>LOADHWIVECSEG</td>
<td>Reference</td>
<td>prog.get(&quot;VECT&quot;)</td>
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<tr>
<td>LOADRTDTEXTSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
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</table>
Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
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<tr>
<td>comment</td>
<td>String</td>
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<td>base</td>
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</tr>
<tr>
<td>len</td>
<td>Numeric</td>
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<tr>
<td>createHeap</td>
<td>Bool</td>
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<tr>
<td>heapSize</td>
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<td>enableHeapLabel</td>
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<td>heapLabel</td>
<td>Extern</td>
<td>prog.extern(&quot;segment_name&quot;,&quot;asm&quot;)</td>
</tr>
<tr>
<td>space</td>
<td>EnumString</td>
<td>&quot;code/data&quot; (&quot;io&quot;)</td>
</tr>
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</table>

Description
The MEM module provides a set of functions used to allocate storage from one or more disjointed segments of memory. These memory segments are specified with Tconf.

MEM always allocates an even number of MADUs and always aligns buffers on an even boundary. This behavior is used to insure that free buffers are always at least two MADUs in length. This behavior does not preclude you from allocating two 512 buffers from a 1K region of on-device memory, for example. It does, however, mean that odd allocations consume one more MADU than expected.

If small code size is important to your application, you can reduce code size significantly by removing the capability to dynamically allocate and free memory. To do this, set the "No Dynamic Memory Heaps" property for the MEM manager to true. If you remove this capability, your program cannot call any of the MEM functions or any object creation functions (such as TSK_create). You need to create all objects to be used by your program statically (with Tconf). You can also create or remove the dynamic memory heap from an individual memory segment in the configuration.

Software modules in DSP/BIOS that allocate storage at run-time use MEM functions; DSP/BIOS does not use the standard C function malloc. DSP/BIOS modules use MEM to allocate storage in the segment selected for that module with Tconf.

The MEM Manager property, Segment for malloc()/free(), is used to implement the standard C function malloc. These functions actually use the MEM functions (with segid = Segment for malloc/free) to allocate and free memory.

Note: The MEM module does not set or configure hardware registers associated with a DSP’s memory subsystem. Such configuration is the responsibility of the user and is typically handled by software loading programs, or in the case of Code Composer Studio, the startup or menu options. For example, to access external memory on a c6000 platform, the External Memory Interface (EMIF) registers must first be set appropriately before any access. The earliest opportunity for EMIF initialization within DSP/BIOS would be during the user initialization hook (see Global Settings in the API Reference Guide).

MEM Manager Properties
The DSP/BIOS Memory Section Manager allows you to specify the memory segments required to locate the various code and data sections of a DSP/BIOS application.
MEM Module

The following global properties can be set for the MEM module in the MEM Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

General tab

- **Reuse Startup Code Space.** If this property is set to true, the startup code section (.sysinit) can be reused after startup is complete.
  
  **Tconf Name:** REUSECODESPACE  **Type:** Bool
  
  **Example:**
  
  ```
  bios.MEM.REUSECODESPACE = false;
  ```

- **Argument Buffer Size.** The size of the .args section. The .args section contains the argc, argv, and envp arguments to the program's main() function. Code Composer loads arguments for the main() function into the .args section. The .args section is parsed by the boot file.
  
  **Tconf Name:** ARGSSIZE  **Type:** Numeric
  
  **Example:**
  
  ```
 bios.MEM.ARGSSIZE = 0x0004;
  ```

- **Stack Size.** The size of the data stack in MADUs. The upper-left corner of the DSP/BIOS Configuration Tool window shows the estimated minimum global stack size required for this application (as a decimal number).

  This size is shown as a hex value in Minimum Addressable Data Units (MADUs). An MADU is the smallest unit of data storage that can be read or written by the CPU. For the c5000 this is a 16-bit word.

  **Tconf Name:** STACKSIZE  **Type:** Numeric
  
  **Example:**
  
  ```
  bios.MEM.STACKSIZE = 0x0400;
  ```

- **System Stack Size (MADUs).** The size of the system stack in MADUs, applicable only on the C55x device.

  **Tconf Name:** SYSSTACKSIZE  **Type:** Numeric
  
  **Example:**
  
  ```
  bios.MEM.SYSSTACKSIZE = 0x0100;
  ```

- **No Dynamic Memory Heaps.** Put a checkmark in this box to completely disable the ability to dynamically allocate memory and the ability to dynamically create and delete objects. If this property is set to true, the program may not call the MEM_alloc, MEM_valloc, MEM_calloc, and malloc or the XXX_create function for any DSP/BIOS module. If this property is set to true, the Segment For DSP/BIOS Objects, Segment for malloc()/free(), and Stack segment for dynamic tasks properties are set to MEM_NULL.

  When you set this property to true, heaps already specified in MEM segments are removed from the configuration. If you later reset this property to false, recreate heaps by configuring properties for individual MEM objects as needed.

  **Tconf Name:** NOMEMORYHEAPS  **Type:** Bool
  
  **Example:**
  
  ```
  bios.MEM.NOMEMORYHEAPS = false;
  ```

- **Segment For DSP/BIOS Objects.** The default memory segment to contain objects created at runtime with an XXX_create function. The XXX_Attrs structure passed to the XXX_create function can override this default. If you select MEM_NULL for this property, creation of DSP/BIOS objects at runtime via the XXX_create functions is disabled.

  **Tconf Name:** BIOSOBJSEG  **Type:** Reference
  
  **Example:**
  
  ```
  bios.MEM.BIOSOBJSEG = prog.get("myMEM");
  ```
• **Segment For malloc() / free().** The memory segment from which space is allocated when a program calls malloc and from which space is freed when a program calls free. If you select MEM_NULL for this property, dynamic memory allocation at run-time is disabled.

  Tconf Name: MALLOCSEG  
  Type: Reference  
  Example: bios.MEM.MALLOCSEG = prog.get("myMEM");

** BIOS Data tab **

• **Argument Buffer Section (.args).** The memory segment containing the .args section.

  Tconf Name: ARGSSEG  
  Type: Reference  
  Example: bios.MEM.ARGSSEG = prog.get("myMEM");

• **Stack Section (.stack).** The memory segment containing the data stack. This segment should be located in RAM. The platform architecture requires that both the user and system stacks (pointed to by the XSP and XSSP registers, respectively) reside in the same 64K page of memory, that is, the upper 7 bits of the stack address (SPH) are shared.

  Tconf Name: STACKSEG  
  Type: Reference  
  Example: bios.MEM.STACKSEG = prog.get("myMEM");

• **System Stack Section (.sysstack).** The memory segment containing the system stack, applicable only on the C55x device.

  Tconf Name: SYSSTACKSEG  
  Type: Reference  
  Example: bios.MEM.SYSSTACKSEG = prog.get("myMEM");

• **DSP/BIOS Init Tables (.gblinit).** The memory segment containing the DSP/BIOS global initialization tables.

  Tconf Name: GBLINITSEG  
  Type: Reference  
  Example: bios.MEM.GBLINITSEG = prog.get("myMEM");

• **TRC Initial Value (.trcdata).** The memory segment containing the TRC mask variable and its initial value. This segment must be placed in RAM.

  Tconf Name: TRCDATASEG  
  Type: Reference  
  Example: bios.MEM.TRCDATASEG = prog.get("myMEM");

• **DSP/BIOS Kernel State (.sysdata).** The memory segment containing system data about the DSP/BIOS kernel state.

  Tconf Name: SYSDATASEG  
  Type: Reference  
  Example: bios.MEM.SYSDATASEG = prog.get("myMEM");

• **DSP/BIOS Conf Sections (.obj).** The memory segment containing configuration properties that can be read by the target program.

  Tconf Name: OBJSEG  
  Type: Reference  
  Example: bios.MEM.OBJSEG = prog.get("myMEM");

** BIOS Code tab **

• **BIOS Code Section (.bios).** The memory segment containing the DSP/BIOS code.

  Tconf Name: BIOSSEG  
  Type: Reference  
  Example: bios.MEM.BIOSSEG = prog.get("myMEM");
MEM Module

- **Startup Code Section (.sysinit)**. The memory segment containing DSP/BIOS startup initialization code; this memory can be reused after main starts executing.
  
  Tconf Name: SYSINITSEG  
  Type: Reference
  
  Example:
  
  ```
  bios.MEM(SYSINITSEG = prog.get("myMEM");
  ```

- **Function Stub Memory (.hwi)**. The memory segment containing dispatch code for HWIs that are configured to be monitored in the HWI Object Properties.
  
  Tconf Name: HWISEG  
  Type: Reference
  
  Example:
  
  ```
  bios.MEM(HWISEG = prog.get("myMEM");
  ```

- **Interrupt Service Table Memory (.hwi_vec)**. The memory segment containing the Interrupt Service Table (IST).
  
  Tconf Name: HWIVECSEG  
  Type: Reference
  
  Example:
  
  ```
  bios.MEM(HWIVECSEG = prog.get("myMEM");
  ```

- **RTDX Text Segment (.rtdx_text)**. The memory segment containing the code sections for the RTDX module.
  
  Tconf Name: RTDXTEXTSEG  
  Type: Reference
  
  Example:
  
  ```
  bios.MEM(RTDXTEXTSEG = prog.get("myMEM");
  ```

Compiler Sections tab

- **User .cmd File For Compiler Sections**. Put a checkmark in this box if you want to have full control over the memory used for the sections that follow. You must then create a linker command file that begins by including the linker command file created by the configuration. Your linker command file should then assign memory for the items normally handled by the following properties. See the *TMS320C54x Optimizing Compiler User's Guide*, (literature number SPRU103E) for more details.
  
  Tconf Name: USERCOMMANDFILE  
  Type: Bool
  
  Example:
  
  ```
  bios.MEM(USERCOMMANDFILE = false;
  ```

- **Text Section (.text)**. The memory segment containing the executable code, string literals, and compiler-generated constants. This segment can be located in ROM or RAM.
  
  Tconf Name: TEXTSEG  
  Type: Reference
  
  Example:
  
  ```
  bios.MEM(TEXTSEG = prog.get("myMEM");
  ```

- **Switch Jump Tables (.switch)**. The memory segment containing the jump tables for switch statements. This segment can be located in ROM or RAM.
  
  Tconf Name: SWITCHSEG  
  Type: Reference
  
  Example:
  
  ```
  bios.MEM(SWITCHSEG = prog.get("myMEM");
  ```

- **C Variables Section (.bss)**. The memory segment containing global and static C variables. At boot or load time, the data in the .cinit section is copied to this segment. This segment should be located in RAM.
  
  Tconf Name: BSSSEG  
  Type: Reference
  
  Example:
  
  ```
  bios.MEM(BSSSEG = prog.get("myMEM");
  ```

- **Data Initialization Section (.cinit)**. The memory segment containing tables for explicitly initialized global and static variables and constants. This segment can be located in ROM or RAM.
  
  Tconf Name: CINITSEG  
  Type: Reference
  
  Example:
  
  ```
  bios.MEM(CINITSEG = prog.get("myMEM");
  ```
• **C Function Initialization Table (.pinit)**. The memory segment containing the table of global object constructors. Global constructors must be called during program initialization. The C/C++ compiler produces a table of constructors to be called at startup. The table is contained in a named section called .pinit. The constructors are invoked in the order that they occur in the table. This segment can be located in ROM or RAM.

  Tconf Name: PINITSEG  
  Type: Reference  
  Example: bios.MEM.PINITSEG = prog.get("myMEM");

• **Constant Sections (.const, .printf)**. These sections can be located in ROM or RAM. The .const section contains string constants and data defined with the const C qualifier. The DSP/BIOS .printf section contains other constant strings used by the Real-Time Analysis tools. The .printf section is not loaded onto the target. Instead, the (COPY) directive is used for this section in the .cmd file. The .printf section is managed along with the .const section, since it must be grouped with the .const section to make sure that no addresses overlap. If you specify these sections in your own .cmd file, you'll need to do something like the following:

  GROUP {  
    .const: {}  
    .printf (COPY): {}  
  } > IRAM

  Tconf Name: CONSTSEG  
  Type: Reference  
  Example: bios.MEM.CONSTSEG = prog.get("myMEM");

• **Data Section (.data)**. This memory segment contains program data. This segment can be located in ROM or RAM.

  Tconf Name: DATASEG  
  Type: Reference  
  Example: bios.MEM.DATASEG = prog.get("myMEM");

• **Data Section (.cio)**. This memory segment contains C standard I/O buffers.

  Tconf Name: CIOSEG  
  Type: Reference  
  Example: bios.MEM.CIOSEG = prog.get("myMEM");

**Load Address tab**

• **Specify Separate Load Addresses**. If you put a checkmark in this box, you can select separate load addresses for the sections listed on this tab.

  Load addresses are useful when, for example, your code must be loaded into ROM, but would run faster in RAM. The linker allows you to allocate sections twice: once to set a load address and again to set a run address.

  If you do not select a separate load address for a section, the section loads and runs at the same address.

  If you do select a separate load address, the section is allocated as if it were two separate sections of the same size. The load address is where raw data for the section is placed. References to items in the section refer to the run address. The application must copy the section from its load address to its run address. For details, see the topics on Runtime Relocation and the .label Directive in the Code Generation Tools help or manual.

  Tconf Name: ENABLELOADADDR  
  Type: Bool  
  Example: bios.MEM.ENABLELOADADDR = false;
• **Load Address - BIOS Code Section (.bios).** The memory segment containing the load allocation of the section that contains DSP/BIOS code.
  
  Tconf Name: LOADBIOSSEG Type: Reference
  
  Example: `bios.MEM.LOADBIOSSEG = prog.get("myMEM");`

• **Load Address - Startup Code Section (.sysinit).** The memory segment containing the load allocation of the section that contains DSP/BIOS startup initialization code.
  
  Tconf Name: LOADSYSINITSEG Type: Reference
  
  Example: `bios.MEM.LOADSYSINITSEG = prog.get("myMEM");`

• **Load Address - DSP/BIOS Init Tables (.gblinit).** The memory segment containing the load allocation of the section that contains the DSP/BIOS global initialization tables.
  
  Tconf Name: LOADGBLINITSEG Type: Reference
  
  Example: `bios.MEM.LOADGBLINITSEG = prog.get("myMEM");`

• **Load Address - TRC Initial Value (.trcdata).** The memory segment containing the load allocation of the section that contains the TRC mask variable and its initial value.
  
  Tconf Name: LOADTRCINITSEG Type: Reference
  
  Example: `bios.MEM.LOADTRCINITSEG = prog.get("myMEM");`

• **Load Address - Text Section (.text).** The memory segment containing the load allocation of the section that contains the executable code, string literals, and compiler-generated constants.
  
  Tconf Name: LOADTEXTSEG Type: Reference
  
  Example: `bios.MEM.LOADTEXTSEG = prog.get("myMEM");`

• **Load Address - Switch Jump Tables (.switch).** The memory segment containing the load allocation of the section that contains the jump tables for switch statements.
  
  Tconf Name: LOADSWITCHSEG Type: Reference
  
  Example: `bios.MEM.LOADSWITCHSEG = prog.get("myMEM");`

• **Load Address - Data Initialization Section (.cinit).** The memory segment containing the load allocation of the section that contains tables for explicitly initialized global and static variables and constants.
  
  Tconf Name: LOADCINITSEG Type: Reference
  
  Example: `bios.MEM.LOADCINITSEG = prog.get("myMEM");`

• **Load Address - C Function Initialization Table (.pinit).** The memory segment containing the load allocation of the section that contains the table of global object constructors.
  
  Tconf Name: LOADPINITSEG Type: Reference
  
  Example: `bios.MEM.LOADPINITSEG = prog.get("myMEM");`

• **Load Address - Constant Sections (.const, .printf).** The memory segment containing the load allocation of the sections that contain string constants, data defined with the `const` C qualifier, and other constant strings used by the Real-Time Analysis tools. The `.printf` section is managed along with the `.const` section to make sure that no addresses overlap.
  
  Tconf Name: LOADCONSTSEG Type: Reference
  
  Example: `bios.MEM.LOADCONSTSEG = prog.get("myMEM");`

• **Load Address - Function Stub Memory (.hwi).** The memory segment containing the load allocation of the section that contains dispatch code for HWIs configured to be monitored.
  
  Tconf Name: LOADHWISEG Type: Reference
  
  Example: `bios.MEM.LOADHWISEG = prog.get("myMEM");`
MEM Module

**Load Address - Interrupt Service Table Memory (.hwi_vec)**. The memory segment containing the load allocation of the section that contains the Interrupt Service Table.

- **Tconf Name**: LOADHWIVECSEG
- **Type**: Reference
- **Example**: `bios.MEM.LOADHWIVECSEG = prog.get("myMEM");`

**Load Address - RTDX Text Segment (.rtdx_text)**. The memory segment containing the load allocation of the section that contains the code sections for the RTDX module.

- **Tconf Name**: LOADRTDXTEXTSEG
- **Type**: Reference
- **Example**: `bios.MEM.LOADRTDXTEXTSEG = prog.get("myMEM");`

### MEM Object Properties

A memory segment represents a contiguous length of code or data memory in the address space of the processor.

To create a MEM object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```javascript
var myMem = bios.MEM.create("myMem");
```

The following properties can be set for a MEM object in the MEM Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **`comment`**. Type a comment to identify this MEM object.
  - **Tconf Name**: comment
  - **Type**: String
  - **Example**: `myMem.comment = "my MEM";

- **`base`**. The address at which this memory segment begins. This value is shown in hex.
  - **Tconf Name**: base
  - **Type**: Numeric
  - **Example**: `myMem.base = 0x000000;

- **`len`**. The length of this memory segment in MADUs. This value is shown in hex.
  - **Tconf Name**: len
  - **Type**: Numeric
  - **Example**: `myMem.len = 0x000000;

- **create a heap in this memory**. If this property is set to true, a heap is created in this memory segment. Memory can be allocated dynamically from a heap. In order to remove the heap from a memory segment, you can select another memory segment that contains a heap for properties that dynamically allocate memory in this memory segment. The properties you should check are in the Memory Section Manager (the Segment for DSP/BIOS objects and Segment for malloc/free properties) and the Task Manager (the Default stack segment for dynamic tasks property). If you disable dynamic memory allocation in the Memory Section Manager, you cannot create a heap in any memory segment.
  - **Tconf Name**: createHeap
  - **Type**: Bool
  - **Example**: `myMem.createHeap = true;

- **heap size**. The size of the heap in MADUs to be created in this memory segment. You cannot control the location of the heap within its memory segment except by making the segment and heap the same sizes. Note that if the base of the heap ends up at address 0x0, the base address of the heap is offset by MEM_HEADERSIZE and the heap size is reduced by MEM_HEADERSIZE.
A heap can potentially be sized to cross a 64K page boundary. See the MEM_alloc topic for information about the effects of page boundaries on heaps.

Tconf Name: heapSize Type: Numeric
Example: myMem.heapSize = 0x03f80;

- **enter a user defined heap identifier.** If this property is set to true, you can define your own identifier label for this heap.
  
  Tconf Name: enableHeapLabel Type: Bool
  Example: myMem.enableHeapLabel = false;

- **heap identifier label.** If the property above is set to true, type a name for this segment's heap.
  
  Tconf Name: heapLabel Type: Extern
  Example: myMem.heapLabel = prog.extern("seg_name", "asm");

- **space.** Type of memory segment. This is set to code for memory segments that store programs, and data for memory segments that store program data.
  
  Tconf Name: space Type: EnumString
  Options: "code/data", "io"
  Example: myMem.space = "code/data";

The predefined memory segments in a configuration file, particularly those for external memory, are dependent on the board template you select. In general, Table 2-5 lists segments that can be defined for the c5000:

**Table 2-5: Typical Memory Segments for C5000 Boards**

<table>
<thead>
<tr>
<th>Name</th>
<th>Memory Segment Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>USERREGS</td>
<td>User scratchpad memory</td>
</tr>
<tr>
<td>BIOSREGS</td>
<td>Scratchpad memory reserved for use by DSP/BIOS</td>
</tr>
<tr>
<td>VECT</td>
<td>Interrupt vector table</td>
</tr>
<tr>
<td>IDATA</td>
<td>Internal data RAM</td>
</tr>
<tr>
<td>IPROG</td>
<td>Internal program RAM</td>
</tr>
<tr>
<td>EDATA</td>
<td>External data memory</td>
</tr>
<tr>
<td>EPROG</td>
<td>External program memory</td>
</tr>
</tbody>
</table>
MEM_alloc

Allocate from a memory segment

C Interface

Syntax

    addr = MEM_alloc(segid, size, align);

Parameters

    Int segid; /* memory segment identifier */
    size_t size; /* block size in MADUs */
    size_t align; /* block alignment */

Return Value

    Void *addr; /* address of allocated block of memory */

Description

MEM_alloc allocates a contiguous block of storage from the memory segment identified by segid and returns the address of this block.

The segid parameter identifies the memory segment to allocate memory from. This identifier can be an integer or a memory segment name defined in the configuration. Files created by the configuration define each configured segment name as a variable with an integer value.

The block contains size MADUs and starts at an address that is a multiple of align. If align is 0 or 1, there is no alignment constraint.

MEM_alloc does not initialize the allocated memory locations.

If the memory request cannot be satisfied, MEM_alloc calls SYS_error with SYS_EALLOC and returns MEM_ILLEGAL.

MEM functions that allocate and deallocate memory internally lock the memory by calling the LCK_pend and LCK_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_alloc cannot be called from the context of a SWI or HWI. MEM_alloc checks the context from which it is called. It calls SYS_error and returns MEM_ILLEGAL if it is called from the wrong context.

A number of other DSP/BIOS APIs call MEM_alloc internally, and thus also cannot be called from the context of a SWI or HWI. See the “Function Callability Table” on page 484 for a detailed list of calling contexts for each DSP/BIOS API.

Page Boundary Issues on the 'C55x

On the 'C55x using the large memory model, MEM objects can configure heaps larger than 64K MADUs (16-bit words for 'C55x). However, memory blocks that cross a 64K page boundary cause C compiler errors. (See the TMS320C55x Optimizing C Compiler User’s Guide for details.)

To prevent such errors, you can use the huge memory model. If you use the large memory model, the remainder of this section applies.

When using the large memory model, the MEM module divides heaps that cross page boundaries into memory blocks that do not cross boundaries. As a result, MEM_alloc and MEM_free can only allocate and free memory within a single memory block, and the largest block that MEM_alloc can allocate in any case is 64K words (0x10000).
For example, suppose you create a RAM segment called MYRAM that is 100K words in length. MYRAM has a base address of 2:F000 and a length of 0x19000. The heap within MYRAM is also 100K words and has a heap identifier label of MYSEG. So this heap also has a base address of 2:F000 and ends at 4:7FFF.

To prevent a memory block from crossing a page boundary, the MEM Module separates this heap into the following memory blocks, which are aligned along 64K page boundaries:

![Figure 2-1. MYSEG Heap Initial Memory Map](image)

Suppose your program calls MEM_alloc in the following sequence:

```c
P3 = MEM_alloc(MYSEG, 0xFF80, 0);
P1 = MEM_alloc(MYSEG, 0x6000, 0);
P2 = MEM_alloc(MYSEG, 0x1800, 0);
P4 = MEM_alloc(MYSEG, 0x800, 0);
```

MEM_alloc allocates memory from the first available memory block that is large enough. The memory block with the lowest address is the first available. In our example, the memory block with base address 2:F000 and length 0x1000 is the first available memory block. MEM_alloc gets memory sections from the bottom of a memory block. If the heap does not have enough memory for a particular call to MEM_alloc, that call returns an error and the next call to MEM_alloc is executed.

The results of these calls to MEM_alloc are shown in the figure and list that follow.
P3 = MEM_alloc(MYSEG, 0xFF80, 0);
This call requests 0xFF80 words. The first available block (at 2:F000) has a size of 0x1000; it is too small for 0xFF80. The next block (at 3:0000) has a size of 0x10000; it is large enough to allocate 0xFF80 words. So, P3 points to a block from 3:0080 to 3:FFFF (because MEM_alloc takes memory from the bottom of a memory block).

P1 = MEM_alloc(MYSEG, 0x6000, 0);
This call requests 0x6000 words. The first block has a size of 0x1000, which is still too small. The next block now has only 0x80 words available because of the previous memory allocation. The last memory block has a size of 0x8000, and is large enough for this allocation. So, P1 points to a block from 4:2000 to 4:7FFF.

P2 = MEM_alloc(MYSEG, 0x1800, 0);
This call requests 0x1800 words. Blocks 1 and 2 are again too small. The last block has 0x2000 words remaining, and can accommodate this allocation. So, P2 points to a block from 4:0800 to 4:1FFF.

P4 = MEM_alloc(MYSEG, 0x800, 0);
This call requests 0x800 words. This time, the first block is large enough. So, P4 points to a block from 2:F800 to 2:FFFF.

Consider how this memory map would change if the same MEM_alloc calls were made in the following sequence:

P1 = MEM_alloc(MYSEG, 0x6000, 0);
P2 = MEM_alloc(MYSEG, 0x1800, 0);
P3 = MEM_alloc(MYSEG, 0xFF80, 0);
P4 = MEM_alloc(MYSEG, 0x800, 0);

The results of this modified call sequence are as follows and are shown in Figure 2-3.
**Figure 2-3. MYSEG Memory Map After Modified Allocation**

- P1 is allocated from 3:A000 to 3:FFFF.
- P2 is allocated from 3:8800 to 3:9FFF.
- P3 is not allocated because no unallocated memory blocks are large enough to hold 0xFF80.
- P4 is allocated from 2:F800 to 2:FFFF.

As a result of page boundary limitations on MEM_alloc, you should follow these guidelines when using large heaps and multiple MEM_alloc calls:

- Create a memory segment specifically for a heap. Give the heap the same size as the memory segment so that the base of the memory segment is at the same location as the base of the heap. (You cannot specify the location of the heap within a memory segment if the memory segment is larger than the heap.) If possible, align the memory segment with a page boundary to maximize the size of memory blocks within the heap.

- If possible, allocate larger blocks of memory from the heap first. Previous allocations of small memory blocks can reduce the size of the memory blocks available for large memory allocations.

- Realize that MEMAlloc can fail and call SYS_error even if the heap contain a sufficient absolute amount of unallocated space. This is because the largest free memory block within the heap may be much smaller than the total amount of unallocated memory.

- If your application allocates memory in an unpredictable sequence, use a heap that is much larger than the amount of memory needed.

**Constraints and Calling Context**

- segid must identify a valid memory segment.
- MEM_alloc cannot be called from a SWI or HWI.
- MEM_alloc cannot be called if the TSK scheduler is disabled.
- align must be 0, or a power of 2 (for example, 1, 2, 4, 8).

**See Also**

MEM_calloc
MEM_free
MEM_valloc
MEM_calloc

Allocate from a memory segment and set value to 0

C Interface

Syntax

```
addr = MEM_calloc(segid, size, align)
```

Parameters

```
Int     segid; /* memory segment identifier */
size_t  size; /* block size in MADUs */
size_t  align; /* block alignment */
```

Return Value

```
Void *addr; /* address of allocated block of memory */
```

Description

MEM_calloc is functionally equivalent to calling MEM_valloc with value set to 0. MEM_calloc allocates a contiguous block of storage from the memory segment identified by segid and returns the address of this block.

The segid parameter identifies the memory segment from which memory is to be allocated. This identifier can be an integer or a memory segment name defined in the configuration. The files created by the configuration define each configured segment name as a variable with an integer value.

The block contains size MADUs and starts at an address that is a multiple of align. If align is 0 or 1, there is no alignment constraint.

If the memory request cannot be satisfied, MEM_calloc calls SYS_error with SYS_EALLOC and returns MEM_ILLEGAL.

MEM functions that allocate and deallocate memory internally lock the memory by calling the LCK_pend and LCK_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_calloc cannot be called from the context of a SWI or HWI.

Constraints and Calling Context

- segid must identify a valid memory segment.
- MEM_calloc cannot be called from a SWI or HWI.
- MEM_calloc cannot be called if the TSK scheduler is disabled.
- align must be 0, or a power of 2 (for example, 1, 2, 4, 8).

See Also

MEM_alloc
MEM_free
MEM_valloc
SYS_error
std.h and stdlib.h functions
MEM_define  Define a new memory segment

C Interface

Syntax

```c
segid = MEM_define(base, length, attrs);
```

Parameters

- `Ptr base; /* base address of new segment */`
- `MEM_sizep length; /* length (in MADUs) of new segment */`
- `MEM_Attrs *attrs; /* segment attributes */`

Return Value

- `Int segid; /* ID of new segment */`

Reentrant

- `yes`

Description

MEM_define defines a new memory segment for use by the DSP/BIOS MEM Module.

The new segment contains length MADUs starting at base. A new table entry is allocated to define the segment, and the entry's index into this table is returned as the segid.

The new block should be aligned on a MEM_HEADERSIZE boundary, and the length should be a multiple of MEM_HEADERSIZE.

If attrs is NULL, the new segment is assigned a default set of attributes. Otherwise, the segment's attributes are specified through a structure of type MEM_Attrs.

---

**Note:** No attributes are supported for segments, and the type MEM_Attrs is defined as a dummy structure.

---

If there are undefined slots available in the internal table of memory segment identifiers, one of those slots is (re)used for the new segment. If there are no undefined slots available in the internal table, the table size is increased via MEM_alloc. See MEM_increaseTableSize to manage performance in this situation.

Constraints and Calling Context

- At least one segment must exist at the time MEM_define is called.
- MEM_define internally locks the memory by calling LCK_pend and LCK_post. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_define cannot be called from the context of a SWI or HWI. It can be called from main() or a TSK. The duration that the API holds the memory lock is variable.
- The length parameter must be a multiple of MEM_HEADERSIZE and must be at least equal to MEM_HEADERSIZE.
- The base Ptr cannot be NULL.

See Also

- MEM_redefine
- MEM_undefine
MEM_free

Free a block of memory

C Interface

Syntax

status = MEM_free(segid, addr, size);

Parameters

Int segid; /* memory segment identifier */
Ptr addr; /* block address pointer */
size_t size; /* block length in MADUs*/

Return Value

Bool status; /* TRUE if successful */

Description

MEM_free places the memory block specified by addr and size back into the free pool of the segment specified by segid. The newly freed block is combined with any adjacent free blocks. This space is then available for further allocation by MEM_alloc. The segid can be an integer or a memory segment name defined in the configuration.

MEM functions that allocate and deallocate memory internally lock the memory by calling the LCK_pend and LCK_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_free cannot be called from the context of a SWI or HWI.

Although MEM_free combines newly freed blocks with adjacent free blocks, it does not combine blocks that cross a 64K page boundary. See the MEM_alloc topic for information about the effects of page boundaries on heaps.

Constraints and Calling Context

- addr must be a valid pointer returned from a call to MEM_alloc.
- segid and size are those values used in a previous call to MEM_alloc.
- MEM_free cannot be called by HWI or SWI functions.
- MEM_free cannot be called if the TSK scheduler is disabled.

See Also

MEM_alloc
std.h and stdlib.h functions
MEM_getBaseAddress  Get base address of a memory heap

C Interface

Syntax
addr = MEM_getBaseAddress(segid);

Parameters
Int segid; /* memory segment identifier */

Return Value
Ptr addr; /* heap base address pointer */

Description
MEM_getBaseAddress returns the base address of the memory heap with the segment ID specified by the segid parameter.

Constraints and Calling Context
- The segid can be an integer or a memory segment name defined in the configuration.

See Also
MEM Object Properties
MEM_increasetableSize

Increase the internal MEM table size

C Interface

Syntax

status = MEM_increaseTableSize(numEntries);

Parameters

Uns numEntries; /* number of segments to increase table by */

Return Value

Int status; /* TRUE if successful */

Reentrant

yes

Description

MEM_increaseTableSize allocates numEntries of undefined memory segments. When MEM_define is called, undefined memory segments are re-used. If no undefined memory segments exist, one is allocated. By using MEM_increaseTableSize, the application can avoid the use of MEM_alloc (thus improving performance and determinism) within the MEM_define call.

MEM_increaseTableSize internally locks memory by calling LCK_pend and LCK_post. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_increaseTableSize cannot be called from the context of a SWI or HWI. It can be called from main() or a TSK. The duration that the API holds the memory lock is variable.

MEM_increaseTableSize returns SYS_OK to indicate success and SYS_EALLOC if an allocation error occurred.

Constraints and Calling Context

• Do not call from the context of a SWI or HWI.

See Also

MEM_define
MEM_undefine
MEM_redefine

Redefine an existing memory segment

C Interface

Syntax

MEM_redefine(segid, base, length);

Parameters

Int segid; /* segment to redefine */
Ptr base; /* base address of new block */
MEM_sizep length; /* length (in MADUs) of new block */

Return Value

Void

Reentrant

yes

Description

MEM_redefine redefines an existing memory segment managed by the DSP/BIOS MEM Module. All pointers in the old segment memory block are automatically freed, and the new segment block is completely available for allocations.

The new block should be aligned on a MEM_HEADERSIZE boundary, and the length should be a multiple of MEM_HEADERSIZE.

Constraints and Calling Context

- MEM_redefine internally locks the memory by calling LCK_pend and LCK_post. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_redefine cannot be called from the context of a SWI or HWI. It can be called from main() or a TSK. The duration that the API holds the memory lock is variable.
- The length parameter must be a multiple of MEM_HEADERSIZE and must be at least equal to MEM_HEADERSIZE.
- The base Ptr cannot be NULL.

See Also

MEM_define
MEM_undefine
MEM_stat

Return the status of a memory segment

C Interface

Syntax

```c
status = MEM_stat(segid, statbuf);
```

Parameters

- `Int segid; /* memory segment identifier */`
- `MEM_Stat *statbuf; /* pointer to stat buffer */`

Return Value

- `Bool status; /* TRUE if successful */`

Description

MEM_stat returns the status of the memory segment specified by `segid` in the status structure pointed to by `statbuf`.

```c
typedef struct MEM_Stat {
    MEM_sizep   size;   /* original size of segment */
    MEM_sizep   used;   /* MADUs used in segment */
    size_t      length; /* largest contiguous block */
} MEM_Stat;
```

All values are expressed in terms of minimum addressable units (MADUs).

MEM_stat returns TRUE if `segid` corresponds to a valid memory segment, and FALSE otherwise. If MEM_stat returns FALSE, the contents of `statbuf` are undefined. If the segment has been undefined with MEM_undefine, this function returns FALSE.

MEM functions that access memory internally lock the memory by calling the LCK_pend and LCK_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_stat cannot be called from the context of a SWI or HWI.

Constraints and Calling Context

- MEM_stat cannot be called from a SWI or HWI.
- MEM_stat cannot be called if the TSK scheduler is disabled.
MEM_undefine  

Undefine an existing memory segment

C Interface

Syntax

MEM_undefine(segid);

Parameters

Int segid; /* segment to undefine */

Return Value

Void

Reentrant

yes

Description

MEM_undefine removes a memory segment from the internal memory tables. Once a memory segment has been undefined, the segid cannot be used in any of the MEM APIs (except MEM_stat). Note: The undefined segid might later be returned by a subsequent MEM_define call.

MEM_undefine internally locks the memory by calling LCK_pend and LCK_post. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_undefine cannot be called from the context of a SWI or HWI. It can be called from main() or a TSK. The duration that the API holds the memory lock is variable.

Constraints and Calling Context

• Do not call from the context of a SWI or HWI.
• MEM_undefine does not free the actual memory buffer managed by the memory segment.

See Also

MEM_define
MEM_redefine
MEM_valloc  Allocate from a memory segment and set value

C Interface

Syntax
addr = MEM_valloc(segid, size, align, value);

Parameters

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Int</td>
<td>segid</td>
<td>/* memory segment identifier */</td>
</tr>
<tr>
<td>size_t</td>
<td>size</td>
<td>/* block size in MADUs */</td>
</tr>
<tr>
<td>size_t</td>
<td>align</td>
<td>/* block alignment */</td>
</tr>
<tr>
<td>Char</td>
<td>value</td>
<td>/* character value */</td>
</tr>
</tbody>
</table>

Return Value

Void *addr; /* address of allocated block of memory */

Description

MEM_valloc uses MEM_alloc to allocate the memory before initializing it to value.

The segid parameter identifies the memory segment from which memory is to be allocated. This identifier can be an integer or a memory segment name defined in the configuration. The files created by the configuration define each configured segment name as a variable with an integer value.

The block contains size MADUs and starts at an address that is a multiple of align. If align is 0 or 1, there is no alignment constraint.

If the memory request cannot be satisfied, MEM_valloc calls SYS_error with SYS_EALLOC and returns MEM_ILLEGAL.

MEM functions that allocate and deallocate memory internally lock the memory by calling the LCK_pend and LCK_post functions. If another task already holds a lock to the memory, there is a context switch. For this reason, MEM_valloc cannot be called from the context of a SWI or HWI.

Constraints and Calling Context

- segid must identify a valid memory segment.
- MEM_valloc cannot be called from a SWI or HWI.
- MEM_valloc cannot be called if the TSK scheduler is disabled.
- align must be 0, or a power of 2 (for example, 1, 2, 4, 8).

See Also

MEM_alloc
MEM_calloc
MEM_free
SYS_error
std.h and stdlib.h functions
2.16 MSGQ Module

The MSGQ module allows for the structured sending and receiving of variable length messages. This module can be used for homogeneous or heterogeneous multi-processor messaging.

Functions

- MSGQ_count. Return the number of messages in a message queue.
- MSGQ_get. Receive a message from the message queue. Performed by reader.
- MSGQ_getAttrs: Returns the attributes of a local message queue.
- MSGQ_getDstQueue. Get destination message queue.
- MSGQ_getMsgId. Return the message ID from a message.
- MSGQ_getMsgSize. Return the message size from a message.
- MSGQ_getSrcQueue. Extract the reply destination from a message.
- MSGQ_isLocalQueue. Returns TRUE if local message queue.
- MSGQ_locate. Synchronously find a message queue. Performed by writer.
- MSGQ_locateAsync. Asynchronously find a message queue. Performed by writer.
- MSGQ_put. Place a message on a message queue. Performed by writer.
- MSGQ_setErrorHandler. Set up handling of internal MSGQ errors.
- MSGQ_setMsgId. Sets the message ID in a message.
- MSGQ_setSrcQueue. Sets the reply destination in a message.
### Constants, Types, and Structures

```c
/* Attributes used to open message queue */
typedef struct MSGQ_Attrs {
    Ptr notifyHandle;
    MSGQ_Pend pend;
    MSGQ_Post post;
} MSGQ_Attrs;

MSGQ_Attrs MSGQ_ATTRS = {
    NULL,                /* notifyHandle */
    (MSGQ_Pend)SYS_zero, /* NOP pend */
    FXN_F_nop            /* NOP post */
};

/* Attributes for message queue location */
typedef struct MSGQ_LocateAttrs {
    Uns timeout;
} MSGQ_LocateAttrs;

MSGQ_LocateAttrs  MSGQ_LOCATEATTRS = {SYS_FOREVER};

/* Attrs for asynchronous message queue location */
typedef struct MSGQ_LocateAsyncAttrs {
    Uint16 poolId;
    Arg arg;
} MSGQ_LocateAsyncAttrs;

MSGQ_LocateAsyncAttrs  MSGQ_LOCATEASYNCATTRS = {0, 0};

/* Configuration structure */
typedef struct MSGQ_Config {
    MSGQ_Obj          *msgqQueues;          /* Array of MSGQ handles */
    MSGQ_TransportObj *transports;          /* Transport array */
    Uint16             numMsgqQueues;       /* Number of MSGQ handles */
    Uint16             numProcessors;       /* Number of processors */
    Uint16             startUninitialized;  /* 1st MSGQ to init */
    MSGQ_Queue         errorQueue;          /* Receives transport err */
    Uint16             errorPoolId;         /* Alloc errors from poolId */
} MSGQ_Config;

/* Asynchronous locate message */
typedef struct MSGQ_AsyncLocateMsg {
    MSGQ_MsgHeader header;
    MSGQ_Queue msgqQueue;
    Arg arg;
} MSGQ_AsyncLocateMsg;

/* Asynchronous error message */
typedef struct MSGQ_AsyncErrorMsg {
    MSGQ_MsgHeader header;
    MSGQ_MqtError errorType;
    Uint16 mqtId;
    Uint16 parameter;
} MSGQ_AsyncErrorMsg;

/* Transport object */
```
typedef struct MSGQ_TransportObj {
    MSGQ_MqtInit  initFxn;    /* Transport init func */
    MSGQ_TransportFxns *fxns; /* Interface funcs */
    Ptr         params; /* Setup parameters */
    Ptr         object; /* Transport-specific object */
    Uint16      procId; /* Processor Id talked to */
} MSGQ_TransportObj;

Configuration Properties
The following list shows the properties that can be configured in a Tconf script, along with their types and
default values. For details, see the MSGQ Manager Properties heading. For descriptions of data types,
see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>ENABLEMSGQ</td>
<td>Bool</td>
<td>false</td>
</tr>
</tbody>
</table>

Description
The MSGQ module allows for the structured sending and receiving of variable length messages. This
module can be used for homogeneous or heterogeneous multi-processor messaging. The MSGQ
module with a substantially similar API is implemented in DSP/BIOS Link for certain TI general-purpose
processors (GPPs), particularly those used in OMAP devices.

MSGQ provides more sophisticated messaging than other modules. It is typically used for complex
situations such as multi-processor messaging. The following are key features of the MSGQ module:

• Writers and readers can be relocated to another processor with no runtime code changes.
• Timeouts are allowed when receiving messages.
• Readers can determine the writer and reply back.
• Receiving a message is deterministic when the timeout is zero.
• Sending a message is non-blocking.
• Messages can reside on any message queue.
• Supports zero-copy transfers.
• Can send and receive from HWIs, SWIs and TSKs.
• Notification mechanism is specified by application.
• Allows QoS (quality of service) on message buffer pools. For example, using specific buffer pools for
  specific message queues.

Messages are sent and received via a message queue. A reader is a thread that gets (reads) messages
from a message queue. A writer is a thread that puts (writes) a message to a message queue. Each
message queue has one reader and can have many writers. A thread may read from or write to multiple message queues.

Conceptually, the reader thread owns a message queue. The processor where the reader resides opens a message queue. Writer threads locate existing message queues to get access to them.

Messages must be allocated from the MSGQ module. Once a message is allocated, it can be sent on any message queue. Once a message is sent, the writer loses ownership of the message and should not attempt to modify the message. Once the reader receives the message, it owns the message. It may either free the message or re-use the message.

Messages in a message queue can be of variable length. The only requirement is that the first field in the definition of a message must be a MSGQ_MsgHeader element.

```c
typedef struct MyMsg {
    MSGQ_MsgHeader header;
    ...
} MyMsg;
```

The MSGQ API uses the MSGQ_MsgHeader internally. Your application should not modify or directly access the fields in the MSGQ_MsgHeader.

The MSGQ module has the following components:

- **MSGQ API.** Applications call the MSGQ functions to open and use a message queue object to send and receive messages. For an overview, see “MSGQ APIs” on page 228. For details, see the sections on the individual APIs.

- **Allocators.** Messages sent via MSGQ must be allocated by an allocator. The allocator determines where and how the memory for the message is allocated. For more about allocators, see the *DSP/BIOS User’s Guide* (SPRU423F).

- **Transports.** Transports are responsible for locating and sending messages with other processors. For more about transports, see the *DSP/BIOS User’s Guide* (SPRU423F).
For more about using the MSGQ module—including information about multi-processor issues and a comparison of data transfer modules—see the *DSP/BIOS User’s Guide* (SPRU423F).

### MSGQ APIs

The MSGQ APIs are used to open and close message queues and to send and receive messages. The MSGQ APIs shield the application from having to contain any knowledge about transports and allocators.

The following figure shows the call sequence of the main MSGQ functions:

![MSGQ Function Calling Sequence](image)

**Figure 2-6. MSGQ Function Calling Sequence**

The reader calls the following APIs:
- MSGQ_open
- MSGQ_get
- MSGQ_free
- MSGQ_close

A writer calls the following APIs:
- MSGQ_locate or MSGQ_locateAsync
- MSGQ_alloc
- MSGQ_put
- MSGQ_release

Wherever possible, the MSGQ APIs have been written to have a deterministic execution time. This allows application designers to be certain that messaging will not consume an unknown number of cycles.

In addition, the MSGQ functions support use of message queues from all types of DSP/BIOS threads: HWIs, SWIs, and TSKs. That is, calls that may be synchronous (blocking) have an asynchronous (non-blocking) alternative.

### Static Configuration

In order to use the MSGQ module and the allocators it depends upon, you must statically configure the following:
- ENABLEMSGQ property of the MSGQ module using Tconf (see “MSGQ Manager Properties” on page 232)
- MSGQ_config variable in application code (see below)
An application must provide a filled in MSGQ_config variable in order to use the MSGQ module.

```c
MSGQ_Config MSGQ_config;
```

The MSGQ_Config type has the following structure:

```c
typedef struct MSGQ_Config {
    MSGQ_Obj      *msgqQueues;     /* Array of message queue handles */
    MSGQ_TransportObj *transports; /* Array of transports */
    Uint16        numMsgqQueues;   /* Number of message queue handles*/
    Uint16        numProcessors;   /* Number of processors */
    Uint16        startUninitialized;  /* First msgq to init */
    MSGQ_Queue    errorQueue;      /* Receives async transport errors*/
    Uint16        errorPoolId;     /* Alloc error msgs from poolId */
} MSGQ_Config;
```

The fields in the MSGQ_Config structure are described in the following table:

<table>
<thead>
<tr>
<th>Field</th>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>msgqQueues</td>
<td>MSGQ_Obj *</td>
<td>Array of message queue objects. The fields of each object do not need to be initialized.</td>
</tr>
<tr>
<td>transports</td>
<td>MSGQ_TransportObj *</td>
<td>Array of transport objects. The fields of each object must be initialized.</td>
</tr>
<tr>
<td>numMsgqQueues</td>
<td>Uint16</td>
<td>Length of the msgqQueues array.</td>
</tr>
<tr>
<td>numProcessors</td>
<td>Uint16</td>
<td>Length of the transports array.</td>
</tr>
<tr>
<td>startUninitialized</td>
<td>Uint16</td>
<td>Index of the first message queue to initialize in the msgqQueue array. This should be set to 0.</td>
</tr>
<tr>
<td>errorQueue</td>
<td>MSGQ_Queue</td>
<td>Message queue to receive transport errors. Initialize to MSGQ_INVALIDMSGQ.</td>
</tr>
<tr>
<td>errorPoolId</td>
<td>Uint16</td>
<td>Allocator to allocate transport errors. Initialize to POOL_INVALIDID.</td>
</tr>
</tbody>
</table>

Internally, MSGQ references its configuration via the MSGQ_config variable. If the MSGQ module is enabled (via Tconf) but the application does not provide the MSGQ_config variable, the application cannot be linked successfully.
In the MSGQ_Config structure, an array of MSGQ_TransportObj items defines transport objects with the following structure:

```c
typedef struct MSGQ_TransportObj {
    MSGQ_MqtInit initFxn;  /* Transport init func */
    MSGQ_TransportFxns *fxns; /* Interface funcs */
    Ptr params; /* Setup parameters */
    Ptr object; /* Transport-specific object */
    Uint16 procId; /* Processor Id talked to */
} MSGQ_TransportObj;
```

The following table describes the fields in the MSGQ_TransportObj structure:

<table>
<thead>
<tr>
<th>Field</th>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>initFxn</td>
<td>MSGQ_MqtInit</td>
<td>Initialization function for this transport. This function is called during DSP/BIOS startup. More explicitly it is called before main().</td>
</tr>
<tr>
<td>fxns</td>
<td>MSGQ_TransportFxns *</td>
<td>Pointer to the transport's interface functions.</td>
</tr>
<tr>
<td>params</td>
<td>Ptr</td>
<td>Pointer to the transport's parameters. This field is transport-specific. Please see documentation provided with your transport for a description of this field.</td>
</tr>
<tr>
<td>info</td>
<td>Ptr</td>
<td>State information needed by the transport. This field is initialized and managed by the transport. Refer to the specific transport implementation to determine how to use this field</td>
</tr>
<tr>
<td>procId</td>
<td>Uint16</td>
<td>Numeric ID of the processor that this transport communicates with. The current processor must have a procId field that matches the GBL.PROCID property.</td>
</tr>
</tbody>
</table>

If no parameter structure is specified (that is, NULL is used) for the MSGQ_TransportObj, the transport uses its default parameters.
The order of the transports array is by processor. The first entry communicates with processor 0, the next entry with processor 1, and so on. On processor n, the nth entry in the transport array should be MSGQ_NOTRANSPORT, since there is no transport to itself. The following example shows a configuration for a single-processor application (that is, processor 0). Note that the 0th entry is MSGQ_NOTRANSPORT.

```
#define NUMMSGQUEUES 4 /* # of local message queues*/
#define NUMPROCESSORS 1 /* Single processor system */

static MSGQ_Obj           msgQueues[NUMMSGQUEUES];
static MSGQ_TransportObj  transports[NUMPROCESSORS] =
                         {MSGQ_NOTRANSPORT};

MSGQ_Config MSGQ_config = {
    msgQueues,
    transports,
    NUMMSGQUEUES,
    NUMPROCESSORS,
    0,
    MSGQ_INVALIDMSGQ,
    POOL_INVALIDID
};
```

Managing Transports at Run-Time

As described in the previous section, MSGQ uses an array of transports of type MSGQ_TransportObj in the MSGQ_config variable. This array is processor ID based. For example, MSGQ_config->transports[0] is the transport to processor 0. Therefore, if a single binary is used on multiple processors, the array must be changed at run-time.

As with the GBL_setProcId API, the transports array can be managed in the User Init Function (see GBL Module Properties). DSP/BIOS only uses MSGQ_config and the transports array after the User Init Function returns.

There are several ways to manage the transports array. Two common ways are as follows:

- **Create a static two-dimensional transports array and select the correct one.** Assume a single image will be used for two processors (procId 0 and 1) in a system with NUMPROCESSORS (3 in this example) processors. The transports array in the single image might look like this:

```
MSGQ_TransportObj transports[2][NUMPROCESSORS] =
{   { MSGQ_NOTRANSPORT,   // proc 0 talk to proc 0
    {...},             // proc 0 talk to proc 1
    {...},             // proc 0 talk to proc 2
  },
  { {...},             // proc 1 talk to proc 0
    MSGQ_NOTRANSPORT,   // proc 1 talk to proc 1
    {...},             // proc 1 talk to proc 2
  }
};
```

In the User Init Function, the application would call GBL_setProcId with the correct processor ID. Then it would assign the correct transport array to MSGQ_config. For example, for processor 1, it would do the following:

```
MSGQ_config.transports = transports[1];
```
Note that this approach does not scale well as the number of processors in the system increases.

- **Fill in the transports array in the User Init Function.** In the User Init Function, you can fill in the contents of the transports array. You would still statically define a 1-dimensional transports array as follows:

  ```c
  MSGQ_TransportObj transports[NUMPROCESSORS];
  ```

  This array would not be initialized. The initialization would occur in the User Init Function. For example on processor 1, it would fill in the transports array as follows.

  ```c
transports[0].initFxn = ...
transports[0].fxns = ...
transports[0].object = ...
transports[0].params = ...
transports[0].procId = 0;
transports[1] = MSGQ_NOTRANSPORT;//no self-transport
transports[2].initFxn = ...
transports[2].fxns = ...
...
transports[2].procId = 2;
MSGQ_config.transport = transports;
```

Note that some of the parameters may not be able to be determined easily at run-time, therefore you may need to use a mixture of these two options.

**Message Queue Management**

When a message queue is closed, the threads that located the closing message queue are not notified. No messages should be sent to a closed message queue. Additionally, there should be no active call to MSGQ_get or MSGQ_getAttrs to a message queue that is being closed. When a message queue is closed, all unread messages in the message queue are freed.

**MSGQ Manager Properties**

To configure the MSGQ manager, the MSGQ_Config structure must be defined in the C code. See “Static Configuration” on page 228.

The following global property must also be set in order to use the MSGQ module:

- **Enable Message Queue Manager.** If ENABLEMSGQ is TRUE, each transport and message queue specified in the MSGQ_config structure (see “Static Configuration” on page 228) is initialized.

  ```c
  Tconf Name: ENABLEMSGQ Type: Bool
  Example: bios.MSGQ.ENABLEMSGQ = true;
  ```
### MSGQ_alloc

**Allocate a message**

#### C Interface

**Syntax**

```c
status = MSGQ_alloc(poolId, msg, size);
```

**Parameters**

- `Uint16 poolId; /* allocate the message from this allocator */`
- `MSGQ_Msg *msg; /* pointer to the returned message */`
- `Uint16 size; /* size of the requested message */`

**Return Value**

- `Int status; /* status */`

**Reentrant**

Yes

**Description**

`MSGQ_alloc` returns a message from the specified allocator. The size is in minimum addressable data units (MADUs).

This function is performed by a writer. This call is non-blocking and can be called from a HWI, SWI or TSK.

All messages must be allocated from an allocator. Once a message is allocated it can be sent. Once a message is received, it must either be freed or re-used.

The poolId must correspond to one of the allocators specified by the allocators field of the POOL_Config structure specified by the application. (See “Static Configuration” on page 278.)

If a message is allocated, SYS_OK is returned. Otherwise, SYS_EINVAL is returned if the poolId is invalid, and SYS_EALLOC is returned if no memory is available to meet the request.

**Constraints and Calling Context**

- All message definitions must have MSGQ_MsgHeader as its first field. For example:

```c
struct MyMsg {
    MSGQ_MsgHeader header; /* Required field */
    ...                    /* User fields */
}
```

**Example**

```c
/* Allocate a message */
status = MSGQ_alloc(STATICPOOLID, (MSGQ_Msg *)&msg, sizeof(MyMsg));
if (status != SYS_OK) {
    SYS_abort("Failed to allocate a message");
}
```

**See Also**

- MSGQ_free
**MSGQ_close**  
*Close a message queue*

**C Interface**

Syntax

```c
status = MSGQ_close(msgqQueue);
```

Parameters

- `MSGQ_Queue` `msgqQueue`; /* Message queue to close */

Return Value

- `Int` `status`; /* status */

**Reentrant**

yes

**Description**

MSGQ_close closes a message queue. If any messages are in the message queue, they are deleted. This function is performed by the reader.

Threads that have located (with MSGQ_locate or MSGQ_locateAsync) the message queue being closed are not notified about the closure.

If successful, this function returns SYS_OK.

**Constraints and Calling Context**

- The message queue must have been returned from MSGQ_open.

**See Also**

- MSGQ_open
MSGQ_count

_Return the number of messages in a message queue_

### C Interface

**Syntax**

```c
status = MSGQ_count(msgqQueue, count);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSGQ_Queue</td>
<td>msgqQueue; /* Message queue to count */</td>
</tr>
<tr>
<td>Uns</td>
<td><em>count; /</em> Pointer to returned count */</td>
</tr>
</tbody>
</table>

**Return Value**

| Int     | status; /* status */ |

**Reentrant**

yes

### Description

This API determines the number of messages in a specific message queue. Only the processor that opened the message queue should call this API to determine the number of messages in the reader's message queue. This API is not thread safe with MSGQ_get when accessing the same message queue, so the caller of MSGQ_count must prevent any calls to MSGQ_get.

If successful, this function returns SYS_OK.

### Constraints and Calling Context

- The message queue must have been returned from a MSGQ_open call.

### Example

```c
status = MSGQ_count(readerMsgQueue, &count);
if (status != SYS_OK) {
    return;
}
LOG_printf(&trace, "There are %d messages.", count);
```

### See Also

MSGQ_open
**MSGQ_free**

*Free a message*

**C Interface**

Syntax

```c
status = MSGQ_free(msg);
```

Parameters

| MSGQ_Msg | msg; /* Message to be freed */ |

Return Value

| Int | status; /* status */ |

**Reentrant**

yes

**Description**

MSGQ_free frees a message back to the allocator.

If successful, this function returns SYS_OK.

This call is non-blocking and can be called from a HWI, SWI or TSK.

**Constraints and Calling Context**

- The message must have been allocated via MSGQ_alloc.

**Example**

```c
status = MSGQ_get(readerMsgQueue, (MSGQ_Msg *)msg,
                  SYS_FOREVER);
if (status != SYS_OK) {
    SYS_printf("MSGQ_get call failed.");
}
// process message
MSGQ_free(msg);
```

**See Also**

MSGQ_alloc
**MSGQ_get**  
*Receive a message from the message queue*

**C Interface**

Syntax

```c
status = MSGQ_get(msgqQueue, msg, timeout);
```

**Parameters**

- `MSGQ_Queue msgqQueue;` /* Message queue */
- `MSGQ_Msg *msg;` /* Pointer to the returned message */
- `Uns timeout;` /* Duration to block if no message */

**Return Value**

- `Int status;` /* status */

**Reentrant**

- yes

**Description**

MSGQ_get returns a message sent via MSGQ_put. The order of retrieval is FIFO.

This function is performed by the reader. Once a message has been received, the reader is responsible for freeing or re-sending the message.

If no messages are present, the pend() function specified in the MSGQ_Attrs passed to MSGQ_open for this message queue is called. The pend() function blocks up to the timeout value (SYS_FOREVER = forever). The timeout units are system clock ticks.

This function is deterministic if timeout is zero. MSGQ_get can be called from a TSK with any timeout. It can be called from a HWI or SWI if the timeout is zero.

If successful, this function returns SYS_OK. Otherwise, SYSETIMEOUT is returned if the timeout expires before the message is received.

**Constraints and Calling Context**

- Only one reader of a message queue is allowed concurrently.
- The message queue must have been returned from a MSGQ_open call.

**Example**

```c
status = MSGQ_get(readerMsgQueue, (MSGQ_Msg *)&msg, 0);
if (status != SYS_OK) {
    /* No messages to process */
    return;
}
```

**See Also**

- MSGQ_put
- MSGQ_open
MSGQ_getAttrs

Returns the attributes of a message queue

C Interface

Syntax

status = MSGQ_getAttrs(msgqQueue, attrs);

Parameters

MSGQ_Queue msgqQueue; /* Message queue */
MSGQ_Attrs *attrs; /* Attributes of message queue */

Return Value

Int status /* status */

Reentrant

yes

Description

MSGQ_getAttrs fills in the attrs structure passed to it with the attributes of a local message queue. These attributes are set by MSGQ_open.

The API returns SYS_OK unless the message queue is not local (that is, it was opened on another processor). If the message queue is not local, the API returns SYS_EINVAL and does not change the contents of the passed in attrs structure.

Example

status = MSGQ_getAttrs (msgqQueue, &attrs);
if (status != SYS_OK) {
    return;
}
notifyHandle = attrs.notifyHandle;

Constraints and Calling Context

- The message queue must have been returned from a MSGQ_open call and must be valid.
- This function can be called from a HWI, SWI or TSK.

See Also

MSGQ_open
MSGQ_getDstQueue  Get destination message queue field in a message

C Interface

Syntax

MSGQ_getDstQueue(msg, msgQueue);

Parameters

MSGQ_Msg msg; /* Message */
MSGQ_Queue *msgQueue; /* Message queue */

Return Value

Void

Reentrant

yes

Description

This API allows the application to determine the destination message queue of a message. This API is generally used by transports to determine the final destination of a message. This API can also be used by the application once the message is received.

This function can be called from a HWI, SWI or TSK.

Constraints and Calling Context

• The message must have been sent via MSGQ_put.
MSGQ_getMsgId  
*Return the message ID from a message*

**C Interface**

**Syntax**

```c
msgId = MSGQ_getMsgId(msg);
```

**Parameters**

- **MSGQ_Msg msg;** /* Message */

**Return Value**

- **Uint16 msgId;** /* Message ID */

**Reentrant**

yes

**Description**

MSGQ_getMsgId returns the message ID from a received message. This message ID is specified via the MSGQ_setMsgId function.

This function can be called from a HWI, SWI or TSK.

**Example**

```c
/* Make sure the message is the one expected */
if (MSGQ_getMsgId((MSGQ_Msg)msg) != MESSAGEID) {
    SYS_abort("Unexpected message");
}
```

**See Also**

- MSGQ_setMsgId
**MSGQ_getMsgSize**  
*Return the message size from a message*

**C Interface**

**Syntax**

```c
size = MSGQ_getMsgSize(msg);
```

**Parameters**

- MSGQ_Msg msg; /* Message */

**Return Value**

- Uint16 size; /* Message size */

**Reentrant**

yes

**Description**

MSGQ_getMsgSize returns the size of the message buffer out of the received message. The size is in minimum addressable data units (MADUs).

This function can be used to determine if a message can be re-used.

This function can be called from a HWI, SWI or TSK.

**See Also**

MSGQ_alloc
**MSGQ_getSrcQueue**  
*Extract the reply destination from a message*

### C Interface

**Syntax**

```c
status = MSGQ_getSrcQueue(msg, msgqQueue);
```

#### Parameters

- `MSGQ_Msg msg; /* Received message */`
- `MSGQ_Queue *msgqQueue; /* Message queue */`

#### Return Value

- `Int status; /* status */`

**Reentrant**

yes

**Description**

Many times a receiver of a message wants to reply to the sender of the message (for example, to send an acknowledgement). When a valid `msgqQueue` is specified in `MSGQ_setSrcQueue`, the receiver of the message can extract the message queue via `MSGQ_getSrcQueue`.

This is basically the same as a `MSGQ_locate` function without knowing the name of the message queue. This function can be used even if the `queueName` used with `MSGQ_open` was NULL or non-unique.

Note: The `msgqQueue` may not be the sender's message queue handle. The sender is free to use any created message queue handle.

This function can be called from a HWI, SWI or TSK.

If successful, this function returns `SYS_OK`.

**Example**

```c
/* Get the handle and send the message back. */
status = MSGQ_getSrcQueue((MSGQ_Msg)msg, &replyQueue);
if (status != SYS_OK) {
    /* Free the message and abort */
    MSGQ_free((MSGQ_Msg)msg);
    SYS_abort("Failed to get handle from message");
}
status = MSGQ_put(replyQueue, (MSGQ_Msg)msg);
```

**See Also**

- `MSGQ_getAttrs`
- `MSGQ_setSrcQueue`
**MSGQ_isLocalQueue**  
*Return whether message queue is local or on other processor*

### C Interface

**Syntax**

```c
flag = MSGQ_isLocalQueue(msgqQueue);
```

**Parameters**

- `MSGQ_Queue msgqQueue; /* Message queue */`

**Return Value**

- `Bool flag; /* status */`

**Reentrant**

- `yes`

**Description**

This API determines whether the message queue is local (that is, opened on this processor) or remote (that is, opened on a different processor).

If the message queue is local, the flag returned is TRUE. Otherwise, it is FALSE.

**Constraints and Calling Context**

- This function can be called from a HWI, SWI or TSK.

**Example**

```c
flag = MSGQ_isLocalQueue(readerMsgQueue);
if (flag == TRUE) {
    /* Message queue is local */
    return;
}
```

**See Also**

- MSGQ_open
**MSGQ_locate**  
*Synchronously find a message queue*

**C Interface**

**Syntax**

```c
status = MSGQ_locate(queueName, msgqQueue, locateAttrs);
```

**Parameters**

- `String queueName;` /* Name of message queue to locate */
- `MSGQ_Queue *msgqQueue;` /* Return located message queue here */
- `MSGQ_LocateAttrs *locateAttrs;` /* Locate attributes */

**Return Value**

- `Int status;` /* status */

**Reentrant**

yes

**Description**

The MSGQ_locate function is used to locate an opened message queue. This function is synchronous (that is, it can block if timeout is non-zero).

This function is performed by a writer. The reader must have already called MSGQ_open for this `queueName`.

MSGQ_locate first searches the local message queues for a name match. If a match is found, that message queue is returned. If no match is found, the transports are queried one at a time. If a transport locates the `queueName`, that message queue is returned. If the transport does not locate the message queue, the next transport is queried. If no transport can locate the message queue, an error is returned.

In a multiple-processor environment, transports can block when they are queried if you call MSGQ_locate. The timeout in the MSGQ_LocateAttrs structure specifies the maximum time each transport can block. The default is SYS_FOREVER (that is, each transport can block forever). Remember that if you specify 1000 clock ticks as the timeout, the total blocking time could be 1000 * number of transports.

Note that timeout is not a fixed amount of time to wait. It is the maximum time each transport waits for a positive or negative response. For example, suppose your timeout is 1000, but the response (found or not found) comes back in 600 ticks. The transport returns the response then; it does not wait for another 400 ticks to recheck for a change.

If you do not want to allow blocking, call MSGQ_locateAsync instead of MSGQ_locate.

The `locateAttrs` parameter is of type MSGQ_LocateAttrs. This type has the following structure:

```c
typedef struct MSGQ_LocateAttrs {
    Uns timeout;
} MSGQ_LocateAttrs;
```

The timeout is the maximum time a transport can block on a synchronous locate in system clock ticks. The default attributes are as follows:

```c
MSGQ_LocateAttrs MSGQ_LOCATEATTRS = {SYS_FOREVER};
```
If successful, this function returns SYS_OK. Otherwise, it returns SYS_ENOTFOUND to indicate that it could not locate the specified message queue.

Constraints and Calling Context

- Cannot be called from main().
- Cannot be called in a SWI or HWI context.

Example

```c
status = MSGQ_locate("reader", &readerMsgQueue, NULL);
if (status != SYS_OK) {
   (SYS_abort("Failed to locate reader message queue");
}
```

See Also

- MSGQ_locateAsync
- MSGQ_open
**MSGQ_locateAsync**  
*Asynchronously find a message queue*

**C Interface**

**Syntax**

```
status = MSGQ_locateAsync(queueName, replyQueue, locateAsyncAttrs);
```

**Parameters**

- `String queueName; /* Name of message queue to locate */`
- `MSGQ_Queue replyQueue; /* Msgq to send locate message */`
- `MSGQ_LocateAsyncAttrs *locateAsyncAttrs;/* Locate attributes */`

**Return Value**

- `Int status; /* status */`

**Reentrant**

- `yes`

**Description**

MSGQ_locateAsync firsts searches the local message queues for a name match. If one is found, an asynchronous locate message is sent to the specified message queue (in the replyQueue parameter). If it is not, all transports are asked to start an asynchronous locate search. After all transports have been asked to start the search, the API returns.

If a transport locates the message queue, an asynchronous locate message is sent to the specified replyQueue. If no transport can locate the message queue, no message is sent.

This function is performed by a writer. The reader must have already called MSGQ_open for this queueName. An asynchronous locate can be performed from a SWI or TSK. It cannot be performed in main().

The message ID for an asynchronous locate message is:

```
/* Asynchronous locate message ID */
#define MSGQ_ASYNCLOCATEMSGID   0xFF00
```

The MSGQ_LocateAsyncAttrs structure has the following fields:

```
typedef struct MSGQ_LocateAsyncAttrs {
    Uint16    poolId;
    Arg       arg;
} MSGQ_LocateAttrs;
```

The default attributes are as follows:

```
MSGQ_LocateAsyncAttrs MSGQ_LOCATEASYNCATTRS = {0, 0};
```

The locate message is allocated from the allocator specified by the locateAsyncAttrs->poolId field.

The locateAsyncAttrs->arg value is included in the asynchronous locate message. This field allows you to correlate requests with the responses.
Once the application receives an asynchronous locate message, it is responsible for freeing the message. The asynchronous locate message received by the replyQueue has the following structure:

```c
typedef struct MSGQ_AsyncLocateMsg {
    MSGQ_MsgHeader  header;
    MSGQ_Queue      msgqQueue;
    Arg             arg;
} MSGQ_AsyncLocateMsg;
```

This function returns SYS_OK to indicated that an asynchronous locate was started. This status does not indicate whether or not the locate will be successful. The SYS_EALLOC status is returned if the message could not be allocated.

### Constraints and Calling Context

- The allocator must be able to allocate an asynchronous locate message.
- Cannot be called in the context of main().

### Example

The following example shows an asynchronous locate performed in a task. Time spent blocking is dictated by the timeout specified in the MSGQ_get call. (Error handling statements were omitted for brevity.)

```c
status = MSGQ_open("myMsgQueue", &myQueue, &msgqAttrs);
locateAsyncAttrs             = MSGQ_LOCATEATTRS;
locateAsyncAttrs.poolId      = STATICPOOLID;
MSGQ_locateAsync("msgQ1", myQueue, &locateAsyncAttrs);
status = MSGQ_get(myQueue, &msg, SYS_FOREVER);
if (MSGQ_getMsgId((MSGQ_Msg)msg) ==
    MSGQ_ASYNCLOCATEMSGID) {
    readerQueue = msg->msgqQueue;
}
MSGQ_free((MSGQ_Msg)msg);
```

### See Also

- MSGQ_locate
- MSGQ_free
- MSGQ_open
**MSGQ_open**  
*Open a message queue*

**C Interface**

Syntax

```c
status = MSGQ_open(queueName, msgqQueue, attrs);
```

**Parameters**

- `String` `queueName`; /* Unique name of the message queue */
- `MSGQ_Queue` `*msgqQueue`; /* Pointer to returned message queue */
- `MSGQ_Attrs` `*attrs`; /* Attributes of the message queue */

**Return Value**

- `Int` `status`; /* status */

**Reentrant**

- `yes`

**Description**

MSGQ_open is the function to open a message queue. This function selects and returns a message queue from the array provided in the static configuration (that is, `MSGQ_config->msgqQueues`).

This function is on the processor where the reader resides. The reader then uses this message queue to receive messages.

If successful, this function returns SYS_OK. Otherwise, it returns SYS_ENOTFOUND to indicate that no empty spot was available in the message queue array.

If the application will use MSGQ_locate or MSGQ_locateAsync to find this message queue, the queueName must be unique. If the application will never need to use the locate APIs, the queueName may be NULL or a non-unique name.

Instead of using a fixed notification mechanism, such as SEM_pend and SEM_post, the MSGQ notification mechanism is supplied in the attrs parameter, which is of type MSGQ_Attrs. If attrs is NULL, the new message queue is assigned a default set of attributes. The structure for MSGQ_Attrs is as follows:

```c
typedef struct MSGQ_Attrs {
    Ptr notifyHandle;
    MSGQ_Pend pend;
    MSGQ_Post post;
} MSGQ_Attrs;
```

The MSGQ_Attrs fields are as follows:

<table>
<thead>
<tr>
<th>Field</th>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>notifyHandle</td>
<td>Ptr</td>
<td>Handle to use in the pend() and post() functions.</td>
</tr>
<tr>
<td>Pend</td>
<td>MSGQ_Pend</td>
<td>Function pointer to a user-specified pend function.</td>
</tr>
<tr>
<td>Post</td>
<td>MSGQ_Post</td>
<td>Function pointer to a user-specified post function.</td>
</tr>
</tbody>
</table>

The `notifyHandle` field must be unique, unless the application will never need to use the locate APIs. If the `notifyHandle` field is NULL, the default behavior is used.
The default attributes are:

```c
MSGQ_Attrs MSGQ_ATTRS = {
    NULL,                /* notifyHandle */
    (MSGQ_Pend)SYS_zero, /* NOP pend */
    FXN_F_nop            /* NOP post */
};
```

The following typedefs are provided by the MSGQ module to allow easier casting of the pend and post functions:

```c
typedef Bool (*MSGQ_Pend)(Ptr notifyHandle, Uns timeout);
typedef Void (*MSGQ_Post)(Ptr notifyHandle);
```

The post() function you specify is always called within MSGQ_put when a writer sends a message.

A reader calls MSGQ_get to receive a message. If there is a message, it returns that message, and the pend() function is not called. The pend() function is only called if there are no messages to receive.

The pend() and post() functions must act in a binary manner. For instance, SEM_pend and SEM_post treat the semaphore as a counting semaphore instead of binary. So SEM_pend and SEM_post are an invalid pend/post pair. The following example, in which the reader calls MSGQ_get with a timeout of SYS_FOREVER, shows why:

1. A writer sends 10 messages, making the count 10 in the semaphore.
2. The reader then calls MSGQ_get 10 times. Each call returns a message without calling the pend() function.
3. The reader then calls MSGQ_get again. Since there are no messages, the pend() function is called. Since the semaphore count was 10, SEM_pend returns TRUE immediately from the pend(). MSGQ would check for messages and there would still be none, so pend() would be called again. This would repeat 9 more times until the count was zero.

If the pend() function were binary (for example, a binary semaphore), the pend() function would be called at most two times in step 3.

So instead of using SEM_pend and SEM_post for synchronous (blocking) opens, you should use SEM_pendBinary and SEM_postBinary.

The following notification attributes could be used if the reader is a SWI function (which cannot block):

```c
MSGQ_Attrs attrs   = MSGQ_ATTRS; // default attributes
// leave attrs.pend as a NOP
attrs.notifyHandle = (Ptr)swiHandle;
attrs.post         = (MSGQ_Pend)SWI_post;
```

The following notification attributes could be used if the reader is a TSK function (which can block):

```c
MSGQ_Attrs attrs   = MSGQ_ATTRS; // default attributes
attrs.notifyHandle = (Ptr)semHandle;
attrs.pend         = (MSGQ_Pend)SEM_pendBinary;
attrs.post         = (MSGQ_Post)SEM_postBinary;
```

**Constraints and Calling Context**

- The message queue returned is to be used by the caller of MSGQ_get. It should not be used by writers to that message queue (that is, callers of MSGQ_put). Writers should use the message queue returned by MSGQ_locate, MSGQ_locateAsync, or MSGQ_getSrcQueue.
• If a post() function is specified, the function must be non-blocking.
• If a pend() function is specified, the function must be non-blocking when timeout is zero.
• Each message queue must have a unique name if the application will use MSGQ_locate or MSGQ_locateAsync.
• The queueName must be persistent. The MSGQ module references this name internally; that is, it does not make a copy of the name.

Example

/* Open the reader message queue.
 * Using semaphores as notification mechanism */
msgqAttrs = MSGQ_ATTRS;
msgqAttrs.notifyHandle = (Ptr)readerSemHandle;
msgqAttrs.pend = (MSGQ_Pend)SEM_pendBinary;
msgqAttrs.post = (MSGQ_Post)SEM_postBinary;
status = MSGQ_open("reader", &readerMsgQueue,
                  &msgqAttrs);
if (status != SYS_OK) {
    SYS_abort("Failed to open the reader message queue");
}

See Also

MSGQ_close
MSGQ_locate
MSGQ_locateAsync
SEM_pendBinary
SEM_postBinary
MSGQ\_put

**Place a message on a message queue**

**C Interface**

Syntax

```c
status = MSGQ\_put(msgqQueue, msg);
```

Parameters

- `MSGQ\_Queue msgqQueue; /* Destination message queue */`
- `MSGQ\_Msg msg; /* Message */`

Return Value

- `Int status; /* status */`

**Reentrant**

- `yes`

**Description**

MSGQ\_put places a message into the specified message queue.

This function is performed by a writer. This function is non-blocking, and can be called from a HWI, SWI or TSK.

The post() function for the destination message queue is called as part of the MSGQ\_put. The post() function is specified MSGQ\_open call in the MSGQ\_Attrs parameter.

If successful, this function returns SYS\_OK. Otherwise, it may return an error code returned by the transport.

There are several features available when sending a message.

- A msgId passed to MSGQ\_setMsgId can be used to indicate the type of message it is. Such a type is completely application-specific, except for IDs defined for MSGQ\_setMsgId. The reader of a message can use MSGQ\_getMsgId to get the ID from the message.

- The source message queue parameter to MSGQ\_setSrcQueue allows the sender of the message to specify a source message queue. The receiver of the message can use MSGQ\_getSrcQueue to extract the embedded message queue from the message. A client/server application might use this mechanism because it allows the server to reply to a message without first locating the sender. For example, each client would have its own message queue that it specifies as the source message queue when it sends a message to the server. The server can use MSGQ\_getSrcQueue to get the message queue to reply back to.

If MSGQ\_put returns an error, the user still owns the message and is responsible for freeing the message (or re-sending it).

**Constraints and Calling Context**

- The msgqQueue must have been returned from MSGQ\_locate, MSGQ\_locateAsync or MSGQ\_getSrcQueue (or MSGQ\_open if the reader of the message queue wants to send themselves a message).

- If MSGQ\_put does not return SYS\_OK, the message is still owned by the caller and must either be freed or re-used.
Example

    /* Send the message back. */
    status = MSGQ_put(replyMsgQueue, (MSGQ_Msg)msg);
    if (status != SYS_OK) {
        /* Need to free the message */
        MSGQ_free((MSGQ_Msg)msg);
        SYS_abort("Failed to send the message");
    }

See Also

    MSGQ_get
    MSGQ_open
    MSGQ_setMsgId
    MSGQ_getMsgId
    MSGQ_setSrcQueue
    MSGQ_getSrcQueue
MSGQ_release  Release a located message queue

C Interface

Syntax

status = MSGQ_release(msgqQueue);

Parameters

MSGQ_Queue msgqQueue; /* Message queue to release */

Return Value

Int status; /* status */

Reentrant

yes

Description

This function releases a located message queue. That is, it releases a message queue returned from
MSGQ_locate or MSGQ_locateAsync.

This function is performed by a writer.

If successful, this function returns SYS_OK. Otherwise, it may return an error code returned by the
transport.

Constraints and Calling Context

• The handle must have been returned from MSGQ_locate or MSGQ_locateAsync.

See Also

MSGQ_locate
MSGQ_locateAsync
**MSGQ_setErrorHandler**  
*Set up handling of internal MSGQ errors*

**C Interface**

```c
status = MSGQ_setErrorHandler(errorQueue, poolId);
```

**Parameters**

- `MSGQ_QUEUE errorQueue; /* Message queue to receive errors */`
- `Uint16 poolId; /* Allocator to allocate error messages */`

**Return Value**

- `Int status; /* status */`

**Reentrant**

- `yes`

**Description**

Asynchronous errors that need to be communicated to the application may occur in a transport. If an application calls `MSGQ_setErrorHandler`, all asynchronous errors are then sent to the message queue specified.

The specified message queue receives asynchronous error messages (if they occur) via `MSGQ_get`.

`poolId` specifies the allocator the transport should use to allocate error messages. If the transports cannot allocate a message, no action is performed.

If this function is not called or if `errorHandler` is set to `MSGQ_INVALIDMSGQ`, no error messages will be allocated and sent.

This function can be called multiple times with only the last handler being active.

If successful, this function returns `SYS_OK`.

The message ID for an asynchronous error message is:

```c
/* Asynchronous error message ID */
#define MSGQ_ASYNCERRORMSGID   0xFF01
```

The following is the structure for an asynchronous error message:

```c
typedef struct MSGQ_AsyncErrorMsg {
    MSGQ_MsgHeader  header;
    MSGQ_MqtError   errorType;
    Uint16          mqtId;
    Uint16          parameter;
} MSGQ_AsyncErrorMsg;
```

The following table describes the fields in the `MSGQ_AsyncErrorMsg` structure:

<table>
<thead>
<tr>
<th>Field</th>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>header</td>
<td>MSGQ_MsgHeader</td>
<td>Required field for every message</td>
</tr>
<tr>
<td>errorType</td>
<td>MSGQ_MqtError</td>
<td>Error ID</td>
</tr>
</tbody>
</table>
The following table lists the valid errorType values and the meanings of their arg fields:

<table>
<thead>
<tr>
<th>errorType</th>
<th>mqtid</th>
<th>parameter</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSGQ_MQTERROREXIT</td>
<td>ID of the transport that is exiting.</td>
<td>Not used.</td>
</tr>
<tr>
<td>MSGQ_MQTFAILEDPUT</td>
<td>ID of the transport that failed to send a message.</td>
<td>ID of destination queue. The parameter is 16 bits, so only the lower 16 bits of the msgQueue is logged. The top 16 bits of the msgQueue contain the destination processor ID, which is also the mqtId. You can OR the mqtId shifted over by 16 bits with the parameter to get the full destination msgQueue.</td>
</tr>
<tr>
<td>MSGQ_MQTERROREXIT</td>
<td>ID of the transport that is exiting.</td>
<td>Not used.</td>
</tr>
<tr>
<td>MSGQ_MQTERRORINTERNAL</td>
<td>Generic internal error.</td>
<td>Transport defined.</td>
</tr>
<tr>
<td>MSGQ_MQTERORPHYSICAL</td>
<td>Problem with the physical link.</td>
<td>Transport defined.</td>
</tr>
<tr>
<td>MSGQ_MQTERORALLOC</td>
<td>Transport could not allocate memory.</td>
<td>Size of the requested memory.</td>
</tr>
</tbody>
</table>

MSGQ_open
MSGQ_get
**MSGQ_setMsgId**  
*Set the message ID in a message*

### C Interface

**Syntax**

```c
MSGQ_setMsgId(msg, msgId);
```

**Parameters**

- `MSGQ_MSG msg; /* Message */`
- `Uint16 msgId; /* Message id */`

**Return Value**

`Void`

**Reentrant**

`yes`

**Description**

Inside each message is a message id field. This API sets this field. The value of `msgId` is application-specific. `MSGQ_getMsgId` can be used to extract this field from a message.

When a message is allocated, the value of this field is `MSGQ_INVALIDMSGID`. When `MSGQ_setMsgId` is called, it updates the field accordingly. This API can be called multiple times on a message.

If a message is sent to another processor, the message Id field is converted by the transports accordingly (for example, endian conversion is performed).

The message IDs used when sending messages are application-specific. They can have any value except values in the following ranges:

- Reserved for the MSGQ module messages: 0xFF00 - 0xFF7F
- Reserved for internal transport usage: 0xFF80 - 0xFFFF
- Used to signify an invalid message ID: 0xFFFF

The following table lists the message IDs currently used by the MSGQ module.

<table>
<thead>
<tr>
<th>Constant Defined in msgq.h</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSGQ_ASYNCLOCATEMSGID</td>
<td>0xFF00</td>
<td>Used to denote an asynchronous locate message.</td>
</tr>
<tr>
<td>MSGQ_ASYNCERRORMSGID</td>
<td>0xFF01</td>
<td>Used to denote an asynchronous transport error.</td>
</tr>
<tr>
<td>MSGQ_INVALIDMSGID</td>
<td>0xFFFF</td>
<td>Used as initial value when message is allocated.</td>
</tr>
</tbody>
</table>

**Constraints and Calling Context**

- Message must have been allocated originally from `MSGQ_alloc`. 
Example

/* Fill in the message */
msg->sequenceNumber = 0;
MSGQ_setMsgId((MSGQ_Msg)msg, MESSAGEID);

/* Send the message */
status = MSGQ_put(readerMsgQueue, (MSGQ_Msg)msg);
    if (status != SYS_OK) {
        SYS_abort("Failed to send the message");
    }

See Also
 MSGQ_getMsgId
 MSGQ_setErrorHandler
MSGQ_setSrcQueue  

Set the reply destination in a message

C Interface

Syntax

```c
MSGQ_setSrcQueue(msg, msgQueue);
```

Parameters

- `MSGQ_MSG msg; /* Message */`
- `MSGQ_Queue msgQueue; /* Message queue */`

Return Value

`Void`

Reentrant

yes

Description

This API allows the sender to specify a message queue that the receiver of the message can reply back to (via MSGQ_getSrcQueue). The `msgQueue` must have been returned by MSGQ_open.

Inside each message is a source message queue field. When a message is allocated, the value of this field is MSGQ_INVALIDMSGQ. When this API is called, it updates the field accordingly. This API can be called multiple times on a message.

If a message is sent to another processor, the source message queue field is managed by the transports accordingly.

Constraints and Calling Context

- Message must have been allocated originally from MSGQ_alloc.
- `msgQueue` must have been returned from MSGQ_open.

Example

```c
/* Fill in the message */
msg->sequenceNumber = 0;
MSGQ_setSrcQueue((MSGQ_Msg)msg, writerMsgQueue);

/* Send the message */
status = MSGQ_put(readerMsgQueue, (MSGQ_Msg)msg);
if (status != SYS_OK) {
    SYS_abort("Failed to send the message");
}
```

See Also

- MSGQ_getSrcQueue
2.17 PIP Module

Important: The PIP module is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

The PIP module is the buffered pipe manager.

Functions

- **PIP_alloc.** Get an empty frame from the pipe.
- **PIP_free.** Recycle a frame back to the pipe.
- **PIP_get.** Get a full frame from the pipe.
- **PIP_getReaderAddr.** Get the value of the readerAddr pointer of the pipe.
- **PIP_getReaderNumFrames.** Get the number of pipe frames available for reading.
- **PIP_getReaderSize.** Get the number of words of data in a pipe frame.
- **PIP_getWriterAddr.** Get the value of the writerAddr pointer of the pipe.
- **PIP_getWriterNumFrames.** Get the number of pipe frames available to write to.
- **PIP_getWriterSize.** Get the number of words that can be written to a pipe frame.
- **PIP.peek.** Get the pipe frame size and address without actually claiming the pipe frame.
- **PIP_put.** Put a full frame into the pipe.
- **PIP_reset.** Reset all fields of a pipe object to their original values.
- **PIP_setWriterSize.** Set the number of valid words written to a pipe frame.

**PIP_Obj Structure**

**Members**

- **Ptr readerAddr.** Pointer to the address to begin reading from after calling PIP_get.
- **Uns readerSize.** Number of words of data in the frame read with PIP_get.
- **Uns readerNumFrames.** Number of frames available to be read.
- **Ptr writerAddr.** Pointer to the address to begin writing to after calling PIP_alloc.
- **Uns writerSize.** Number of words available in the frame allocated with PIP_alloc.
- **Uns writerNumFrames.** Number of frames available to be written to.

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the PIP Manager Properties and PIP Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

**Module Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>
Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>bufSeg</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>bufAlign</td>
<td>Int16</td>
<td>1</td>
</tr>
<tr>
<td>frameSize</td>
<td>Int16</td>
<td>8</td>
</tr>
<tr>
<td>numFrames</td>
<td>Int16</td>
<td>2</td>
</tr>
<tr>
<td>monitor</td>
<td>EnumString</td>
<td>&quot;reader&quot; (&quot;writer&quot;, &quot;none&quot;)</td>
</tr>
<tr>
<td>notifyWriterFxnx</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>notifyWriterArg0</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>notifyWriterArg1</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>notifyReaderFxnx</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>notifyReaderArg0</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>notifyReaderArg1</td>
<td>Arg</td>
<td>0</td>
</tr>
</tbody>
</table>

Description

The PIP module manages data pipes, which are used to buffer streams of input and output data. These data pipes provide a consistent software data structure you can use to drive I/O between the DSP device and all kinds of real-time peripheral devices.

Each pipe object maintains a buffer divided into a fixed number of fixed length frames, specified by the numframes and framesize properties. All I/O operations on a pipe deal with one frame at a time; although each frame has a fixed length, the application can put a variable amount of data in each frame up to the length of the frame.

A pipe has two ends, as shown in Figure Figure 2-7. The writer end (also called the producer) is where your program writes frames of data. The reader end (also called the consumer) is where your program reads frames of data.

**Figure 2-7. Pipe Schematic**

Internally, pipes are implemented as a circular list; frames are reused at the writer end of the pipe after PIP_free releases them.

The notifyReader and notifyWriter functions are called from the context of the code that calls PIP_put or PIP_free. These functions can be written in C or assembly. To avoid problems with recursion, the notifyReader and notifyWriter functions normally should not directly call any of the PIP module functions.
for the same pipe. Instead, they should post a SWI that uses the PIP module functions. However, PIP calls may be made from the notifyReader and notifyWriter functions if the functions have been protected against re-entrancy.

**Note:** When DSP/BIOS starts up, it calls the notifyWriter function internally for each created pipe object to initiate the pipe’s I/O.

The code that calls PIP_free or PIP_put should preserve any necessary registers.

Often one end of a pipe is controlled by an HWI and the other end is controlled by a SWI function, such as SWI_andnHook.

HST objects use PIP objects internally for I/O between the host and the target. Your program only needs to act as the reader or the writer when you use an HST object, because the host controls the other end of the pipe.

Pipes can also be used to transfer data within the program between two application threads.

**PIP Manager Properties**

The pipe manager manages objects that allow the efficient transfer of frames of data between a single reader and a single writer. This transfer is often between an HWI and a SWI, but pipes can also be used to transfer data between two application threads.

The following global property can be set for the PIP module in the PIP Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the PIP objects.
  
  **Tconf Name:** OBJMEMSEG  
  **Type:** Reference
  
  **Example:**
  ```
  bios.PIP.OBJMEMSEG = prog.get("myMEM");
  ```

**PIP Object Properties**

A pipe object maintains a single contiguous buffer partitioned into a fixed number of fixed length frames. All I/O operations on a pipe deal with one frame at a time; although each frame has a fixed length, the application can put a variable amount of data in each frame (up to the length of the frame).

To create a PIP object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```javascript
var myPip = bios.PIP.create("myPip");
```

The following properties can be set for a PIP object in the PIP Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this PIP object.
  
  **Tconf Name:** comment  
  **Type:** String
  
  **Example:**
  ```
  myPip.comment = "my PIP";
  ```

- **bufseg.** The memory segment that the buffer is allocated within; all frames are allocated from a single contiguous buffer (of size framesize x numframes).
  
  **Tconf Name:** bufSeg  
  **Type:** Reference
  
  **Example:**
  ```
  myPip.bufSeg = prog.get("myMEM");
  ```
• **bufalign.** The alignment (in words) of the buffer allocated within the specified memory segment.
  
  **Tconf Name:** bufAlign  
  **Type:** Int16

  **Example:**  
  ```cpp
  myPip.bufAlign = 1;
  ```

• **framesize.** The length of each frame (in words)
  
  **Tconf Name:** frameSize  
  **Type:** Int16

  **Example:**  
  ```cpp
  myPip.frameSize = 8;
  ```

• **numframes.** The number of frames
  
  **Tconf Name:** numFrames  
  **Type:** Int16

  **Example:**  
  ```cpp
  myPip.numFrames = 2;
  ```

• **monitor.** The end of the pipe to be monitored by a hidden STS object. Can be set to reader, writer, or nothing. In the Statistics View analysis tool, your choice determines whether the STS display for this pipe shows a count of the number of frames handled at the reader or writer end of the pipe.
  
  **Tconf Name:** monitor  
  **Type:** EnumString

  **Options:**  
  ```cpp
  "reader", "writer", "none"
  ```

  **Example:**  
  ```cpp
  myPip.monitor = "reader";
  ```

• **notifyWriter.** The function to execute when a frame of free space is available. This function should notify (for example, by calling SWI_andnHook) the object that writes to this pipe that an empty frame is available.

  The notifyWriter function is performed as part of the thread that called PIP_free or PIP_alloc. To avoid problems with recursion, the notifyWriter function should not directly call any of the PIP module functions for the same pipe.

  **Tconf Name:** notifyWriterFxn  
  **Type:** Extern

  **Example:**  
  ```cpp
  myPip.notifyWriterFxn = prog.extern("writerFxn");
  ```

• **nwarg0, nwarg1.** Two Arg type arguments for the notifyWriter function.

  **Tconf Name:** notifyWriterArg0  
  **Type:** Arg

  **Tconf Name:** notifyWriterArg1  
  **Type:** Arg

  **Example:**  
  ```cpp
  myPip.notifyWriterArg0 = 0;
  ```

• **notifyReader.** The function to execute when a frame of data is available. This function should notify (for example, by calling SWI_andnHook) the object that reads from this pipe that a full frame is ready to be processed.

  The notifyReader function is performed as part of the thread that called PIP_put or PIP_get. To avoid problems with recursion, the notifyReader function should not directly call any of the PIP module functions for the same pipe.

  **Tconf Name:** notifyReaderFxn  
  **Type:** Extern

  **Example:**  
  ```cpp
  myPip.notifyReaderFxn = prog.extern("readerFxn");
  ```

• **nrarg0, nrarg1.** Two Arg type arguments for the notifyReader function.

  **Tconf Name:** notifyReaderArg0  
  **Type:** Arg

  **Tconf Name:** notifyReaderArg1  
  **Type:** Arg

  **Example:**  
  ```cpp
  myPip.notifyReaderArg0 = 0;
  ```
**PIP_alloc**

*Allocate an empty frame from a pipe*

**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

**C Interface**

**Syntax**

```c
PIP_alloc(pipe);
```

**Parameters**

- `PIP_Handle pipe; /* pipe object handle */`

**Return Value**

`Void`

**Reentrant**

`no`

**Description**

`PIP_alloc` allocates an empty frame from the pipe you specify. You can write to this frame and then use `PIP_put` to put the frame into the pipe.

If empty frames are available after `PIP_alloc` allocates a frame, `PIP_alloc` runs the function specified by the `notifyWriter` property of the PIP object. This function should notify (for example, by calling `SWI_andnHook`) the object that writes to this pipe that an empty frame is available. The `notifyWriter` function is performed as part of the thread that calls `PIP_free` or `PIP_alloc`. To avoid problems with recursion, the `notifyWriter` function should not directly call any PIP module functions for the same pipe.

**Constraints and Calling Context**

- Before calling `PIP_alloc`, a function should check the `writerNumFrames` member of the `PIP_Obj` structure by calling `PIP_getWriterNumFrames` to make sure it is greater than 0 (that is, at least one empty frame is available).
- `PIP_alloc` can only be called one time before calling `PIP_put`. You cannot operate on two frames from the same pipe simultaneously.
Example

```c
Void copy(HST_Obj *input, HST_Obj *output)
{
  PIP_Obj  *in, *out;
  Uns      *src, *dst;
  Uns      size;

  in = HST_getpipe(input);
  out = HST_getpipe(output);

  if (PIP_getReaderNumFrames(in) == 0 ||
      PIP_getWriterNumFrames(out) == 0) {
    error;
  }

  /* get input data and allocate output frame */
  PIP_get(in);
  PIP_alloc(out);

  /* copy input data to output frame */
  src = PIP_getReaderAddr(in);
  dst = PIP_getWriterAddr(out);
  size = PIP_getReaderSize(in);
  PIP_setWriterSize(out, size);
  for (; size > 0; size--) {
    *dst++ = *src++;
  }

  /* output copied data and free input frame */
  PIP_put(out);
  PIP_free(in);
}
```

The example for HST_getpipe, page 2–152, also uses a pipe with host channel objects.

See Also
- PIP_free
- PIP_get
- PIP_put
- HST_getpipe
**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

### C Interface

**Syntax**

```c
void PIP_free(pipe);
```

**Parameters**

- `PIP_Handle pipe; /* pipe object handle */`

**Return Value**

- `Void`

**Reentrant**

- `no`

**Description**

`PIP_free` releases a frame after you have read the frame with `PIP_get`. The frame is recycled so that `PIP_alloc` can reuse it.

After `PIP_free` releases the frame, it runs the function specified by the `notifyWriter` property of the `PIP` object. This function should notify (for example, by calling `SWI_andnHook`) the object that writes to this pipe that an empty frame is available. The `notifyWriter` function is performed as part of the thread that called `PIP_free` or `PIP_alloc`. To avoid problems with recursion, the `notifyWriter` function should not directly call any of the `PIP` module functions for the same pipe.

**Constraints and Calling Context**

- When called within an HWI, the code sequence calling `PIP_free` must be either wrapped within an `HWI_enter/HWI_exit` pair or invoked by the HWI dispatcher.

**Example**

See the example for `PIP_alloc`, page 2–263. The example for `HST_getpipe`, page 2–152, also uses a pipe with host channel objects.

**See Also**

- `PIP_alloc`
- `PIP_get`
- `PIP_put`
- `HST_getpipe`
PIP_get

Get a full frame from the pipe

Important: This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

C Interface

Syntax

```c
PIP_get(pipe);
```

Parameters

- `PIP_Handle pipe; /* pipe object handle */`

Return Value

Void

Reentrant

no

Description

`PIP_get` gets a frame from the pipe after some other function puts the frame into the pipe with `PIP_put`. If full frames are available after `PIP_get` gets a frame, `PIP_get` runs the function specified by the notifyReader property of the PIP object. This function should notify (for example, by calling `SWI_andnHook`) the object that reads from this pipe that a full frame is available. The notifyReader function is performed as part of the thread that calls `PIP_get` or `PIP_put`. To avoid problems with recursion, the notifyReader function should not directly call any PIP module functions for the same pipe.

Constraints and Calling Context

- Before calling `PIP_get`, a function should check the readerNumFrames member of the PIP_Obj structure by calling `PIP_getReaderNumFrames` to make sure it is greater than 0 (that is, at least one full frame is available).
- `PIP_get` can only be called one time before calling `PIP_free`. You cannot operate on two frames from the same pipe simultaneously.

Example

See the example for `PIP_alloc`, page 2–263. The example for `HST_getpipe`, page 2–152, also uses a pipe with host channel objects.

See Also

- `PIP_alloc`
- `PIP_free`
- `PIP_put`
- `HST_getpipe`
PIP_getReaderAddr  Get the value of the readerAddr pointer of the pipe

**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

### C Interface

**Syntax**

```
readerAddr = PIP_getReaderAddr(pipe);
```

**Parameters**

- `PIP_Handle pipe; /* pipe object handle */`

**Return Value**

- `Ptr readerAddr`

**Reentrant**

- `yes`

**Description**

`PIP_getReaderAddr` is a C function that returns the value of the readerAddr pointer of a pipe object. The readerAddr pointer is normally used following a call to `PIP_get`, as the address to begin reading from.

**Example**

```
Void audio(PIP_Obj *in, PIP_Obj *out)
{
    Uns         *src, *dst;
    Uns         size;

    if (PIP_getReaderNumFrames(in) == 0 ||
        PIP_getWriterNumFrames(out) == 0) {
        error;
    }  
    PIP_get(in);    /* get input data */
    PIP_alloc(out); /* allocate output buffer */

    /* copy input data to output buffer */
    src = PIP_getReaderAddr(in);
    dst = PIP_getWriterAddr(out);
    size = PIP_getReaderSize(in);
    PIP_setWriterSize(out, size);
    for (; size > 0; size--) {
        *dst++ = *src++;
    }

    /* output copied data and free input buffer */
    PIP_put(out);
    PIP_free(in);
}
```
PIP_getReaderNumFrames

Get the number of pipe frames available for reading

Important: This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

C Interface

Syntax

```c
num = PIP_getReaderNumFrames(pipe);
```

Parameters

- `PIP_Handle pipe; /* pip object handle */`
- `Uns num; /* number of filled frames to be read */`

Reentrant

yes

Description

PIP_getReaderNumFrames is a C function that returns the value of the readerNumFrames element of a pipe object.

Before a function attempts to read from a pipe it should call PIP_getReaderNumFrames to ensure at least one full frame is available.

Example

See the example for PIP_getReaderAddr, page 2–267.
**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

### C Interface

**Syntax**

```c
num = PIP_getReaderSize(pipe);
```

**Parameters**

- `PIP_Handle pipe; /* pipe object handle*/`

**Return Value**

- `Uns num; /* number of words to be read from filled frame */`

**Reentrant**

- Yes

### Description

`PIP_getReaderSize` is a C function that returns the value of the `readerSize` element of a pipe object.

As a function reads from a pipe it should use `PIP_getReaderSize` to determine the number of valid words of data in the pipe frame.

### Example

See the example for `PIP_getReaderAddr`, page 2–267.
**PIP_getWriterAddr**  
*Get the value of the writerAddr pointer of the pipe*

**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface**

**Syntax**

```c
writerAddr = PIP_getWriterAddr(pipe);
```

**Parameters**

- `PIP_Handle pipe; /* pipe object handle */`

**Return Value**

- `Ptr writerAddr;`

**Reentrant**

- `yes`

**Description**

PIP_getWriterAddr is a C function that returns the value of the writerAddr pointer of a pipe object. The writerAddr pointer is normally used following a call to PIP_alloc, as the address to begin writing to.

**Example**

See the example for PIP_getReaderAddr, page 2–267.
**PIP_getWriterNumFrames**  
*Get number of pipe frames available to be written to*

**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

---

**C Interface**

**Syntax**

```c
num = PIP_getWriterNumFrames(pipe);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>PIP_Handle</td>
<td>pipe;</td>
</tr>
</tbody>
</table>

**Return Value**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Uns</td>
<td>num;</td>
</tr>
</tbody>
</table>

**Reentrant**

yes

**Description**

PIP_getWriterNumFrames is a C function that returns the value of the writerNumFrames element of a pipe object.

Before a function attempts to write to a pipe, it should call PIP_getWriterNumFrames to ensure at least one empty frame is available.

**Example**

See the example for PIP_getReaderAddr, page 2–267.
**PIP_getWriterSize**

*Get the number of words that can be written to a pipe frame*

**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

**C Interface**

**Syntax**

```
num = PIP_getWriterSize(pipe);
```

**Parameters**

- `PIP_Handle pipe; /* pipe object handle*/`

**Return Value**

- `Uns num; /* num of words to be written in empty frame */`

**Reentrant**

yes

**Description**

PIP_getWriterSize is a C function that returns the value of the writerSize element of a pipe object. As a function writes to a pipe, it can use PIP_getWriterSize to determine the maximum number words that can be written to a pipe frame.

**Example**

```
if (PIP_getWriterNumFrames(rxPipe) > 0) {
    PIP_alloc(rxPipe);
    DSS_rxPtr = PIP_getWriterAddr(rxPipe);
    DSS_rxCnt = PIP_getWriterSize(rxPipe);
}
```
**PIP_peak**  
*Get pipe frame size and address without actually claiming pipe frame*

**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

### C Interface

**Syntax**

```c
framesize = PIP_peek(pipe, addr, rw);
```

**Parameters**

- `PIP_Handle pipe;` /* pipe object handle */
- `Ptr *addr;` /* address of variable with frame address */
- `Uns rw;` /* flag to indicate the reader or writer side */

**Return Value**

- `Int framesize;` /* the frame size */

**Description**

`PIP_peek` can be used before calling `PIP_alloc` or `PIP_get` to get the pipe frame size and address without actually claiming the pipe frame.

The pipe parameter is the pipe object handle, the addr parameter is the address of the variable that keeps the retrieved frame address, and the rw parameter is the flag that indicates what side of the pipe `PIP_peek` is to operate on. If `rw` is `PIP_READER`, then `PIP_peek` operates on the reader side of the pipe. If `rw` is `PIP_WRITER`, then `PIP_peek` operates on the writer side of the pipe.

`PIP_getReaderNumFrames` or `PIP_getWriterNumFrames` can be called to ensure that a frame exists before calling `PIP_peek`, although `PIP_peek` returns –1 if no pipe frame exists.

`PIP_peek` returns the frame size, or –1 if no pipe frames are available. If the return value of `PIP_peek` in frame size is not –1, then `*addr` is the location of the frame address.

**See Also**

- `PIP_alloc`
- `PIP_free`
- `PIP_get`
- `PIP_put`
- `PIP_reset`
**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

### C Interface

**Syntax**

```c
PIP_put(pipe);
```

**Parameters**

- `PIP_Handle pipe; /* pipe object handle */`

**Return Value**

`Void`

**Reentrant**

`no`

**Description**

`PIP_put` puts a frame into a pipe after you have allocated the frame with `PIP_alloc` and written data to the frame. The reader can then use `PIP_get` to get a frame from the pipe.

After `PIP_put` puts the frame into the pipe, it runs the function specified by the `notifyReader` property of the PIP object. This function should notify (for example, by calling `SWI_andnHook`) the object that reads from this pipe that a full frame is ready to be processed. The `notifyReader` function is performed as part of the thread that called `PIP_get` or `PIP_put`. To avoid problems with recursion, the `notifyReader` function should not directly call any of the PIP module functions for the same pipe.

### Constraints and Calling Context

- When called within an HWI, the code sequence calling `PIP_put` must be either wrapped within an `HWI_enter/HWI_exit` pair or invoked by the HWI dispatcher.

### Example

See the example for `PIP_alloc`, page 2–263. The example for `HST_getpipe`, page 2–152, also uses a pipe with host channel objects.

### See Also

- `PIP_alloc`
- `PIP_free`
- `PIP_get`
- `HST_getpipe`
Important: This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

C Interface

Syntax

```
PIP_reset(pipe);
```

Parameters

```
PIP_Handle pipe; /* pipe object handle */
```

Return Value

Void

Description

`PIP_reset` resets all fields of a pipe object to their original values.

The pipe parameter specifies the address of the pipe object that is to be reset.

Constraints and Calling Context

- `PIP_reset` should not be called between the `PIP_alloc` call and the `PIP_put` call or between the `PIP_get` call and the `PIP_free` call.
- `PIP_reset` should be called when interrupts are disabled to avoid the race condition.

See Also

- `PIP_alloc`
- `PIP_free`
- `PIP_get`
- `PIP_peek`
- `PIP_put`
**PIP_setWriterSize**  
*Set the number of valid words written to a pipe frame*

**Important:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. We recommend that you use the SIO module instead.

### C Interface

**Syntax**

```c
PIP_setWriterSize(pipe, size);
```

**Parameters**

- `PIP_Handle pipe;` /* pipe object handle */
- `Uns size;` /* size to be set */

**Return Value**

- `Void`

**Reentrant**

- `no`

**Description**

`PIP_setWriterSize` is a C function that sets the value of the writerSize element of a pipe object.  

As a function writes to a pipe, it can use `PIP_setWriterSize` to indicate the number of valid words being written to a pipe frame.

**Example**

See the example for `PIP_getReaderAddr`, page 2–267.
2.18 POOL Module

The POOL module describes the interface that allocators must provide.

Functions

None; this module describes an interface to be implemented by allocators

Constants, Types, and Structures

POOL_Config POOL_config;

typedef struct POOL_Config {
    POOL_Obj *allocators; /* Array of allocators */
    Uint16 numAllocators; /* Num of allocators */
} POOL_Config;

typedef struct POOL_Obj {
    POOL_Init initFxn; /* Allocator init function */
    POOL_Fxns *fxns; /* Interface functions */
    Ptr params; /* Setup parameters */
    Ptr object; /* Allocator’s object */
} POOL_Obj, *POOL_Handle;

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the POOL Manager Properties heading. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>ENABLEPOOL</td>
<td>Bool</td>
<td>false</td>
</tr>
</tbody>
</table>

Description

The POOL module describes standard interface functions that allocators must provide. The allocator interface functions are called internally by the MSGQ module and not by user applications. A simple static allocator, called STATICPOOL, is provided with DSP/BIOS. Other allocators can be implemented by following the standard interface.

Note: This document does not discuss how to write an allocator. Information about designing allocators will be provided in a future document.

All messages sent via the MSGQ module must be allocated by an allocator. The allocator determines where and how the memory for the message is allocated.

An allocator is an instance of an implementation of the allocator interface. An application may instantiate one or more instances of an allocator.
An application can use multiple allocators. The purpose of having multiple allocators is to allow an application to regulate its message usage. For example, an application can allocate critical messages from one pool of fast on-chip memory and non-critical messages from another pool of slower external memory.

![allocator diagram]

**Figure 2-8. Allocators and Message Pools**

### Static Configuration

In order to use an allocator and the POOL module, you must statically configure the following:

- **ENABLEPOOL** property of the POOL module using Tconf (see “POOL Manager Properties” on page 280)
- **POOL_config** variable in application code (see below)

An application must provide a filled in **POOL_config** variable if it uses one or more allocators.

```c
POOL_Config POOL_config;
```

Where the **POOL_Config** structure has the following structure:

```c
typedef struct POOL_Config {
    POOL_Obj *allocators;    /* Array of allocators */
    Uint16    numAllocators; /* Num of allocators */
} POOL_Config;
```

The fields in this structure are as follows:

<table>
<thead>
<tr>
<th>Field</th>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>allocators</td>
<td>POOL_Obj</td>
<td>Array of allocator objects</td>
</tr>
<tr>
<td>numAllocators</td>
<td>Uint16</td>
<td>Number of allocators in the allocator array.</td>
</tr>
</tbody>
</table>

If the POOL module is enabled via Tconf and the application does not provide the **POOL_config** variable, the application cannot be linked successfully.

The following is the **POOL_Obj** structure:

```c
typedef struct POOL_Obj {
    POOL_Init  initFxn;  /* Allocator init function */
    POOL_Fxns *fxns;     /* Interface functions */
    Ptr        params;   /* Setup parameters */
    Ptr        object;   /* Allocator’s object */
} POOL_Obj, *POOL_Handle;
```
The fields in the `POOL_Obj` structure are as follows:

<table>
<thead>
<tr>
<th>Field</th>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>initFxn</td>
<td>POOL_Init</td>
<td>Initialization function for this allocator. This function will be called during DSP/BIOS initialization. More explicitly it is called before main().</td>
</tr>
<tr>
<td>fxns</td>
<td>POOL_Fxns *</td>
<td>Pointer to the allocator's interface functions.</td>
</tr>
<tr>
<td>params</td>
<td>Ptr</td>
<td>Pointer to the allocator's parameters. This field is allocator-specific. Please see the documentation provided with your allocator for a description of this field.</td>
</tr>
<tr>
<td>object</td>
<td>Ptr</td>
<td>State information needed by the allocator. This field is initialized and managed by the allocator. See the allocator documentation to determine how to specify this field.</td>
</tr>
</tbody>
</table>

One allocator implementation (STATICPOOL) is shipped with DSP/BIOS. Additional allocator implementations can be created by application writers.

**STATICPOOL Allocator**

The STATICPOOL allocator takes a user-specified buffer and allocates fixed-size messages from the buffer. The following are its configuration parameters:

```c
typedef struct STATICPOOL_Params {
  Ptr   addr;
  size_t length;
  size_t bufferSize;
} STATICPOOL_Params;
```

The following table describes the fields in this structure:

<table>
<thead>
<tr>
<th>Field</th>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>addr</td>
<td>Ptr</td>
<td>User supplied block of memory for allocating messages from. The address will be aligned on an 8 MADU boundary for correct structure alignment on all ISAs. If there is a chance the buffer is not aligned, allow at least 7 extra MADUs of space to allow room for the alignment. You can use the DATA_ALIGN pragma to force alignment yourself.</td>
</tr>
<tr>
<td>length</td>
<td>size_t</td>
<td>Size of the block of memory pointed to by addr.</td>
</tr>
<tr>
<td>bufferSize</td>
<td>size_t</td>
<td>Size of the buffers in the block of memory. The bufferSize must be a multiple of 8 to allow correct structure alignment.</td>
</tr>
</tbody>
</table>

The following figure shows how the fields in `STATICPOOL_Params` define the layout of the buffer:
Since the STATICPOOL buffer is generally used in static systems, the application must provide the memory for the STATICPOOL_Obj. So the object field of the POOL_Obj must be set to STATICPOOL_Obj instead of NULL.

The following is an example of an application that has two allocators (two instances of the STATICPOOL implementation).

```c
#define NUMMSGS  8  /* Number of msgs per allocator */

/* Size of messages in the two allocators. Must be a
 * multiple of 8 as required by static allocator. */
#define MSGSIZE0   64
#define MSGSIZE1  128

enum {  /* Allocator ID and number of allocators */
    MQASTATICID0 = 0,
    MQASTATICID1,
    NUMALLOCATORS
};

#pragma DATA_ALIGN(staticBuf0, 8) /* As required */
#pragma DATA_ALIGN(staticBuf1, 8) /* As required */
static Char staticBuf0[MSGSIZE0 * NUMMSGS];
static Char staticBuf1[MSGSIZE1 * NUMMSGS];

static MQASTATIC_Params poolParams0 = {staticBuf0,
    sizeof(staticBuf0), MSGSIZE0};
static MQASTATIC_Params poolParams1 = {staticBuf1,
    sizeof(staticBuf1), MSGSIZE1};

static STATICPOOL_Obj poolObj0, poolObj1;

static POOL_Obj allocators[NUMALLOCATORS] =
    {{STATICPOOL_init, (POOL_Fxns *)&STATICPOOL_FXNS,
        &poolParams0, &poolObj0}
    {{STATICPOOL_init, (POOL_Fxns *)&STATICPOOL_FXNS,
        &poolParams1, &poolObj1}};

POOL_Config  POOL_config =
    {allocators, NUMALLOCATORS};
```

**POOL Manager Properties**

To configure the POOL manager, the POOL_Config structure must be defined in the application code. See “Static Configuration” on page 278.

The following global property must also be set in order to use the POOL module:

- **Enable POOL Manager.** If ENABLEPOOL is TRUE, each allocator specified in the POOL_config structure (see “Static Configuration” on page 278) is initialized and opened.

  ```
  Tconf Name:    ENABLEPOOL    Type: Bool
  Example:      bios.POOL.ENABLEPOOL = true;
  ```
2.19 PRD Module

The PRD module is the periodic function manager.

Functions

- PRD_getticks. Get the current tick count.
- PRD_start. Arm a periodic function for one-time execution.
- PRD_stop. Stop a periodic function from execution.
- PRD_tick. Advance tick counter, dispatch periodic functions.

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the PRD Manager Properties and PRD Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>USECLK</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>MICROSECONDS</td>
<td>Int16</td>
<td>1000.0</td>
</tr>
</tbody>
</table>

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>period</td>
<td>Int16</td>
<td>32767</td>
</tr>
<tr>
<td>mode</td>
<td>EnumString</td>
<td>&quot;continuous&quot; (&quot;one-shot&quot;)</td>
</tr>
<tr>
<td>fxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>arg0</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>arg1</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>order</td>
<td>Int16</td>
<td>0</td>
</tr>
</tbody>
</table>

Description

While some applications can schedule functions based on a real-time clock, many applications need to schedule functions based on I/O availability or some other programmatic event.

The PRD module allows you to create PRD objects that schedule periodic execution of program functions. The period can be driven by the CLK module or by calls to PRD_tick whenever a specific event occurs. There can be several PRD objects, but all are driven by the same period counter. Each PRD object can execute its functions at different intervals based on the period counter.

- **To schedule functions based on a real-time clock.** Set the clock interrupt rate you want to use in the CLK Object Properties. Set the "Use On-chip Clock (CLK)" property of the PRD Manager Properties to true. Set the frequency of execution (in number of clock interrupt ticks) in the period property for the individual period object.
• **To schedule functions based on I/O availability or some other event.** Set the "Use On-chip Clock (CLK)" property of the PRD Manager Properties to false. Set the frequency of execution (in number of ticks) in the period property for the individual period object. Your program should call PRD_tick to increment the tick counter.

The function executed by a PRD object is statically defined in the configuration. PRD functions are called from the context of the function run by the PRD_swi SWI object. PRD functions can be written in C or assembly and must follow the C calling conventions described in the compiler manual.

The PRD module uses a SWI object (called PRD_swi by default) which itself is triggered on a periodic basis to manage execution of period objects. Normally, this SWI object should have the highest SWI priority to allow this SWI to be performed once per tick. This SWI is automatically created (or deleted) by the configuration if one or more (or no) PRD objects exist. The total time required to perform all PRD functions must be less than the number of microseconds between ticks. Any more lengthy processing should be scheduled as a separate SWI, TSK, or IDL thread.

See the [Code Composer Studio](http://www.ti.com) online tutorial for an example that demonstrates the interaction between the PRD module and the SWI module.

When the PRD_swi object runs its function, the following actions occur:

```c
for ("Loop through period objects") {
  if ("time for a periodic function")
    "run that periodic function";
}
```

### PRD Manager Properties

The DSP/BIOS Periodic Function Manager allows the creation of an arbitrary number of objects that encapsulate a function, two arguments, and a period specifying the time between successive invocations of the function. The period is expressed in ticks, and a tick is defined as a single invocation of the PRD_tick operation. The time between successive invocations of PRD_tick defines the period represented by a tick.

The following global properties can be set for the PRD module in the PRD Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment containing the PRD objects.
  - **Tconf Name:** OBJMEMSEG
  - **Type:** Reference
  - **Example:**
    ```
    bios.PRD.OBJMEMSEG = prog.get("myMEM");
    ```

- **Use CLK Manager to drive PRD.** If this property is set to true, the on-device timer hardware (managed by the CLK Module) is used to advance the tick count; otherwise, the application must invoke PRD_tick on a periodic basis. If the CLK module is used to drive PRDs, the ticks are equal to the low-resolution time increment rate.
  - **Tconf Name:** USECLK
  - **Type:** Bool
  - **Example:**
    ```
    bios.PRD.USECLK = true;
    ```

- **Microseconds/Tick.** The number of microseconds between ticks. If the "Use CLK Manager to drive PRD field" property above is set to true, this property is automatically set by the CLK module; otherwise, you must explicitly set this property. The total time required to perform all PRD functions must be less than the number of microseconds between ticks.
  - **Tconf Name:** MICROSECONDS
  - **Type:** Int16
  - **Example:**
    ```
    bios.PRD.MICROSECONDS = 1000.0;
    ```
PRD Object Properties

To create a PRD object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```javascript
var myPrd = bios.PRD.create("myPrd");
```

If you cannot create a new PRD object (an error occurs or the Insert PRD item is inactive in the DSP/BIOS Configuration Tool), increase the Stack Size property in the MEM Manager Properties before adding a PRD object.

The following properties can be set for a PRD object in the PRD Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this PRD object.
  
  Tconf Name: comment Type: String
  
  Example: `myPrd.comment = "my PRD";`

- **period (ticks).** The function executes after this number of ticks have elapsed.
  
  Tconf Name: period Type: Int16
  
  Example: `myPrd.period = 32767;`

- **mode.** If "continuous" is used, the function executes every "period" number of ticks. If "one-shot" is used, the function executes just once after "period" ticks.
  
  Tconf Name: mode Type: EnumString
  
  Options: "continuous", "one-shot"
  
  Example: `myPrd.mode = "continuous";`

- **function.** The function to be executed. The total time required to perform all PRD functions must be less than the number of microseconds between ticks.
  
  Tconf Name: fxn Type: Extern
  
  Example: `myPrd.fxn = prog.extern("prdFxn");`

- **arg0, arg1.** Two Arg type arguments for the user-specified function above.
  
  Tconf Name: arg0 Type: Arg
  
  Tconf Name: arg1 Type: Arg
  
  Example: `myPrd.arg0 = 0;`

- **period (ms).** The number of milliseconds represented by the period specified above. This is an informational property only.
  
  Tconf Name: N/A

- **order.** Set this property to all PRD objects so that the numbers match the sequence in which PRD functions should be executed.
  
  Tconf Name: order Type: Int16
  
  Example: `myPrd.order = 2;`
PRD_getticks

Get the current tick count

C Interface

Syntax

    num = PRD_getticks();

Parameters

    Void

Return Value

    LgUns num /* current tick counter */

Reentrant

    yes

Description

PRD_getticks returns the current period tick count as a 32-bit value.

If the periodic functions are being driven by the on-device timer, the tick value is the number of low
resolution clock ticks that have occurred since the program started running. When the number of ticks
reaches the maximum value that can be stored in 32 bits, the value wraps back to 0. See the CLK Module,
page 2–59, for more details.

If the periodic functions are being driven programmatically, the tick value is the number of times PRD_tick
has been called.

Example

    /* ======== showTicks ======== */
    Void showTicks
    {
        LOG_printf(&trace, "ticks = %d", PRD_getticks());
    }

See Also

    PRD_start
    PRD_tick
    CLK_gethtime
    CLK_getltime
    STS_delta
PRD_start  

Arm a periodic function for one-shot execution

C Interface

Syntax

PRD_start(prd);

Parameters

PRD_Handle prd; /* prd object handle*/

Return Value

Void

Reentrant

no

Description

PRD_start starts a period object that has its mode property set to one-shot in the configuration. Unlike PRD objects that are configured as continuous, one-shot PRD objects do not automatically continue to run. A one-shot PRD object runs its function only after the specified number of ticks have occurred after a call to PRD_start.

For example, you might have a function that should be executed a certain number of periodic ticks after some condition is met.

When you use PRD_start to start a period object, the exact time the function runs can vary by nearly one tick cycle. As Figure Figure 2-10 shows, PRD ticks occur at a fixed rate and the call to PRD_start can occur at any point between ticks

![Figure 2-10. PRD Tick Cycles](image)

If PRD_start is called again before the period for the object has elapsed, the object’s tick count is reset. The PRD object does not run until its “period” number of ticks have elapsed.

Example

/* ======== startPRD ======== */
Void startPrd(Int periodID)
{
    if ("condition met") {
        PRD_start(&periodID);
    }
}

See Also

PRD_tick
PRD_getticks
PRD_stop  Stop a period object to prevent its function execution

C Interface

Syntax
   PRD_stop(prd);

Parameters
   PRD_Handle prd; /* prd object handle*/

Return Value
   Void

Reentrant
   no

Description
   PRD_stop stops a period object to prevent its function execution. In most cases, PRD_stop is used to
   stop a period object that has its mode property set to one-shot in the configuration.

   Unlike PRD objects that are configured as continuous, one-shot PRD objects do not automatically
   continue to run. A one-shot PRD object runs its function only after the specified numbers of ticks have
   occurred after a call to PRD_start.

   PRD_stop is the way to stop those one-shot PRD objects once started and before their period counters
   have run out.

Example
   PRD_stop(&prd);

See Also
   PRD_getticks
   PRD_start
   PRD_tick
**PRD_tick**  
*Advance tick counter, enable periodic functions*

**C Interface**

**Syntax**
```
PRD_tick();
```

**Parameters**
- Void

**Return Value**
- Void

**Reentrant**
- no

**Description**

PRD_tick advances the period counter by one tick. Unless you are driving PRD functions using the on-device clock, PRD objects execute their functions at intervals based on this counter.

For example, an HWI could perform PRD_tick to notify a periodic function when data is available for processing.

**Constraints and Calling Context**

- All the registers that are modified by this API should be saved and restored, before and after the API is invoked, respectively.
- When called within an HWI, the code sequence calling PRD_tick must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.
- Interrupts need to be disabled before calling PRD_tick.

**See Also**
- PRD_start
- PRD_getticks
2.20 PWRM Module

The PWRM module lets you reduce the power consumption of your DSP/BIOS application.

The PWRM module is currently available for the 'C5509A EVM. Partial support for other 'C55x devices is also available. See the DSP/BIOS release notes to determine which features are supported on different devices.

Functions

- PWRM_changeSetpoint. Initiate a change to the V/F setpoint.
- PWRM_configure. Set new configuration parameters for PWRM.
- PWRM_getCapabilities. Get information on PWRM's capabilities on the current platform.
- PWRM_getCurrentSetpoint. Get the current V/F setpoint in effect.
- PWRM_getDependencyCount. Get count of dependencies currently declared on a resource.
- PWRM_getNumSetpoints. Get the number of V/F setpoints supported for the current platform.
- PWRM_getSetpointInfo. Get the corresponding frequency and CPU core voltage for a setpoint.
- PWRM_getTransitionLatency. Get the latency to scale from one setpoint to another setpoint.
- PWRM_idleClocks. Immediately idle clock domains.
- PWRM_registerNotify. Register a pwrmNotifyFxn function to be called on a specific power event.
- pwrmNotifyFxn. Function to be called on a registered power event.
- PWRM_releaseDependency. Release a dependency that has been previously declared.
- PWRM_setDependency. Declare a dependency upon a resource.
- PWRM_sleepDSP. Transition the DSP to a new sleep state.
- PWRM_unregisterNotify. Unregister for an event notification from PWRM.

Description

The DSP/BIOS Power Manager, PWRM, is a DSP/BIOS module that lets you reduce the power consumption of your application in the following ways:

- You can idle specific clock domains to reduce active power consumption.
- You can specify a power-saving function to be called automatically at boot time. This function can idle power-using peripherals and subsystems as desired.
- You can dynamically change the operating voltage and frequency of the CPU. This is called V/F scaling. Since power usage is linearly proportional to the frequency and quadratically proportional to the voltage, using the PWRM module can result in significant power savings.
- You can set custom sleep modes to save power during inactivity. These can be set statically or at run-time.
- You can coordinate sleep modes and V/F scaling using registration and notification mechanisms provided by the PWRM module.
- PWRM functions are designed to save and restore the users environment where appropriate. For example, interrupt masks are saved before and restored after going to deep sleep.
For further description of these features in DSP/BIOS, see the *TMS320 DSP/BIOS User's Guide* (SPRU423). For information about the Power Scaling Library, see *Using the Power Scaling Library on the TMS320C5509* (SPRA848).

**Constants, Types, and Structures**

typedef Void * PWRM_NotifyHandle;

typedef Uns PWRM_Status;

typedef struct PWRM_Config {
   Bool scaleVoltage;
   Bool waitForVoltageScale;
   Uns  idleMask;
} PWRM_Config;

typedef struct PWRM_Attrs {
   Bool scaleVoltage;        /* scale voltage */
   Bool waitForVoltageScale; /* wait on volt change */
   Uns idleMask;             /* domains to idle */
} PWRM_Attrs;

The following constants are used as return codes by various PWRM functions:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred.</td>
</tr>
<tr>
<td>PWRM_EINVALIDEVENT</td>
<td>The specified PWRM event type is invalid.</td>
</tr>
<tr>
<td>PWRM_EINVALIDHANDLE</td>
<td>The specified handle is invalid.</td>
</tr>
<tr>
<td>PWRM_EINVALIDPOINTER</td>
<td>A pointer is invalid.</td>
</tr>
<tr>
<td>PWRM_EINVALIDVALUE</td>
<td>A value is invalid.</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The operation is not implemented by PWRM on this platform.</td>
</tr>
<tr>
<td>PWRM_ENOTSUPPORTED</td>
<td>The requested setting is not supported. For example, a client has</td>
</tr>
<tr>
<td></td>
<td>registered with PWRM indicating that it cannot support the requested</td>
</tr>
<tr>
<td></td>
<td>V/F setpoint.</td>
</tr>
<tr>
<td>PWRM_EOUTOFRANGE</td>
<td>The operation could not be completed because a parameter was out of</td>
</tr>
<tr>
<td></td>
<td>the range supported by PWRM.</td>
</tr>
<tr>
<td>PWRM_ETIMEOUT</td>
<td>A timeout occurred while trying to complete the operation.</td>
</tr>
<tr>
<td>PWRM_ETOOMANYCALLS</td>
<td>Indicates PWRM_releaseDependency has been called more times for a</td>
</tr>
<tr>
<td></td>
<td>resource than PWRM_setDependency was called.</td>
</tr>
<tr>
<td>PWRM_EBUSY</td>
<td>The requested operation cannot be performed at this time; PWRM is</td>
</tr>
<tr>
<td></td>
<td>busy processing a previous request.</td>
</tr>
<tr>
<td>PWRM_EINITFAILURE</td>
<td>A failure occurred while initializing V/F scaling support; V/F scaling is unavailable.</td>
</tr>
</tbody>
</table>
The PWRM_configure and PWRM_idleClocks functions use the following constants to identify clock domains to be idled:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_IDLECPU</td>
<td>Idle the CPU clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEDMA</td>
<td>Idle the DMA clock domain</td>
</tr>
<tr>
<td>PWRM_IDLECACHE</td>
<td>Idle the CACHE clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEPERIPH</td>
<td>Idle the PERIPH clock domain</td>
</tr>
<tr>
<td>PWRM_IDLECLKGEN</td>
<td>Idle the CLKGEN clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEEMIF</td>
<td>Idle the EMIF clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEIPORT</td>
<td>Idle the IPORT clock domain (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEHWA</td>
<td>Idle the HWA clock domain (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEMPORT</td>
<td>Idle the MPORT clock domain (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEXPORT</td>
<td>Idle the XPORT clock domain (OMAP 2420 only)</td>
</tr>
</tbody>
</table>

### Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the PWRM Manager Properties topic. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

### Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>ENABLE</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>BOOTHOOK</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>BOOTHOOKFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>ADAPTCLK</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>DEVICEINIT</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>RESOURCETRACKING</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>DEVICEBMEMSEG</td>
<td>Bool</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>IDLEDOMAINS</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>IDLEIPORT</td>
<td>Bool</td>
<td>false (OMAP 2420 only)</td>
</tr>
<tr>
<td>IDLEHWA</td>
<td>Bool</td>
<td>false (OMAP 2420 only)</td>
</tr>
<tr>
<td>IDLEMPORT</td>
<td>Bool</td>
<td>false (OMAP 2420 only)</td>
</tr>
<tr>
<td>IDLEXPORT</td>
<td>Bool</td>
<td>false (OMAP 2420 only)</td>
</tr>
<tr>
<td>IDLEEMIF</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>IDLECLKGEN</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>IDLEPERIPH</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>IDLECACHE</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>IDLEDMA</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>IDLECPU</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>SCALING</td>
<td>Bool</td>
<td>false</td>
</tr>
</tbody>
</table>
An example demonstrating the use of the V/F scaling APIs of PWRM is located in the `<bios_install_dir>/ti/bios/examples/advanced/vfscale` folder.

An example demonstrating the use of PWRM’s boot hook to call a developer-defined function to implement power savings on boot, idle DSP clock domains to reduce active power consumption, and invoke deep sleep is in the `<bios_install_dir>/ti/bios/examples/advanced/sleep` folder.

### PWRM Manager Properties

The following global properties can be set for the PWRM module in the PWRM Manager Properties dialog of Gconf or in a Tconf script:

#### General tab

- **Enable PWRM Manager.** Check this box if you want to enable the power manager. If you do not plan to use the power manager, you should leave it disabled to reduce the size of your application.  
  
  **Tconf Name:** ENABLE  
  **Type:** Bool  
  **Example:** bios.PWRM.ENABLE = false;
• **Call user hook function at boot time.** Check this box if you want to specify a function to be called during application startup. Such a function is called before the main() function runs.

  Tconf Name: BOOTHOOK      Type: Bool
  Example: bios.PWRM.BOOTHOOK = false;

• **Function.** Specify the function to be called during application startup if you set the property above to true. The function may be used, for example to idle clock domains or to turn off or idle powered resources.

  Tconf Name: BOOTHOOKFXN      Type: Extern
  Example: bios.PWRM.BOOTHOOKFXN = prog.extern("FXN_F_nop");

• **Reprogram BIOS clock after frequency scaling.** This property specifies whether the DSP/BIOS clock module should be reprogrammed after frequency scaling operations. If it is set to true (the default), the CLK module registers for V/F frequency setpoint change notifications and is reprogrammed after a setpoint change. If you do not use DSP timers for CLK functionality (that is, if you use an external clock trigger), set this property to false to save code space and eliminate unnecessary steps. If you set this property to true, do not use the CLK_reconfig, CLK_stop, or CLK_start APIs in your application.

  Tconf Name: ADAPTCLK      Type: Bool
  Example: bios.PWRM.ADAPTCLK = false;

• **Enable device initialization by PWRM.** Set this to true if you want PWRM to initialize the DSP device to a low power state at boot time. This initialization happens before the main() function runs. If PWRM does not support initialization for the device, this property is not writeable.

  Tconf Name: DEVICEINIT      Type: Bool
  Example: bios.PWRM.DEVICEINIT = false;

• **Enable resource tracking by PWRM.** Set this to true if you want to enable the resource tracking feature of PWRM. When enabled, calls to PWRM_setDependency and PWRM_releaseDependency track application and OS dependencies on power-manageable resources, and appropriately power them up or down as needed. If PWRM does not support resource tracking for the device, this property is not writeable.

  Tconf Name: RESOURCETRACKING      Type: Bool
  Example: bios.PWRM.RESOURCETRACKING = false;

• **MEM section for device database.** Select the memory segment where PWRM should locate the resource database for the device. This property is writeable only if either "Enable device initialization by PWRM" or "Enable resource tracking by PWRM" is set to true.

  Tconf Name: DEVICEDBMEMSEG      Type: Reference
  Example: bios.PWRM.DEVICEDBMEMSEG = prog.get("myMEM");

**Idling tab**

• **Idle DSP domains in the BIOS idle loop.** This property specifies whether the PWRM module should idle the specified clock domains within the DSP/BIOS idle loop. If it is set to true, an IDL object called PWRM_idleDomains is created. This object runs a function that idles the clock domains selected by this tab. This function treats the configured clock domains as a bitmask, and ORs these bits with those currently set in the Idle Status Register (ISTR). It then writes the combined mask to the Idle Configuration Register (ICR), and then invokes the IDLE instruction. When a HWI, SWI, or TSK...
thread is ready to run, the idled clock domains are restored to their previous configuration. If you want to idle a specific domain indefinitely, use the PWRM_idleClocks function. To configure which clock domains are idled in deep sleep mode, use the Sleep tab.

Tconf Name: IDLEDOMAINS Type: Bool
Example: bios.PWRM.IDLEDOMAINS = false;

- **HWA.** Checking this box causes the HWA clock domain to be idled during the DSP/BIOS idle loop. This setting can be modified at runtime using the PWRM_configure function. (OMAP 2420 only)

  Tconf Name: IDLEHWA Type: Bool
  Example: bios.PWRM.IDLEHWA = false;

- **IPORT.** Checking this box causes the IPORT clock domain to be idled during the DSP/BIOS idle loop. The CACHE and CPU domains must be idled before you can choose to idle the IPORT domain. This setting can be modified at runtime using the PWRM_configure function. (OMAP 2420 only)

  Tconf Name: IDLEIPORT Type: Bool
  Example: bios.PWRM.IDLEIPORT = false;

- **MPORT.** Checking this box causes the MPORT clock domain to be idled during the DSP/BIOS idle loop. The DMA domain must be idled before you can choose to idle the MPORT domain. This setting can be modified at runtime using the PWRM_configure function. (OMAP 2420 only)

  Tconf Name: IDLEMPORT Type: Bool
  Example: bios.PWRM.IDLEMPORT = false;

- **XPORT.** Checking this box causes the XPORT clock domain to be idled during the DSP/BIOS idle loop. The DMA and CPU domains must be idled before you can choose to idle the XPORT domain. This setting can be modified at runtime using the PWRM_configure function. (OMAP 2420 only)

  Tconf Name: IDLEXPORT Type: Bool
  Example: bios.PWRM.IDLEXPORT = false;

- **EMIF.** Checking this box causes the EMIF clock domain to be idled during the DSP/BIOS idle loop. This setting can be modified at runtime using the PWRM_configure function.

  Tconf Name: IDLEEMIF Type: Bool
  Example: bios.PWRM.IDLEEMIF = false;

- **CLKGEN.** Checking this box causes the CLKGEN clock domain to be idled during the DSP/BIOS idle loop. The CACHE, DMA, and CPU domains must be idled before you can choose to idle the CLKGEN domain. This setting can be modified at runtime using the PWRM_configure function.

  Tconf Name: IDLECLKGEN Type: Bool
  Example: bios.PWRM.IDLECLKGEN = false;

- **PERIPHS.** Checking this box causes the PERIPH clock domain to be idled during the DSP/BIOS idle loop. This setting can be modified at runtime using the PWRM_configure function.

Checking this box does not ensure that every peripheral is idled during the idle loop. Several peripherals can specify whether to idle when the peripheral domain is idled. For example, on the ‘C5509A, the McBSP is specified via the IDLE_EN bit in the PCR, timers via the IDLE_EN bit in the TCR, the ADC module via the IdleEn bit in the ADCCR, the I2C module via the IDLEEN bit in the ICMR, USB via the IDLEEN bit in USBIDLECTL, and the MMC controller via the IDLEEN bit in the
MMCFCLK. Code that manages such peripherals may set the corresponding idle enable bit to ensure the peripheral idles when the top-level peripheral domain is idled. For details, see the TMS320C55x DSP Peripherals Reference Guide (SPRU317).

Tconf Name: IDLEPERIPH     Type: Bool
Example: bios.PWRM.IDLEPERIPH = false;

• CACHE. Checking this box causes the CACHE clock domain to be idled during the DSP/BIOS idle loop. The CACHE domain must remain idled if the CLKGEN domain is idled. This setting can be modified at runtime using the PWRM_configure function.

Tconf Name: IDLECACHE     Type: Bool
Example: bios.PWRM.IDLECACHE = true;

• DMA. Checking this box causes the DMA clock domain to be idled during the DSP/BIOS idle loop. The DMA domain must remain idled if the CLKGEN domain is idled. This setting can be modified at runtime using the PWRM_configure function.

Tconf Name: IDLEDMA     Type: Bool
Example: bios.PWRM.IDLEDMA = false;

• CPU. Checking this box causes the CPU clock domain to be idled during the DSP/BIOS idle loop. The CPU domain must remain idled if the CLKGEN domain is idled. This setting can be modified at runtime using the PWRM_configure function.

Tconf Name: IDLECPU     Type: Bool
Example: bios.PWRM.IDLECPU = true;

V/F Scaling tab

• Enable Voltage and Frequency Scaling. This property specifies whether voltage and frequency scaling are to be enabled for the application. Setting this property to true causes the Power Scaling Library (PSL) library specified by the PSLCONFIGLIB property to be linked with the application.

Tconf Name: SCALING     Type: Bool
Example: bios.PWRM.SCALING = false;

• Initial frequency (index to frequency table). Specify the initial frequency of the DSP after booting. This value is a setpoint from the Frequency Setpoint Table. For details, see “PWRM_changeSetpoint” on page 297.

Tconf Name: INITIALFREQ     Type: Numeric
Example: bios.PWRM.INITIALFREQ = 15;

• Initial voltage (volts). Specify the initial voltage of the DSP after it has been booted.

Tconf Name: INITVOLTS     Type: Numeric
Example: bios.PWRM.INITVOLTS = 1.6;

• Scale voltage along with frequency. This property specifies whether voltage should be scaled along with frequency. You may want to disable voltage scaling to reduce latency when changing the frequency. If this property is set to true, a change to the frequency (via PWRM_changeSetpoint) results in a voltage change when possible. For example, changing from setpoint 15 to setpoint 0 results in a frequency change from 200 to 6 MHz, as well as a voltage change from 1.6 to 1.1. If this property is set to false, voltage is not scaled down along with frequency. The voltage is always scaled up if the new setpoint frequency is higher than that supported at the current voltage. This setting can be modified at runtime using the PWRM_configure function.

Tconf Name: SCALEVOLT     Type: Bool
Example: bios.PWRMSCALEVOLT = false;
• **Wait while voltage is being scaled down.** This property specifies whether PWRM functions should wait during down-voltage transitions. Such transition times can be long, as they typically depend upon power supply load. Currently, it is recommended that this property remain set to false. (Note that the PWRM module always waits during up-voltage transitions; this is required to avoid overclocking the DSP.) This setting can be modified at runtime using the PWRM_configure function.

  Tconf Name: WAITVOLT Type: Bool
  Example: bios.PWRM.WAITVOLT = true;

• **PSL Configuration Library.** Specify the PSL configuration library to link with. Specify only the filename of the library to link with for this property. The include path to the PSL Configuration Library should be added to the linker command file if it is not in the default path. An example library filename is PSL_cfg_c5509a.a55L.

  Tconf Name: PSLCONFIGLIB Type: String
  Example: bios.PWRM.PSLCONFIGLIB = "PSL_cfg_c5509a.a55L"

### Sleep tab

• **Enable deep sleep.** This property specifies whether to enable deep sleep. If it is set to false, you cannot select the remaining items in this tab.

  Tconf Name: ENABLESLEEP Type: Bool
  Example: bios.PWRM.ENABLESLEEP = true;

• **HWA.** Checking this box causes the HWA clock domain to be idled during deep sleep. (OMAP 2420 only)

  Tconf Name: SLEEPHWA Type: Bool
  Example: bios.PWRM.SLEEPHWA = true;

• **IPORT.** Checking this box causes the IPORT clock domain to be idled during deep sleep. The CACHE and CPU domains must be idled for deep sleep before you can choose to idle the IPORT domain. (OMAP 2420 only)

  Tconf Name: SLEEPIPORT Type: Bool
  Example: bios.PWRM.SLEEPIPORT = true;

• **MPORT.** Checking this box causes the MPORT clock domain to be idled during deep sleep. The DMA domain must be idled for deep sleep before you can choose to idle the MPORT domain. (OMAP 2420 only)

  Tconf Name: SLEEPMPORT Type: Bool
  Example: bios.PWRM.SLEEPMPORT = true;

• **XPORT.** Checking this box causes the XPORT clock domain to be idled during deep sleep. The DMA and CPU domains must be idled for deep sleep before you can choose to idle the XPORT domain. (OMAP 2420 only)

  Tconf Name: SLEEPXPORT Type: Bool
  Example: bios.PWRM.SLEEPXPORT = true;

• **EMIF.** Setting this property to true causes the EMIF clock domain to be idled during deep sleep.

  Tconf Name: SLEEPEMIF Type: Bool
  Example: bios.PWRM.SLEEPEMIF = true;

• **CLKGEN.** Checking this box causes the CLKGEN clock domain to be idled during deep sleep. The CACHE, DMA, and CPU domains must be idled for deep sleep before you can choose to idle the CLKGEN domain.

  Tconf Name: SLEEPCLKGEN Type: Bool
  Example: bios.PWRM.SLEEPCLKGEN = true;
• **PERIPHs.** Checking this box causes the PERIPH clock domain to be idled during deep sleep. See the description of the PERIPH box in the Idling tab for details on idling various peripherals when the PERIPH clock domain is idled.
  
  **Tconf Name:** SLEEPPERIPH  
  **Type:** Bool  
  **Example:** bios.PWRM.SLEEPPERIPH = true;

• **CACHE.** Checking this box causes the CACHE clock domain to be idled during deep sleep. The CACHE domain must remain idled if the CLKGEN domain is idled.
  
  **Tconf Name:** SLEEPCACHE  
  **Type:** Bool  
  **Example:** bios.PWRM.SLEEPCACHE = true;

• **DMA.** Checking this box causes the DMA clock domain to be idled during deep sleep. The DMA domain must remain idled if the CLKGEN domain is idled.
  
  **Tconf Name:** SLEEPDMA  
  **Type:** Bool  
  **Example:** bios.PWRM.SLEEPDMA = true;

• **CPU.** Checking this box causes the CPU clock domain to be idled during deep sleep. The CPU domain must remain idled if the CLKGEN domain is idled.
  
  **Tconf Name:** SLEEPCPU  
  **Type:** Bool  
  **Example:** bios.PWRM.SLEEPCPU = true;

• **Wakeup interrupt mask, IER0.** Specifies the wakeup interrupt mask for IER0. This mask is loaded into the DSP's Interrupt Enable Register 0 (IER0) before the PWRM module causes the DSP to sleep. The bits in IER0 and IER1 determine which interrupts are enabled. You can use these bits to enable interrupts that can wake the DSP. For example, a button press by the user might cause an interrupt that is enabled. The IER mappings for each DSP are defined in that DSP's data sheet.
  
  **Tconf Name:** WKUPIER0  
  **Type:** Numeric  
  **Example:** bios.PWRM.WKUPIER0 = 0;

• **Wakeup interrupt mask, IER1.** Specifies the wakeup interrupt mask for IER1. This mask is loaded into the DSP's Interrupt Enable Register 1 (IER1) before the PWRM module causes the DSP to sleep.
  
  **Tconf Name:** WKUPIER1  
  **Type:** Numeric  
  **Example:** bios.PWRM.WKUPIER1 = 0;

• **Enable sleep until restart.** This property specifies whether "sleep until restart" mode is enabled. In this mode, the only way to wake the DSP is to perform a DSP reset.
  
  **Tconf Name:** SLEEPUNTILRESTART  
  **Type:** Bool  
  **Example:** bios.PWRM.SLEEPUNTILRESTART = true;

• **Enable snooze mode.** Because of the limited DSP timer resolution, this feature is not currently implemented.
  
  **Tconf Name:** ENABLESNOOZE  
  **Type:** Bool  
  **Example:** bios.PWRM.ENABLESNOOZE = false;

• **Timer to be used for snooze mode.** Because of the limited DSP timer resolution, this feature is not currently implemented.
  
  **Tconf Name:** TIMERFORSNOOZE  
  **Type:** EnumString  
  **Options:** "Timer 0", "Timer 1"  
  **Example:** bios.PWRM.TIMERFORSNOOZE = "Timer 1";
PWRM_changeSetpoint

Initiate a change to the V/F setpoint

C Interface

Syntax

```
status = PWRM_changeSetpoint(newSetpoint, notifyTimeout);
```

Parameters

- `Uns newSetpoint; /* new V/F setpoint */`
- `Uns notifyTimeout; /* maximum time to wait for notification */`

Return Value

- `PWRM_Status status; /* returned status */`

Reentrant

yes

Description

PWRM_changeSetpoint changes the voltage and frequency of the DSP CPU. Reducing the clock rate (frequency) results in a linear decrease in power consumption. Reducing the operating voltage results in a quadratic reduction in power consumption. Note that there are issues you should be aware of when reducing the clock frequency. For a discussion of these issues, see the TMS320 DSP/BIOS User’s Guide (SPRA423).

The newSetpoint parameter is a numeric value that indexes into a table of frequency/voltage pairs, as defined by the underlying PSL library. For example, the following table shows the setpoints for the 'C5509A EVM:

<table>
<thead>
<tr>
<th>Setpoint</th>
<th>'C5509A EVM Frequency (MHz)</th>
<th>'C5509A EVM Voltage (volts)</th>
</tr>
</thead>
<tbody>
<tr>
<td>15</td>
<td>192</td>
<td>1.6</td>
</tr>
<tr>
<td>14</td>
<td>180</td>
<td>1.6</td>
</tr>
<tr>
<td>13</td>
<td>168</td>
<td>1.6</td>
</tr>
<tr>
<td>12</td>
<td>156</td>
<td>1.6</td>
</tr>
<tr>
<td>11</td>
<td>144</td>
<td>1.4</td>
</tr>
<tr>
<td>10</td>
<td>132</td>
<td>1.4</td>
</tr>
<tr>
<td>9</td>
<td>120</td>
<td>1.4</td>
</tr>
<tr>
<td>8</td>
<td>108</td>
<td>1.2</td>
</tr>
<tr>
<td>7</td>
<td>96</td>
<td>1.2</td>
</tr>
<tr>
<td>6</td>
<td>84</td>
<td>1.2</td>
</tr>
<tr>
<td>5</td>
<td>72</td>
<td>1.2</td>
</tr>
<tr>
<td>4</td>
<td>60</td>
<td>1.2</td>
</tr>
<tr>
<td>3</td>
<td>48</td>
<td>1.2</td>
</tr>
<tr>
<td>2</td>
<td>12</td>
<td>1.2</td>
</tr>
<tr>
<td>1</td>
<td>6</td>
<td>1.2</td>
</tr>
<tr>
<td>0</td>
<td>3</td>
<td>1.2</td>
</tr>
</tbody>
</table>

The notifyTimeout parameter is the maximum amount of time (in system clock ticks) to wait for registered notification functions (set by PWRM_registerNotify) to respond to a delayed completion, before declaring failure and returning PWRM_ETIMEOUT.
For example, if notifyTimeout is set to 200, PWRM_changeSetpoint waits up to 200 ticks (typically 200 milliseconds) before declaring that a function has failed to respond. PWRM uses notifyTimeout for each notification. For example, if notification functions are registered for both before and after setpoint changes, PWRM_changeSetpoint waits up to notifyTimeout on each notification. All registered notification functions are called from the context of PWRM_changeSetpoint.

PWRM_changeSetpoint returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded and the new setpoint is in effect.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred. The requested setpoint transition did not occur.</td>
</tr>
<tr>
<td>PWRM_NOTIMPLEMENTED</td>
<td>V/F scaling is not implemented by PWRM on this platform.</td>
</tr>
<tr>
<td>PWRM_ENOTSUPPORTED</td>
<td>The operation could not be completed because a client registered with PWRM indicating that it cannot support the requested setpoint.</td>
</tr>
<tr>
<td>PWRM_EOUTOFRANGE</td>
<td>The operation could not be completed because newSetpoint is not a valid value for the platform.</td>
</tr>
<tr>
<td>PWRM_ETIMEOUT</td>
<td>A registered notification function did not respond within the specified notifyTimeout.</td>
</tr>
<tr>
<td>PWRM_EBUSY</td>
<td>The requested operation cannot be performed at this time; PWRM is busy processing a previous request.</td>
</tr>
<tr>
<td>PWRM_EINITFAILURE</td>
<td>A failure occurred while initializing V/F scaling support; V/F scaling is unavailable.</td>
</tr>
</tbody>
</table>

The application should treat return values of PWRM_ETIMEOUT or PWRM_EFAIL as critical system failures. These values indicate the notification client is unresponsive, and the system is in an unknown state.

PWRM_changeSetpoint disables SWI and TSK scheduling when it begins making a change. However, HWIs may run during the notification process. After the setpoint has been changed, SWI and TSK scheduling is re-enabled, and a context switch occurs only if some other thread has since been made ready to run.

Constraints and Calling Context

- PWRM_changeSetpoint cannot be called from an HWI.
- This API cannot be called from a program’s main() function.
- PWRM_changeSetpoint can be called from a SWI only if notifyTimeout is 0.
Example

```c
#define TIMEOUT   10  /* timeout for notifications */

PWRM_Status status;
Uns i = 5;

status = PWRM_changeSetpoint(i, TIMEOUT);
if (status == PWRM_SOK) {
    LOG_printf(TRACE, "New setpoint = %d", i);
}
else if (status == PWRM_ENOTSUPPORTED) {
    LOG_printf(TRACE, "Setpoint %d unsupported", i);
}
else {
    LOG_printf(TRACE, "Error: status = %x", status);
    return;
}

GBL_getFrequency
GBL_setFrequency
```
PWRM_configure

Set new configuration properties for PWRM

C Interface

Syntax

status = PWRM_configure(attrs);

Parameters

PWRM_Attrs attrs; /* configuration attributes */

Return Value

PWRM_Status status; /* returned status */

Description

PWRM_configure specifies new configuration properties for the PWRM module. It overrides those specified in the static configuration.

Configuration parameters are specified via a PWRM_Attrs structure. This attribute structure can vary by platform. For the 'C5509A, this structure contains the following:

typedef struct PWRM_Attrs {
  Bool scaleVoltage;        /* scale voltage */
  Bool waitForVoltageScale; /* wait on volt change */
  Uns  idleMask;            /* domains to idle */
} PWRM_Attrs;

In this structure, scaleVoltage indicates whether PWRM should scale voltages during setpoint changes. It corresponds to the "Scale voltage along with frequency" configuration property in the V/F Scaling tab. If scaleVoltage is TRUE, the voltage is scaled down if possible when going to a lower frequency. If scaleVoltage if FALSE, the voltage is not scaled lower. The voltage is always scaled up if the new (destination) setpoint frequency is higher than that supported at the current voltage.

The waitForVoltageScale flag indicates whether PWRM should wait for a down-voltage transition to complete before returning from PWRM_changeSetpoint. It corresponds to the "Wait while voltage is being scaled down" configuration property in the V/F Scaling tab. Such transition times can be long, as they typically depend upon power supply load. Currently, it is recommended that this item always be TRUE. (The PWRM module always waits during up-voltage transitions; this is required to avoid overclocking the DSP.)

The idleMask is a bitmask that specifies additional clock domains to be idled in the DSP/BIOS idle loop. This bitmask is ORed with the current Idle Status Register (ISTR) contents and then written to the Idle Configuration Register (ICR) before idling the processor. When the processor is awoken by an interrupt, the bits for the domains that were idled on entry to the DSP/BIOS idle loop are written to the ICR register and the IDLE instruction is invoked again to restore the previous idle configuration.

See the Idling tab of the configuration properties for descriptions of required interactions between idled clock domains. The bitmask can be formed using the following predefined mask constants:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_IDLECPU</td>
<td>Idle the CPU clock domain</td>
</tr>
</tbody>
</table>
PWRM_configure returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_IDLEDMA</td>
<td>Idle the DMA clock domain</td>
</tr>
<tr>
<td>PWRM_IDLECACHE</td>
<td>Idle the CACHE clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEPERIPH</td>
<td>Idle the PERIPH clock domain</td>
</tr>
<tr>
<td>PWRM_IDLECLKGEN</td>
<td>Idle the CLKGEN clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEEMIF</td>
<td>Idle the EMIF clock domain (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEIPORT</td>
<td>Idle the IPORT clock domain (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEHWA</td>
<td>Idle the HWA clock domain (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEMPORT</td>
<td>Idle the MPORT clock domain (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEXPORT</td>
<td>Idle the XPORT clock domain (OMAP 2420 only)</td>
</tr>
</tbody>
</table>

Name Usage

- **PWRM_SOK** The operation succeeded.
- **PWRM_EFAIL** A general failure occurred.
- **PWRM_EINVALIDPOINTER** The operation failed because the attrs parameter was NULL.
- **PWRM_EINVALIDVALUE** The operation failed because the idleMask is invalid. For example, if the CLKGEN domain is to be idled, the CPU, DMA, and CACHE domains must also be idled.
**PWRM_getCapabilities**  
*Get information on PWRM capabilities on the current platform*

### C Interface

**Syntax**

```c
status = PWRM_getCapabilities(capsMask);
```

**Parameters**

- `Uns *capsMask; /* pointer to location for capabilities */`

**Return Value**

- `PWRM_Status status; /* returned status */`

### Reentrant

yes

### Description

PWRM_getCapabilities returns information about the PWRM module’s capabilities on the current platform.

The `capsMask` parameter should point to the location where `PWRM_getCapabilities` should write a bitmask that defines the capabilities. You can use the following constants to check for capabilities in the bitmask:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_CDEEPSLEEP</td>
<td>PWRM_sleepDSP supports deep sleep mode.</td>
</tr>
<tr>
<td>PWRM_CRESOURCETRACKING</td>
<td>The PWRM module supports dynamic resource tracking.</td>
</tr>
<tr>
<td>PWRM_CSLEEPUNTILRESTART</td>
<td>PWRM_sleepDSP supports sleep until restart.</td>
</tr>
<tr>
<td>PWRM_CSNOOZE</td>
<td>PWRM_sleepDSP supports snooze mode.</td>
</tr>
<tr>
<td>PWRM_CVFSCALING</td>
<td>The PWRM module supports voltage and frequency scaling.</td>
</tr>
</tbody>
</table>

PWRM_getCapabilities returns one of the following constants as a status value of type `PWRM_Status`:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred.</td>
</tr>
<tr>
<td>PWRM_EINVALIDPOINTER</td>
<td>The operation failed because the capsMask parameter was NULL.</td>
</tr>
</tbody>
</table>
Example

```c
PWRM_Status status;
Uns capsMask;

/* Query PWRM capabilities on this platform */
status = PWRM_getCapabilities(&capsMask);
LOG_printf(TRACE, "Returned mask=0x%X", capsMask);
if (status != PWRM_SOK) { /* exit on error */
    LOG_printf(TRACE, "Status = %x", status);
    return;
}
/* exit if V/F scaling not supported */
if ((capsMask & PWRM_CVFSCALING) == 0) {
    LOG_printf(TRACE, "V/F scaling not supported");
    return;
}
```
PWRM_getCurrentSetpoint

Get the current setpoint

C Interface

Syntax

```c
status = PWRM_getCurrentSetpoint(setpoint);
```

Parameters

Uns *setpoint; /* current V/F setpoint */

Return Value

PWRM_Status status; /* returned status */

Reentrant

no

Description

PWRM_getCurrentSetpoint returns the V/F scaling setpoint currently in use.

The setpoint parameter should point to the location where PWRM_getCurrentSetpoint should write the current setpoint. See PWRM_changeSetpoint for a list of valid setpoints.

PWRM_getCurrentSetpoint returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred.</td>
</tr>
<tr>
<td>PWRM EINVALVALIDPOINTER</td>
<td>The operation failed because the setpoint parameter was NULL.</td>
</tr>
<tr>
<td>PWRM EINITFAILURE</td>
<td>A failure occurred while initializing V/F scaling support; V/F scaling is unavailable.</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The operation failed because V/F scaling is not supported.</td>
</tr>
</tbody>
</table>

Constraints and Calling Context

- If a call to PWRM_getCurrentSetpoint is preempted by a thread that changes the setpoint, the value PWRM_getCurrentSetpoint returns is the old setpoint and not the new setpoint. If this may cause a problem in your application, you can disable scheduling around the call to PWRM_getCurrentSetpoint.

Example

```c
PWRM_Status status;
Uns currSetpoint;

status = PWRM_getCurrentSetpoint(&currSetpoint);
LOG_printf(TRACE, "Setpoint: \%d", currSetpoint);
if (status != PWRM_SOK) { /* exit on error */
    LOG_printf(TRACE, "Status = \%x", status);
    return;
}
```
**PWRM_getDependencyCount**  
*Get count of dependencies declared on a resource*

**C Interface**

**Syntax**

```c
status = PWRM_getDependencyCount(resourceID, count);
```

**Parameters**

- `Uns resourceID; /* resource ID */`
- `Uns *count; /* pointer to where count is written */`

**Return Value**

- `PWRM_Status status; /* returned status */`

**Reentrant**

- `yes`

**Description**

`PWRM_getDependencyCount` returns the number of dependencies that are currently declared on a resource. Normally this corresponds to the number of times `PWRM_setDependency` has been called for the resource, minus the number of times `PWRM_releaseDependency` has been called for the same resource.

Resource IDs are device-specific. They are defined in a `PWRM_Resource` enumeration in a device-specific header file. For example, see `pwrm5509a.h` for the 'C5509A.

`PWRM_getDependencyCount` returns one of the following constants as a status value of type `PWRM_Status`:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded, and the reference count was written to the location pointed to by count.</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The operation failed because resource tracking is not supported.</td>
</tr>
</tbody>
</table>

**Example**

```c
/* Display some dependency counts */
LOG_printf(&trace, "Initial dependencies:");
PWRM_getDependencyCount(PWRM_5509A_CLKOUT, &count);
LOG_printf(&trace, "CLKOUT count = %d", count);
PWRM_getDependencyCount(PWRM_5509A_MCBSP0, &count);
LOG_printf(&trace, "McBSP0 count = %d", count);
PWRM_getDependencyCount(PWRM_5509A_DMA_DOMAIN, &count);
LOG_printf(&trace, "DMA domain count = %d", count);
```
PWRM_getNumSetpoints | Get number of setpoints supported by platform

C Interface

Syntax

status = PWRM_getNumSetpoints(numberSetpoints);

Parameters

Uns *numberSetpoints;/* number of supported setpoints */

Return Value

PWRM_Status status; /* returned status */

Reentrant

yes

Description

PWRM_getNumSetpoints returns the number of setpoints supported by the currently configured platform.

The numberSetpoints parameter should point to the location where PWRM_getNumSetpoints should write the number of setpoints. See PWRM_changeSetpoint for a list of valid setpoints. If V/F scaling is supported, the number of setpoints is greater than or equal to 1.

PWRM_getNumSetpoints returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred.</td>
</tr>
<tr>
<td>PWRM EINVALVALIDPOINTER</td>
<td>The operation failed because the numberSetpoints parameter was NULL.</td>
</tr>
<tr>
<td>PWRM_EINITFAILURE</td>
<td>A failure occurred while initializing V/F scaling support; V/F scaling is unavailable</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The operation failed because V/F scaling is not supported.</td>
</tr>
</tbody>
</table>

Example

PWRM_Status status;
Uns numSetpoints;

status = PWRM_getNumSetpoints(&numSetpoints);
if (status == PWRM_SOK) {
    LOG_printf(TRACE, "NumSetpoints: %d", numSetpoints);
} else {
    LOG_printf(TRACE, "Error: status = %x", status);
}
PWRM_getSetpointInfo

Get frequency and CPU core voltage for a setpoint

C Interface

Syntax

```c
status = PWRM_getSetpointInfo(setpoint, frequency, voltage);
```

Parameters

- `setpoint`: /* the setpoint to query */
- `frequency`: /* DSP core frequency */
- `voltage`: /* DSP voltage */

Return Value

- `status`: /* returned status */

Reentrant

- yes

Description

PWRM_getSetpointInfo returns the DSP CPU frequency and voltage for a given setpoint.

The setpoint parameter should specify the setpoint value for which you want to know the frequency and voltage on this platform. See PWRM_changeSetpoint for a list of valid setpoints.

The frequency parameter should point to the location where PWRM_getSetpointInfo should write the DSP core frequency for the specified setpoint.

The voltage parameter should point to the location where PWRM_getSetpointInfo should write the DSP voltage for the specified setpoint.

PWRM_getSetpointInfo returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred.</td>
</tr>
<tr>
<td>PWRM EINVALVALUE</td>
<td>The operation failed because the setpoint parameter is invalid.</td>
</tr>
<tr>
<td>PWRM EINVALPOINTER</td>
<td>The operation failed because the frequency or voltage parameter was NULL.</td>
</tr>
<tr>
<td>PWRM EINITFAILURE</td>
<td>A failure occurred while initializing V/F scaling support; V/F scaling is unavailable</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The operation failed because V/F scaling is not supported.</td>
</tr>
</tbody>
</table>
Example

```c
PWRM_Status status;

/* global arrays for saving setpoint info */
#define MAX_SETPOINTS 16
float freq[MAX_SETPOINTS];
float volts[MAX_SETPOINTS];

status = PWRM_getSetpointInfo(i, &freq[i], &volts[i]);
if (status != PWRM_SOK) { /* exit on error */
    LOG_printf(TRACE, "Error: status=%x", status);
    return;
}
```
PWRM_getTransitionLatency

Get latency to scale between specific setpoints

C Interface

Syntax

```c
status = PWRM_getTransitionLatency(initialSetpoint, finalSetpoint, frequencyLatency, voltageLatency);
```

Parameters

- `Uns initialSetpoint;` /* setpoint to be scaled from */
- `Uns finalSetpoint;` /* setpoint to be scaled to */
- `Uns *frequencyLatency;` /* frequency transition latency */
- `Uns *voltageLatency;` /* voltage transition latency */

Return Value

- `PWRM_Status` status; /* returned status */

Reentrant

Yes

Description

PWRM_getTransitionLatency retrieves the latencies (times required) in microseconds to scale from a specific setpoint to another specific setpoint.

The `initialSetpoint` parameter should specify the setpoint from which the transition would start. The `finalSetpoint` parameter should specify the setpoint at which the transition would end. See PWRM_changeSetpoint for a list of valid setpoints.

The `frequencyLatency` parameter should point to the location where PWRM_getTransitionLatency should write the time required to change the CPU frequency from that of the `initialSetpoint` to that of the `finalSetpoint` in microseconds.

Similarly, the `voltageLatency` should point to the location where PWRM_getTransitionLatency should write the time required to change the voltage from that of the `initialSetpoint` to that of the `finalSetpoint` in microseconds.

When frequency and voltage are scaled together, the total latency is the sum of the frequency scaling latency and the voltage scaling latency.

PWRM_getTransitionLatency returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred.</td>
</tr>
<tr>
<td>PWRM EINVALVALUE</td>
<td>The operation failed because the initialSetpoint or finalSetpoint value was invalid.</td>
</tr>
<tr>
<td>PWRM EINVALPOINTER</td>
<td>The operation failed because the frequencyLatency or voltageLatency parameter was NULL.</td>
</tr>
<tr>
<td>PWRM EINVALFAILURE</td>
<td>A failure occurred while initializing V/F scaling support; V/F scaling is unavailable</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The operation failed because V/F scaling is not supported.</td>
</tr>
</tbody>
</table>
The time required to change a setpoint may not be deterministic (depending on the hardware characteristics, the underlying Power Scaling Library implementation, and the specific V/F swing), but it is bounded by the value returned by PWRM_getTransitionLatency.

Example

```c
PWRM_Status status;
Uns frequencyLatency;
Uns voltageLatency;

status = PWRM_getTransitionLatency(15, 0,
                                   &frequencyLatency, &voltageLatency);

if (status != PWRM_SOK) {
    LOG_printf(TRACE, "Error: status=%x", status);
} else {
    LOG_printf(TRACE, "Frequency latency: %d, Voltage latency: %d",
                frequencyLatency, voltageLatency);
}
```
**PWRM_idleClocks** *Immediately idle clock domains*

**C Interface**

Syntax

```
status = PWRM_idleClocks(domainMask, idleStatus);
```

**Parameters**

Uns domainMask; /* bitmask of clock domains to be idled */
Uns *idleStatus; /* contents of ISTR after idling */

**Return Value**

PWRM_Status status; /* returned status */

**Reentrant**

yes

**Description**

PWRM_idleClocks immediately turns off the specified clock domains. This allows applications to idle non-CPU domains at any point in the application.

The domainMask is a bitmask that specifies clock domains to be idled. This value is written to the ICR register before idling the processor. See the Idling tab of the configuration properties for descriptions of required interactions between idled clock domains. The bitmask can be formed using the following predefined mask constants:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_IDLEDMA</td>
<td>Idle the DMA clock domain</td>
</tr>
<tr>
<td>PWRM_IDLECACHE</td>
<td>Idle the CACHE clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEPERIPH</td>
<td>Idle the PERIPH clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEEMIF</td>
<td>Idle the EMIF clock domain</td>
</tr>
<tr>
<td>PWRM_IDLEIPORT</td>
<td>Idle the IPORT clock domain  (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEHWA</td>
<td>Idle the HWA clock domain    (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEMPORT</td>
<td>Idle the MPORT clock domain  (OMAP 2420 only)</td>
</tr>
<tr>
<td>PWRM_IDLEEXPORT</td>
<td>Idle the XPORT clock domain  (OMAP 2420 only)</td>
</tr>
</tbody>
</table>

The idleStatus parameter should point to the location where PWRM_idleClocks should write the contents of the Idle Status Register (ISTR) after idling clock domains. If PWRM_idleClocks returns PWRM_EFAIL, this parameter can be used to determine which domains were idled and which were not. For example, if a bit was set in the domainMask but is not set in idleStatus, the corresponding domain could not be idled.

PWRM_idleClocks returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred. One of the domains specified in domainMask did not go idle.</td>
</tr>
<tr>
<td>PWRM EINVALPOINTER</td>
<td>Operation failed because the idleStatus parameter was NULL.</td>
</tr>
<tr>
<td>PWRM EINVALVALUE</td>
<td>Operation failed because the domainMask is invalid.</td>
</tr>
</tbody>
</table>
Example

```c
PWRM_Status status;
Uns idleStatus;

status = PWRM_idleClocks(PWRM_IDLEEMIF | PWRM_IDLEDMA, &idleStatus);
if(idleStatus == (PWRM_IDLEEMIF | PWRM_IDLEDMA)) {
    LOG_printf(TRACE, "Idled domains successfully");
}
```
**PWRM_registerNotify**  
*Register a function to be called on a specific power event*

**C Interface**

**Syntax**

```c
status = PWRM_registerNotify(eventType, eventMask, notifyFxn, clientArg, notifyHandle, 
    delayedCompletionFxn);
```

**Parameters**

- `PWRM_Event eventType; /* type of power event */`
- `LgUns eventMask; /* event-specific mask */`
- `Fxnf notifyFxn; /* function to call on event */`
- `Arg clientArg; /* argument to pass to notifyFxn */`
- `PWRM_NotifyHandle *notifyHandle; /* handle for unregistering */`
- `Fxnf *delayedCompletionFxn; /* fxn to call if delay */`

**Return Value**

- `PWRM_Status status; /* returned status */`

**Reentrant**

- yes

**Description**

`PWRM_registerNotify` registers a function to be called when a specific power event occurs. Registrations and the corresponding notifications are processed in FIFO order. The function registered must behave as described in the `pwrmNotifyFxn` section.

The `eventType` parameter identifies the type of power event for which the notify function being registered is to be called. The `eventType` parameter can vary by platform, and is enumerated as `PWRM_Event`. For example, on the 'C5509 this parameter may have one of the following values:

<table>
<thead>
<tr>
<th>Value</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_PENDINGSETPOINTCHANGE</td>
<td>V/F setpoint is about to change.</td>
</tr>
<tr>
<td>PWRM_DONESETPOINTCHANGE</td>
<td>The pending V/F setpoint change has now been made.</td>
</tr>
<tr>
<td>PWRM_GOINGTODEEPSLEEP</td>
<td>The DSP is going to DEEPSLEEP state.</td>
</tr>
<tr>
<td>PWRM_AWAKEFROMDEEPSLEEP</td>
<td>The DSP has awoken from DEEPSLEEP.</td>
</tr>
<tr>
<td>PWRM_GOINGTOSNOOZE</td>
<td>The DSP is going to snooze mode.</td>
</tr>
<tr>
<td>PWRM_AWAKEFROMSNOOZE</td>
<td>The DSP has awoken from snooze.</td>
</tr>
<tr>
<td>PWRM_GOINGTOSLEEPUNTILRESTART</td>
<td>DSP going to deep sleep and must be restarted to resume.</td>
</tr>
</tbody>
</table>

**Note:** Snooze mode is currently not implemented.

The `eventMask` parameter is an event-specific mask. Currently `eventMask` is relevant only to setpoint changes, but it may be used in the future for other power events. For V/F setpoint registrations, this mask defines the setpoints the client supports. For example, if the client supports only one setpoint, it should set only the single corresponding bit in `eventMask`. Using the `eventMask` allows `PWRM_changeSetpoint` to immediately determine whether to begin the notification process or return `PWRM_ENOTSUPPORTED`.  

---

Note: Snooze mode is currently not implemented.
The notifyFxnn parameter specifies the function to call when the specified power event occurs. The notifyFunction must behave as described in the pwrmNotifyFxnn section.

The clientArg parameter is an arbitrary argument to be passed to the client upon notification. This argument may allow one notify function to be used by multiple instances of a driver (that is, the clientArg can be used to identify the instance of the driver that is being notified).

The notifyHandle parameter should point to the location where PWRM_registerNotify should write a notification handle. If the application later needs to unregister the notification function, the application should pass this handle to PWRM_unregisterNotify.

The delayedCompletionFxnn is a pointer to a function provided by the PWRM module to the client at registration time. If a client cannot act immediately upon notification, its notify function should return PWRM_NOTIFYNOTDONE. Later, when the action is complete, the client should call the delayedCompletionFxnn to signal PWRM that it has finished. The delayedCompletionFxnn is a void function, taking no arguments, and having no return value. If a client can and does act immediately on the notification, it should return PWRM_NOTIFYDONE in response to notification, and should not call the delayedCompletionFxnn.

For example, if a DMA driver is to prepare for a setpoint change, it may need to wait for the current DMA transfer to complete. When the driver finishes processing the event (for example, on the next hardware interrupt), it calls the delayedCompletionFxnn function provided when it registered for notification. This completion function tells the PWRM module that the driver is finished. Meanwhile, the PWRM module was able to continue notifying other clients, and was waiting for all clients to signal completion.

PWRM_registerNotify returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The function was successfully registered.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred.</td>
</tr>
<tr>
<td>PWRM_EINVALIDPOINTER</td>
<td>The operation failed because the notifyFxnn, notifyHandle, or delayedCompletionFxnn parameter was NULL.</td>
</tr>
<tr>
<td>PWRM_EINVALIDEVENT</td>
<td>Operation failed because eventType is invalid.</td>
</tr>
</tbody>
</table>

**Constraints and Calling Context**

- PWRM_registerNotify cannot be called from a SWI or HWI. This is because PWRM_registerNotify internally calls MEM_alloc, which may cause a context switch.
Example

/* client allows all setpoints */
#define ALLSETPOINTSLALLOWED 0xFFFF
/* client doesn't allow lowest 4 setpoints */
#define SOMESETPOINTSLALLOWED 0xFFF0

PWRM_NotifyHandle notifyHandle1;
PWRM_NotifyHandle notifyHandle2;

/* pointers to returned delayed completion fxns */
Fxn delayFxn1;
Fxn delayFxn2;

/* Client 1 registers pre-setpoint notification */
PWRM_registerNotify(PWRM_PENDINGSETPOINTCHANGE,
                    ALLSETPOINTSLALLOWED, (Fxn)myNotifyFxn1,
                    (Arg)0x1111, &notifyHandle1, (Fxn *) &delayFxn1);

/* Client 2 registers post-setpoint notification */
PWRM_registerNotify(PWRM_DONESETPOINTCHANGE,
                    SOMESETPOINTSLALLOWED, (Fxn)myNotifyFxn2,
                    (Arg)0x2222, &notifyHandle2, &delayFxn2);
pwrmNotifyFxn  
*Function to be called on a registered power event*

**C Interface**

**Syntax**

```c
status = notifyFxn(eventType, eventArg1, eventArg2, clientArg);
```

**Parameters**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>eventType</td>
<td>type of power event</td>
</tr>
<tr>
<td>eventArg1</td>
<td>event-specific argument</td>
</tr>
<tr>
<td>eventArg2</td>
<td>event-specific argument</td>
</tr>
<tr>
<td>clientArg</td>
<td>arbitrary argument</td>
</tr>
</tbody>
</table>

**Return Value**

<table>
<thead>
<tr>
<th>Return Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>status</td>
<td>returned status</td>
</tr>
</tbody>
</table>

**Description**

PWRM_registerNotify registers a function to be called when a specific power event occurs. Clients, which are typically drivers, register notification functions they need to run when a particular power event occurs.

This topic describes the required prototype and behavior of such notification functions. Your application must provide and register these functions. Registered functions are called internally by the PWRM module.

The eventType parameter identifies the type of power event for which the notify function is being called. This parameter has an enumerated type of PWRM_Event. The values for this parameter are listed in the PWRM_registerNotify topic.

The eventArg1 and eventArg2 parameters are event-specific arguments. Currently, eventArg1 and eventArg2 are used only for V/F scaling events:

- **Pending setpoint change** (PWRM_PENDINGSETPOINTCHANGE). The eventArg1 holds the current setpoint, and eventArg2 holds the pending setpoint.
- **Done setpoint change** (PWRM_DONESETPOINTCHANGE). The eventArg1 holds the previous setpoint, and eventArg2 holds the new setpoint.

The clientArg parameter holds the arbitrary argument passed to PWRM_registerNotify when this function was registered. This argument may allow one notify function to be used by multiple instances of a driver (that is, the clientArg can be used to identify the instance of the driver that is being notified).

The notification function must return one of the following constants as a status value of type PWRM_NotifyResponse:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_NOTIFYDONE</td>
<td>The client processed the notification function successfully.</td>
</tr>
<tr>
<td>PWRM_NOTIFYNOTDONE</td>
<td>The client must wait for interrupt processing to occur before it can proceed. The client must later call the delayedCompletionFxn specified when this function was registered with PWRM_registerNotify.</td>
</tr>
</tbody>
</table>
Constraints and Calling Context

- The notification function should not call PWRM APIs that trigger a notification event (PWRM_changeSetpoint and PWRM_sleepDSP). If such an API is called, the PWRM_EBUSY status code is returned.

Example

```c
/* notification function prototypes */
PWRM_NotifyResponse myNotifyFxn1(
    PWRM_Event eventType, Arg eventArg1, Arg eventArg2,
    Arg clientArg);
PWRM_NotifyResponse myNotifyFxn2(
    PWRM_Event eventType, Arg eventArg1, Arg eventArg2,
    Arg clientArg);

/* ======== myNotifyFxn1 ======== */
PWRM_NotifyResponse myNotifyFxn1(
    PWRM_Event eventType, Arg eventArg, Arg eventArg2,
    Arg clientArg)
{
    #if VERBOSE
        LOG_printf(TRACE, "client #1 notify,
            PENDINGSETPOINTCHANGE");
        LOG_printf(TRACE, "eventArg=%p, eventArg2=%p",
            eventArg, eventArg2);
        LOG_printf(TRACE, "clientArg=%p", clientArg);
        LOG_printf(TRACE, "signal notify complete");
    #endif

    return(PWRM_NOTIFYDONE);   /* notify complete */
}
```
PWRM_releaseDependency

Release a dependency that was previously declared

C Interface

Syntax

status = PWRM_releaseDependency(resourceID);

Parameters

resourceID; /* resource ID */

Return Value

status; /* returned status */

Reentrant

yes

Description

This function is the companion to PWRM_setDependency. It releases a resource dependency that was previously set.

Resource IDs are device-specific. They are defined in a PWRM_Resource enumeration in a device-specific header file. For example, see pwrm5509a.h for the 'C5509A.

PWRM_ETOOMANYCALLS is returned if you call PWRM_releaseDependency when there are no dependencies currently declared for the specified resource (either because all have been released or because none were set).

PWRM_releaseDependency returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded, and dependency has been released.</td>
</tr>
<tr>
<td>PWRM_ETOOMANYCALLS</td>
<td>A dependency was not previously set and was therefore not released.</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The operation failed because resource tracking is not supported.</td>
</tr>
</tbody>
</table>

Example

/* Release default dependency on CLKOUT to save power*/
PWRM_releaseDependency(PWRM_5509A_CLKOUT);
**PWRM_setDependency**  
*Declare a dependency upon a resource*

**C Interface**

`status = PWRM_setDependency(resourceID);`

**Syntax**

**Parameters**

| Uns resourceID; /* resource ID */ |

**Return Value**

| PWRM_Status status; /* returned status */ |

**Reentrant**

yes

**Description**

This function sets a dependency on a resource. It is the companion to `PWRM_releaseDependency`. Resource IDs are device-specific. They are defined in a `PWRM_Resource` enumeration in a device-specific header file. For example, see `pwrm5509a.h` for the 'C5509A.

`PWRM_setDependency` returns one of the following constants as a status value of type `PWRM_Status`:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The operation succeeded, and dependency has been set.</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The operation failed because resource tracking is not supported.</td>
</tr>
</tbody>
</table>

**Example**

```c
/* Declare an application dependency upon McBSP0 */
PWRM_setDependency(PWRM_5509A_MCBSP0);

/* Declare application dependency upon DMA domain */
PWRM_setDependency(PWRM_5509A_DMA_DOMAIN);
```
PWRM_sleepDSP

Transition the DSP to a new sleep state

C Interface

Syntax

```c
status = PWRM_sleepDSP(sleepCode, sleepArg, notifyTimeout);
```

Parameters

- **Uns** `sleepCode; /* new sleep state */`
- **LgUns** `sleepArg; /* sleepCode-specific argument */`
- **Uns** `notifyTimeout; /* maximum time to wait for notification */`

Return Value

- **PWRM_Status** `status; /* returned status */`

Reentrant

yes

Description

PWRM_sleepDSP transitions the DSP to a new sleep state.

The sleepCode parameter indicates the new sleep state for the DSP. The sleep states supported by PWRM usually vary by device. (See the DSP/BIOS release notes to determine which sleep states are available for your device.) For example, the following constants may be used to activate sleep states on the 'C5509:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_DEEPSLEEP</td>
<td>Put the DSP in deep sleep until a configured interrupt occurs to wake the DSP.</td>
</tr>
<tr>
<td>PWRM_SLEEPUNTILRESTART</td>
<td>Idle all DSP clock domains. The only way to wake up is a DSP reset.</td>
</tr>
<tr>
<td>PWRM_SNOOZE</td>
<td>Sleep the DSP for the number of milliseconds specified by sleepArg.</td>
</tr>
</tbody>
</table>

A call to PWRM_sleepDSP with PWRM_DEEPSLEEP or PWRM_SNOOZE returns when the DSP awakes from deep sleep or snoozing (respectively). The interrupts that can wake the DSP from deep sleep are specified by the following PWRM Manager Properties: Wakeup interrupt mask, IER0 and Wakeup interrupt mask, IER1.

A call to PWRM_sleepDSP with PWRM_SLEEPUNTILRESTART never returns. The use of PWRM_SLEEPUNTILRESTART indicates that the only way to wake up is a DSP reset.

Note: Snooze mode is currently not implemented.

The sleepArg parameter is a sleepCode-specific argument. Currently, it is used only for PWRM_SNOOZE mode to indicate the duration (in milliseconds) for snoozing the DSP.

The notifyTimeout parameter is the maximum amount of time (in system clock ticks) to wait for registered notification functions (set by PWRM_registerNotify) to respond to a delayed completion, before declaring failure and returning PWRM_ETIMEOUT.
PWRM_sleepDSP returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>A successful sleep and wake occurred.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred. Could not sleep the DSP.</td>
</tr>
<tr>
<td>PWRM_ENOTIMPLEMENTED</td>
<td>The requested sleep mode is not implemented on this platform.</td>
</tr>
<tr>
<td>PWRM_EOUTOFRANGE</td>
<td>The operation could not be completed because sleepArg is out of range of the capabilities of PWRM.</td>
</tr>
<tr>
<td>PWRM_ETIMEOUT</td>
<td>A registered notification function did not respond within the specified notifyTimeout.</td>
</tr>
<tr>
<td>PWRM_EBUSY</td>
<td>The requested operation cannot be performed at this time; PWRM is busy processing a previous request.</td>
</tr>
</tbody>
</table>

Due to the critical system nature of sleep commands, clients that register for sleep notification should make every effort to respond immediately to the sleep event.

The application should treat return values of PWRM_ETIMEOUT or PWRM_EFAIL as critical system failures. These values indicate the notification client is unresponsive, and the system is in an unknown state.

**Constraints and Calling Context**
- PWRM_sleepDSP cannot be called from an HWI.
- This API cannot be called from a program’s main() function.
- PWRM_sleepDSP can be called from a SWI only if notifyTimeout is 0.

**Example**

```c
#define TIMEOUT 10  /* timeout after 10 ticks */

LOG_printf(TRACE, "Putting DSP to deep sleep...\n");
status = PWRM_sleepDSP(PWRM_DEEPSLEEP, 0, TIMEOUT);
LOG_printf(TRACE, "DSP awake from deep sleep");
LOG_printf(TRACE, "Returned sleep status 0x%x", status);
```
PWRM_unregisterNotify

Unregister for an event notification from PWRM

C Interface

Syntax

status = PWRM_unregisterNotify(notifyHandle);

Parameters

PWRM_NotifyHandle notifyHandle; /* handle to registered function */

Return Value

PWRM_Status status; /* returned status */

Reentrant

yes

Description

PWRM_unregisterNotify unregisters an event notification that was registered by PWRM_registerNotify. For example, when an audio codec device is closed, it no longer needs to be notified, and should unregister for event notification.

The notifyHandle parameter is the parameter that was provided by PWRM_registerNotify when the function was registered.

PWRM_unregisterNotify returns one of the following constants as a status value of type PWRM_Status:

<table>
<thead>
<tr>
<th>Name</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_SOK</td>
<td>The function was successfully unregistered.</td>
</tr>
<tr>
<td>PWRM_EFAIL</td>
<td>A general failure occurred.</td>
</tr>
<tr>
<td>PWRM_EINVALIDHANDLE</td>
<td>Operation failed because notifyHandle is invalid.</td>
</tr>
</tbody>
</table>

Constraints and Calling Context

- This API cannot be called from a program’s main() function.

Example

PWRM_NotifyHandle notifyHandle1;

PWRM_registerNotify(PWRM_PENDINGSETPOINTCHANGE, ALLSETPOINTSALLOWED, (Fxn)myNotifyFxn1, (Arg)0x1111, &notifyHandle1, (Fxn *)&delayFxn1);

...  

PWRM_unregisterNotify(notifyHandle1);
2.21 QUE Module

The QUE module is the atomic queue manager.

**Functions**

- QUE_create. Create an empty queue.
- QUE_delete. Delete an empty queue.
- QUE_dequeue. Remove from front of queue (non-atomically).
- QUE_empty. Test for an empty queue.
- QUE_enqueue. Insert at end of queue (non-atomically).
- QUE_get. Remove element from front of queue (atomically)
- QUE_head. Return element at front of queue.
- QUE_insert. Insert in middle of queue (non-atomically).
- QUE_new. Set a queue to be empty.
- QUE_next. Return next element in queue (non-atomically).
- QUE_prev. Return previous element in queue (non-atomically).
- QUE_put. Put element at end of queue (atomically).
- QUE_remove. Remove from middle of queue (non-atomically).

**Constants, Types, and Structures**

```c
typedef struct QUE_Obj *QUE_Handle; /* queue obj handle */
struct QUE_Attrs{     /* queue attributes */
    Int  dummy;     /* DUMMY */
};
QUE_Attrs QUE_ATTRS = {      /* default attribute values */
    0,
};
typedef QUE_Elem;        /* queue element */
```

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the QUE Manager Properties and QUE Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

**Module Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

**Instance Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
</tbody>
</table>
Description

The QUE module makes available a set of functions that manipulate queue objects accessed through handles of type QUE_Handle. Each queue contains an ordered sequence of zero or more elements referenced through variables of type QUE_Elem, which are generally embedded as the first field within a structure. The QUE_Elem item is used as an internal pointer.

For example, the DEV_Frame structure, which is used by the SIO Module and DEV Module to enqueue and dequeue I/O buffers, contains a field of type QUE_Elem:

```c
struct DEV_Frame {   /* frame object */
    QUE_Elem   link;       /* must be first field! */
    Ptr        addr;       /* buffer address */
    size_t     size;       /* buffer size */
    Arg        misc;       /* reserved for driver */
    Arg        arg;        /* user argument */
    Uns        cmd;        /* mini-driver command */
    Int        status;     /* status of command */
} DEV_Frame;
```

Many QUE module functions either are passed or return a pointer to an element having the structure defined for QUE elements.

The functions QUE_put and QUE_get are atomic in that they manipulate the queue with interrupts disabled. These functions can therefore be used to safely share queues between tasks, or between tasks and SWIs or HWIs. All other QUE functions should only be called by tasks, or by tasks and SWIs or HWIs when they are used in conjunction with some mutual exclusion mechanism (for example, SEM_pend / SEM_post, TSK_disable / TSK_enable).

Once a queue has been created, use MEM_alloc to allocate elements for the queue.

QUE Manager Properties

The following global property can be set for the QUE module in the QUE Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the QUE objects.
  - Tconf Name: OBJMEMSEG
  - Type: Reference
  - Example: `bios.QUE.OBJMEMSEG = prog.get("myMEM");`

QUE Object Properties

To create a QUE object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```c
var myQue = bios.QUE.create("myQue");
```

The following property can be set for a QUE object in the PRD Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this QUE object.
  - Tconf Name: comment
  - Type: String
  - Example: `myQue.comment = "my QUE";`
**QUE_create**  
*Create an empty queue*

### C Interface

**Syntax**

```c
queue = QUE_create(attrs);
```

**Parameters**

- `QUE_Attrs *attrs;` /* pointer to queue attributes */

**Return Value**

- `QUE_Handle queue;` /* handle for new queue object */

### Description

`QUE_create` creates a new queue which is initially empty. If successful, `QUE_create` returns the handle of the new queue. If unsuccessful, `QUE_create` returns NULL unless it aborts (for example, because it directly or indirectly calls `SYS_error`, and `SYS_error` is configured to abort).

If `attrs` is NULL, the new queue is assigned a default set of attributes. Otherwise, the queue’s attributes are specified through a structure of type `QUE_Attrs`.

**Note:** At present, no attributes are supported for queue objects, and the type `QUE_Attrs` is defined as a dummy structure.

All default attribute values are contained in the constant `QUE_ATTRS`, which can be assigned to a variable of type `QUE_Attrs` prior to calling `QUE_create`.

You can also create a queue by declaring a variable of type `QUE_Obj` and initializing the queue with `QUE_new`.

`QUE_create` calls `MEM_alloc` to dynamically create the object’s data structure. `MEM_alloc` must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the `MEM Module`, page 2–204.

### Constraints and Calling Context

- `QUE_create` cannot be called from a SWI or HWI.
- You can reduce the size of your application program by creating objects with the Tconf rather than using the `XXX_create` functions.

### See Also

- `MEM_alloc`
- `QUE_empty`
- `QUE_delete`
- `SYS_error`
**QUE_delete**  
*Delete an empty queue*

### C Interface

**Syntax**

```c
QUE_delete(queue);
```

**Parameters**

- `QUE_Handle queue; /* queue handle */`

**Return Value**

`Void`

### Description

`QUE_delete` uses `MEM_free` to free the queue object referenced by `queue`.  

`QUE_delete` calls `MEM_free` to delete the `QUE` object. `MEM_free` must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

### Constraints and Calling Context

- `queue` must be empty.
- `QUE_delete` cannot be called from a SWI or HWI.
- No check is performed to prevent `QUE_delete` from being used on a statically-created object. If a program attempts to delete a queue object that was created using `Tconf`, `SYS_error` is called.

### See Also

- `QUE_create`
- `QUE_empty`
**QUE_dequeue**  
*Remove from front of queue (non-atomically)*

**C Interface**

Syntax

```c
elem = QUE_dequeue(queue);
```

Parameters

- **QUE_Handle queue;** /* queue object handle */

Return Value

- **Ptr elem;** /* pointer to former first element */

**Description**

QUE_dequeue removes the element from the front of queue and returns elem.

The return value, elem, is a pointer to the element at the front of the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE_Elem and is used as an internal pointer.

Calling QUE_dequeue with an empty queue returns the queue itself. However, QUE_dequeue is non-atomic. Therefore, the method described for QUE_get of checking to see if a queue is empty and returning the first element otherwise is non-atomic.

---

**Note:**

You should use QUE_get instead of QUE_dequeue if multiple threads share a queue. QUE_get runs atomically and is never interrupted; QUE_dequeue performs the same action but runs non-atomically. You can use QUE_dequeue if you disable interrupts or use a synchronization mechanism such as LCK or SEM to protect the queue. An HWI or task that preempts QUE_dequeue and operates on the same queue can corrupt the data structure.

QUE_dequeue is somewhat faster than QUE_get, but you should not use it unless you know your QUE operation cannot be preempted by another thread that operates on the same queue.

---

**See Also**

- QUE_get
**QUE_empty**  
*Test for an empty queue*

**C Interface**

Syntax

```c
empty = QUE_empty(queue);
```

Parameters

- `QUE_Handle queue; /* queue object handle */`

Return Value

- `Bool empty; /* TRUE if queue is empty */`

**Description**

`QUE_empty` returns TRUE if there are no elements in queue, and FALSE otherwise.

**See Also**

- `QUE_get`
## QUE_enqueue

*Insert at end of queue (non-atomically)*

### C Interface

#### Syntax

```c
QUE_enqueue(queue, elem);
```

#### Parameters

- `queue`: /* queue object handle */
- `elem`: /* pointer to queue element */

#### Return Value

`Void`

#### Description

`QUE_enqueue` inserts `elem` at the end of `queue`.

The `elem` parameter must be a pointer to an element to be placed in the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type `QUE_Elem` and is used as an internal pointer.

---

**Note:**

Use `QUE_put` instead of `QUE_enqueue` if multiple threads share a queue. `QUE_put` is never interrupted; `QUE_enqueue` performs the same action but runs non-atomically.

You can use `QUE_enqueue` if you disable interrupts or use a synchronization mechanism such as LCK or SEM to protect the queue.

`QUE_enqueue` is somewhat faster than `QUE_put`, but you should not use it unless you know your QUE operation cannot be preempted by another thread that operates on the same queue.

---

#### See Also

- `QUE_put`
**QUE_get**  
*Get element from front of queue (atomically)*

**C Interface**

**Syntax**

```c
elem = QUE_get(queue);
```

**Parameters**

- **C_INTERFACE**
  - `QE_Handle queue; /* queue object handle */`

**Return Value**

- **QE_UInt**
  - `*elem; /* pointer to former first element */`

**Description**

QUE_get removes the element from the front of queue and returns elem.

The return value, elem, is a pointer to the element at the front of the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE_Elem and is used as an internal pointer.

Since QUE_get manipulates the queue with interrupts disabled, the queue can be shared by multiple tasks, or by tasks and SWIs or HWIs.

Calling QUE_get with an empty queue returns the queue itself. This provides a means for using a single atomic action to check if a queue is empty, and to remove and return the first element if it is not empty:

```c
if ((QE_Handle)(elem = QUE_get(q)) != q)
    `process elem`
```

**Note:**

Use QUE_get instead of QUE_dequeue if multiple threads share a queue. QUE_get is never interrupted; QUE_dequeue performs the same action but runs non-atomically. You can use QUE_dequeue if you disable interrupts or use a synchronization mechanism such as LCK or SEM to protect the queue.

QUE_dequeue is somewhat faster than QUE_get, but you should not use it unless you know your QUE operation cannot be preempted by another thread that operates on the same queue.

**See Also**

- QUE_create
- QUE_empty
- QUE_put
QUE_head  
*Return element at front of queue*

**C Interface**

Syntax

```c
elem = QUE_head(queue);
```

**Parameters**

- **QUE_Handle** queue; /* queue object handle */

**Return Value**

- **QUE_Elem** *elem; /* pointer to first element */

**Description**

QUE_head returns a pointer to the element at the front of queue. The element is not removed from the queue.

The return value, *elem*, is a pointer to the element at the front of the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type QUE_Elem and is used as an internal pointer.

Calling QUE_head with an empty queue returns the queue itself.

**See Also**

- QUE_create
- QUE_empty
- QUE_put
**QUE_insert**  
*Insert in middle of queue (non-atomically)*

**C Interface**

Syntax

```c
QUE_insert(qelem, elem);
```

Parameters

- `Ptr qelem; /* element already in queue */`
- `Ptr elem; /* element to be inserted in queue */`

Return Value

`Void`

**Description**

QUE_insert inserts `elem` in the queue in front of `qelem`. The `qelem` parameter is a pointer to an existing element of the QUE. The `elem` parameter is a pointer to an element to be placed in the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type `QUE_Elem` and is used as an internal pointer.

---

**Note:** If the queue is shared by multiple tasks, or tasks and SWIs or HWIs, QUE_insert should be used in conjunction with some mutual exclusion mechanism (for example, `SEM_pend/SEM_post`, `TSK_disable/TSK_enable`).

---

**See Also**

- `QUE_head`
- `QUE_next`
- `QUE_prev`
- `QUE_remove`
**QUE_new**  
*Set a queue to be empty*

**C Interface**

Syntax
```
QUE_new(queue);
```

Parameters
```
QUE_Handle queue;    /* pointer to queue object */
```

Return Value
Void

**Description**
QUE_new adjusts a queue object to make the queue empty. This operation is not atomic. A typical use of QUE_new is to initialize a queue object that has been statically declared instead of being created with QUE_create. Note that if the queue is not empty, the element(s) in the queue are not freed or otherwise handled, but are simply abandoned.

If you created a queue by declaring a variable of type QUE_Obj, you can initialize the queue with QUE_new.

**See Also**
- QUE_create
- QUE_delete
- QUE_empty
**QUE_next**  
*Return next element in queue (non-atomically)*

**C Interface**

Syntax

```c
elem = QUE_next(qelem);
```

Parameters

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ptr</td>
<td>qelem</td>
<td>/* element in queue */</td>
</tr>
</tbody>
</table>

Return Value

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ptr</td>
<td>elem</td>
<td>/* next element in queue */</td>
</tr>
</tbody>
</table>

**Description**

QUE_next returns `elem` which points to the element in the queue after `qelem`.

The `qelem` parameter is a pointer to an existing element of the QUE. The return value, `elem`, is a pointer to the next element in the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type `QUE_Elem` and is used as an internal pointer.

Since QUE queues are implemented as doubly linked lists with a dummy node at the head, it is possible for QUE_next to return a pointer to the queue itself. Be careful not to call QUE_remove(elem) in this case.

**Note:**

If the queue is shared by multiple tasks, or tasks and SWIs or HWIs, QUE_next should be used in conjunction with some mutual exclusion mechanism (for example, SEM_pend/SEM_post, TSK_disable/TSK_enable).

**See Also**

- QUE_get
- QUE_insert
- QUE_prev
- QUE_remove
**QUE_prev**  
*Return previous element in queue (non-atomically)*

**C Interface**

**Syntax**

```c
elem = QUE_prev(qelem);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>Ptr qelem;</code></td>
<td>/* element in queue */</td>
</tr>
</tbody>
</table>

**Return Value**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>Ptr elem;</code></td>
<td>/* previous element in queue */</td>
</tr>
</tbody>
</table>

**Description**

`QUE_prev` returns `elem` which points to the element in the queue before `qelem`.

The `qelem` parameter is a pointer to an existing element of the QUE. The return value, `elem`, is a pointer to the previous element in the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type `QUE_Elem` and is used as an internal pointer.

Since QUE queues are implemented as doubly linked lists with a dummy node at the head, it is possible for `QUE_prev` to return a pointer to the queue itself. Be careful not to call `QUE_remove(elem)` in this case.

**Note:** If the queue is shared by multiple tasks, or tasks and SWIs or HWIs, `QUE_prev` should be used in conjunction with some mutual exclusion mechanism (for example, `SEM_pend/SEM_post`, `TSK_disable/TSK_enable`).

**See Also**

- `QUE_head`
- `QUE_insert`
- `QUE_next`
- `QUE_remove`
 QUE_put

Put element at end of queue (atomically)

C Interface

Syntax
QUE_put(queue, elem);

Parameters
QUE_Handle queue; /* queue object handle */
Void *elem; /* pointer to new queue element */

Return Value
Void

Description
QUE_put puts elem at the end of queue.

The elem parameter is a pointer to an element to be placed at the end of the QUE. Such elements have
a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure
must be of type QUE_Elem and is used as an internal pointer.

Since QUE_put manipulates queues with interrupts disabled, queues can be shared by multiple tasks, or
by tasks and SWIs or HWIs.

Note:
Use QUE_put instead of QUE_enqueue if multiple threads share a queue. QUE_put is
never interrupted; QUE_enqueue performs the same action but runs non-atomically.
You can use QUE_enqueue if you disable interrupts or use a synchronization
mechanism such as LCK or SEM to protect the queue.

QUE_enqueue is somewhat faster than QUE_put, but you should not use it unless you
know your QUE operation cannot be preempted by another thread that operates on the
same queue.

See Also
QUE_get
QUE_head
**QUE_remove**  
*Remove from middle of queue (non-atomically)*

### C Interface

**Syntax**

```c
QUE_remove(qelem);
```

**Parameters**

- `Ptr qelem; /* element in queue */`

**Return Value**

`Void`

### Description

`QUE_remove` removes `qelem` from the queue.

The `qelem` parameter is a pointer to an existing element to be removed from the QUE. Such elements have a structure defined similarly to that in the example in the QUE Module topic. The first field in the structure must be of type `QUE_Elem` and is used as an internal pointer.

Since QUE queues are implemented as doubly linked lists with a dummy node at the head, be careful not to remove the header node. This can happen when `qelem` is the return value of `QUE_next` or `QUE_prev`. The following code sample shows how `qelem` should be verified before calling `QUE_remove`.

```c
QUE_Elem *qelem;.

/* get pointer to first element in the queue */
qelem = QUE_head(queue);

/* scan entire queue for desired element */
while (qelem != queue) {
    if(' qelem is the elem we're looking for ') {  
        break;
    }
    qelem = QUE_next(qelem);
}
/* make sure qelem is not the queue itself */
if (qelem != queue) {
    QUE_remove(qelem);
}
```

**Note:** If the queue is shared by multiple tasks, or tasks and SWIs or HWIs, `QUE_remove` should be used in conjunction with some mutual exclusion mechanism (for example, `SEM_pend/SEM_post`, `TSK_disable/TSK_enable`).

### Constraints and Calling Context

`QUE_remove` should not be called when `qelem` is equal to the queue itself.

### See Also

- `QUE_head`
- `QUE_insert`
- `QUE_next`
- `QUE_prev`
2.22 RTDX Module

The RTDX modules manage the real-time data exchange settings.

**RTDX Data Declaration Macros**
- RTDX_CreateInputChannel
- RTDX_CreateOutputChannel

**Function Macros**
- RTDX_disableInput
- RTDX_disableOutput
- RTDX_enableInput
- RTDX_enableOutput
- RTDX_read
- RTDX_readNB
- RTDX_sizeofInput
- RTDX_write

**Channel Test Macros**
- RTDX_channelBusy
- RTDX_isInputEnabled
- RTDX_isOutputEnabled

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the RTDX Manager Properties and RTDX Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

**Module Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>ENABLERTDX</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>MODE</td>
<td>EnumString</td>
<td>&quot;JTAG&quot; (&quot;Simulator&quot;)</td>
</tr>
<tr>
<td>RTDXDATASEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>BUFSIZE</td>
<td>Int16</td>
<td>258</td>
</tr>
<tr>
<td>INTERRUPTMASK</td>
<td>Int16</td>
<td>0x00000000</td>
</tr>
</tbody>
</table>

**Instance Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>channelMode</td>
<td>EnumString</td>
<td>&quot;output&quot; (&quot;input&quot;)</td>
</tr>
</tbody>
</table>

**Description**

The RTDX module provides the data types and functions for:
- Sending data from the target to the host.
- Sending data from the host to the target.
Data channels are represented by global structures. A data channel can be used for input or output, but not both. The contents of an input or output structure are not known to the user. A channel structure has two states: enabled and disabled. When a channel is enabled, any data written to the channel is sent to the host. Channels are initially disabled.

The RTDX assembly interface, `rtdx.i`, is a macro interface file that can be used to interface to RTDX at the assembly level.

**RTDX Manager Properties**

The following target configuration properties can be set for the RTDX module in the RTDX Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Enable Real-Time Data Exchange (RTDX).** This property should be set to true if you want to link RTDX support into your application.
  
  **Tconf Name:** `ENABLERTDX`  
  **Type:** Bool  
  **Example:** `bios.RTDX.ENABLERTDX = true;`

- **RTDX Mode.** Select the port configuration mode RTDX should use to establish communication between the host and target. The default is JTAG for most targets. Set this to simulator if you use a simulator. The HS-RTDX emulation technology is also available. If this property is set incorrectly, a message says “RTDX target application does not match emulation protocol” when you load the program.
  
  **Tconf Name:** `MODE`  
  **Type:** EnumString  
  **Options:** "JTAG", "Simulator"  
  **Example:** `bios.RTDX.MODE = "JTAG";`  

- **RTDX Data Segment (.rtdx_data).** The memory segment used for buffering target-to-host data transfers. The RTDX message buffer and state variables are placed in this segment.
  
  **Tconf Name:** `RTDXDATASEG`  
  **Type:** Reference  
  **Example:** `bios.RTDX.RTDXDATASEG = prog.get("myMEM");`

- **RTDX Buffer Size (MADUs).** The size of the RTDX target-to-host message buffer, in minimum addressable data units (MADUs). The default size is 1032 to accommodate a 1024-byte block and two control words. HST channels using RTDX are limited by this value.
  
  **Tconf Name:** `BUFSIZE`  
  **Type:** Int16  
  **Example:** `bios.RTDX.BUFSIZE = 258;`

- **RTDX Interrupt Mask.** This mask interrupts to be temporarily disabled inside critical RTDX sections. The default value of zero (0) disables all interrupts within critical RTDX sections. Such sections are short (usually <100 cycles). Disabling interrupts also temporarily disables other RTDX clients and prevents other RTDX function calls.
  
  You should allow all interrupts to be disabled inside critical RTDX sections if your application makes any RTDX calls from SWI or TSK threads. If your application does not make RTDX calls from SWI or TSK threads, you may modify bits in this mask to enable specific high-priority interrupts. See the RTDX documentation for details.

  **Tconf Name:** `INTERRUPTMASK`  
  **Type:** Int16  
  **Example:** `bios.RTDX.INTERRUPTMASK = 0x00000000;`
RTDX Object Properties

To create an RTDX object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```javascript
var myRtdx = bios.RTDX.create("myRtdx");
```

The following properties can be set for an RTDX object in the RTDX Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this RTDX object.
  
  **Tconf Name:** comment  
  **Type:** String
  
  **Example:**
  ```javascript
  myRtdx.comment = "my RTDX";
  ```

- **Channel Mode.** Select output if the RTDX channel handles output from the DSP to the host. Select input if the RTDX channel handles input to the DSP from the host.
  
  **Tconf Name:** channelMode  
  **Type:** EnumString
  
  **Options:** "input", "output"
  
  **Example:**
  ```javascript
  myRtdx.channelMode = "output";
  ```

---

**Note:** Programs must be linked with C run-time libraries and contain the symbol `_main`. 
RTDX_channelBusy

Return status indicating whether data channel is busy

C Interface

Syntax

```c
int RTDX_channelBusy( RTDX_inputChannel *pichan );
```

Parameters

- `pichan` /* Identifier for the input data channel */

Return Value

- `int` /* Status: 0 = Channel is not busy. */
- /* non-zero = Channel is busy. */

Reentrant

- yes

Description

RTDX_channelBusy is designed to be used in conjunction with RTDX_readNB. The return value indicates whether the specified data channel is currently in use or not. If a channel is busy reading, the test/control flag (TC) bit of status register 0 (STO) is set to 1. Otherwise, the TC bit is set to 0.

Constraints and Calling Context

- RTDX_channelBusy cannot be called by an HWI function.

See Also

- RTDX_readNB
**RTDX_CreateInputChannel**  
*Declare input channel structure*

**C Interface**

**Syntax**

```c
RTDX_CreateInputChannel( ichan );
```

**Parameters**

- `ichan` /* Label for the input channel */

**Return Value**

- `none`

**Reentrant**

- `no`

**Description**

This macro declares and initializes to 0, the RTDX data channel for input.

Data channels must be declared as global objects. A data channel can be used either for input or output, but not both. The contents of an input or output data channel are unknown to the user.

A channel can be in one of two states: enabled or disabled. Channels are initialized as disabled.

Channels can be enabled or disabled via a User Interface function. They can also be enabled or disabled remotely from Code Composer or its COM interface.

**Constraints and Calling Context**

- RTDX_CreateInputChannel cannot be called by an HWI function.

**See Also**

- RTDX_CreateOutputChannel
RTDX_CreateOutputChannel

Declare output channel structure

C Interface

Syntax

RTDX_CreateOutputChannel( ochan );

Parameters

ochan /* Label for the output channel */

Return Value

none

Reentrant

no

Description

This macro declares and initializes the RTDX data channels for output.

Data channels must be declared as global objects. A data channel can be used either for input or output, but not both. The contents of an input or output data channel are unknown to the user.

A channel can be in one of two states: enabled or disabled. Channels are initialized as disabled.

Channels can be enabled or disabled via a User Interface function. They can also be enabled or disabled remotely from Code Composer Studio or its OLE interface.

Constraints and Calling Context

- RTDX_CreateOutputChannel cannot be called by an HWI function.

See Also

RTDX_CreateInputChannel
RTDX_disableInput

Disable an input data channel

C Interface

Syntax
void RTDX_disableInput( RTDX_inputChannel *ichan );

Parameters
ichan /* Identifier for the input data channel */

Return Value
void

Reentrant
yes

Description
A call to a disable function causes the specified input channel to be disabled.

Constraints and Calling Context
• RTDX_disableInput cannot be called by an HWI function.

See Also
RTDX_disableOutput
RTDX_enableInput
RTDX_read
RTDX_disableOutput  
Disable an output data channel

C Interface

Syntax

```c
void RTDX_disableOutput( RTDX_outputChannel *ochan );
```

Parameters

- `ochan` /* Identifier for an output data channel */

Return Value

`void`

Reentrant

`yes`

Description

A call to a disable function causes the specified data channel to be disabled.

Constraints and Calling Context

- RTDX_disableOutput cannot be called by an HWI function.

See Also

- RTDX_disableInput
- RTDX_enableOutput
- RTDX_read
**RTDX_enableInput**  
*Enable an input data channel*

**C Interface**

**Syntax**

```c
void RTDX_enableInput( RTDX_inputChannel *ichan );
```

**Parameters**

- ochan /* Identifier for an output data channel */
- ichan /* Identifier for the input data channel */

**Return Value**

```c
void
```

**Reentrant**

yes

**Description**

A call to an enable function causes the specified data channel to be enabled.

**Constraints and Calling Context**

- RTDX_enableInput cannot be called by an HWI function.

**See Also**

- RTDX_disableInput
- RTDX_enableOutput
- RTDX_read
**RTDX_enableOutput**  
*Enable an output data channel*

**C Interface**

**Syntax**
```c
void RTDX_enableOutput( RTDX_outputChannel *ochan );
```

**Parameters**
- `ochan` /* Identifier for an output data channel */

**Return Value**
- `void`

**Reentrant**
- yes

**Description**
A call to an enable function causes the specified data channel to be enabled.

**Constraints and Calling Context**
- RTDX_enableOutput cannot be called by an HWI function.

**See Also**
- RTDX_disableOutput
- RTDX_enableInput
- RTDX_write
**RTDX_isInputEnabled**  
*Return status of the input data channel*

### C Interface

**Syntax**

```c
RTDX_isInputEnabled( ichan );
```

**Parameter**

```c
ichan /* Identifier for an input channel. */
```

**Return Value**

```c
0 /* Not enabled. */
```

```c
non-zero /* Enabled. */
```

**Reentrant**

yes

**Description**

The RTDX_isInputEnabled macro tests to see if an input channel is enabled and sets the test/control flag (TC bit) of status register 0 to 1 if the input channel is enabled. Otherwise, it sets the TC bit to 0.

**Constraints and Calling Context**

- RTDX_isInputEnabled cannot be called by an HWI function.

**See Also**

RTDX_isOutputEnabled
**RTDX_isOutputEnabled**  
*Return status of the output data channel*

**C Interface**

**Syntax**

```c
RTDX_isOutputEnabled(ochan);
```

**Parameter**

`ochan` /* Identifier for an output channel. */

**Return Value**

0 /* Not enabled. */
non-zero /* Enabled. */

**Reentrant**

yes

**Description**

The RTDX_isOutputEnabled macro tests to see if an output channel is enabled and sets the test/control flag (TC bit) of status register 0 to 1 if the output channel is enabled. Otherwise, it sets the TC bit to 0.

**Constraints and Calling Context**

- RTDX_isOutputEnabled cannot be called by an HWI function.

**See Also**

RTDX_isInputEnabled
RTDX_read

Read from an input channel

C Interface

Syntax

```c
int RTDX_read( RTDX_inputChannel *ichan, void *buffer, int bsize );
```

Parameters

- `ichan` /* Identifier for the input data channel */
- `buffer` /* A pointer to the buffer that receives the data */
- `bsize` /* The size of the buffer in address units */

Return Value

- `> 0` /* The number of address units of data */
  /* actually supplied in buffer. */
- `0` /* Failure. Cannot post read request */
  /* because target buffer is full. */
- `RTDX_READ_ERROR` /* Failure. Channel currently busy or not enabled. */

Reentrant

yes

Description

RTDX_read causes a read request to be posted to the specified input data channel. If the channel is enabled, RTDX_read waits until the data has arrived. On return from the function, the data has been copied into the specified buffer and the number of address units of data actually supplied is returned. The function returns RTDX_READ_ERROR immediately if the channel is currently busy reading or is not enabled.

When RTDX_read is used, the target application notifies the RTDX Host Library that it is ready to receive data and then waits for the RTDX Host Library to write data to the target buffer. When the data is received, the target application continues execution.

The specified data is to be written to the specified output data channel, provided that channel is enabled. On return from the function, the data has been copied out of the specified user buffer and into the RTDX target buffer. If the channel is not enabled, the write operation is suppressed. If the RTDX target buffer is full, failure is returned.

When RTDX_readNB is used, the target application notifies the RTDX Host Library that it is ready to receive data, but the target application does not wait. Execution of the target application continues immediately. Use RTDX_channelBusy and RTDX_sizeofInput to determine when the RTDX Host Library has written data to the target buffer.

Constraints and Calling Context

- RTDX_read cannot be called by an HWI function.

See Also

- RTDX_channelBusy
- RTDX_readNB
RTDX_readNB  
*Read from input channel without blocking*

**C Interface**

**Syntax**

```c
int RTDX_readNB( RTDX_inputChannel *ichan, void *buffer, int bsize );
```

**Parameters**

- `ichan` /* Identifier for the input data channel */
- `buffer` /* A pointer to the buffer that receives the data */
- `bsize` /* The size of the buffer in address units */

**Return Value**

- RTDX_OK /* Success.*/
- 0 (zero) /* Failure. The target buffer is full. */
- RTDX_READ_ERROR /*Channel is currently busy reading. */

**Reentrant**

yes

**Description**

RTDX_readNB is a nonblocking form of the function RTDX_read. RTDX_readNB issues a read request to be posted to the specified input data channel and immediately returns. If the channel is not enabled or the channel is currently busy reading, the function returns RTDX_READ_ERROR. The function returns 0 if it cannot post the read request due to lack of space in the RTDX target buffer.

When the function RTDX_readNB is used, the target application notifies the RTDX Host Library that it is ready to receive data but the target application does not wait. Execution of the target application continues immediately. Use the RTDX_channelBusy and RTDX_sizeofInput functions to determine when the RTDX Host Library has written data into the target buffer.

When RTDX_read is used, the target application notifies the RTDX Host Library that it is ready to receive data and then waits for the RTDX Host Library to write data into the target buffer. When the data is received, the target application continues execution.

**Constraints and Calling Context**

- RTDX_readNB cannot be called by an HWI function.

**See Also**

- RTDX_channelBusy
- RTDX_read
- RTDX_sizeofInput
RTDX_sizeofInput

Return the number of MADUs read from a data channel

C Interface

Syntax

int RTDX_sizeofInput( RTDX_inputChannel *pichan );

Parameters

pichan /* Identifier for the input data channel */

Return Value

int /* Number of sizeof units of data actually */
/* supplied in buffer */

Reentrant

yes

Description

RTDX_sizeofInput is designed to be used in conjunction with RTDX_readNB after a read operation has completed. The function returns the number of sizeof units actually read from the specified data channel into the accumulator (register A).

Constraints and Calling Context

• RTDX_sizeofInput cannot be called by an HWI function.

See Also

RTDX_readNB
**RTDX_write**

Write to an output channel

C Interface

Syntax

```c
int RTDX_write( RTDX_outputChannel *ochan, void *buffer, int bsize );
```

Parameters

- `ochan` /* Identifier for the output data channel */
- `buffer` /* A pointer to the buffer containing the data */
- `bsize` /* The size of the buffer in address units */

Return Value

- `int` /* Status: non-zero = Success. 0 = Failure */

Reentrant

- `yes`

Description

RTDX_write causes the specified data to be written to the specified output data channel, provided that channel is enabled. On return from the function, the data has been copied out of the specified user buffer and into the RTDX target buffer. If the channel is not enabled, the write operation is suppressed. If the RTDX target buffer is full, Failure is returned.

Constraints and Calling Context

- RTDX_write cannot be called by an HWI function.

See Also

- RTDX_read
2.23 SEM Module

The SEM module is the semaphore manager.

Functions

- `SEM_count`. Get current semaphore count
- `SEM_create`. Create a semaphore
- `SEM_delete`. Delete a semaphore
- `SEM_new`. Initialize a semaphore
- `SEM_pend`. Wait for a counting semaphore
- `SEM_pendBinary`. Wait for a binary semaphore
- `SEM_post`. Signal a counting semaphore
- `SEM_postBinary`. Signal a binary semaphore
- `SEM_reset`. Reset semaphore

Constants, Types, and Structures

```c
typedef struct SEM_Obj *SEM_Handle;
/* handle for semaphore object */

struct SEM_Attrs { /* semaphore attributes */
    String name; /* printable name */
};

SEM_Attrs SEM_ATTRS = { /* default attribute values */
    "", /* name */
};
```

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the SEM Manager Properties and SEM Object Properties topics. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>count</td>
<td>Int16</td>
<td>0</td>
</tr>
</tbody>
</table>

Description

The SEM module provides a set of functions that manipulate semaphore objects accessed through handles of type `SEM_Handle`. Semaphores can be used for task synchronization and mutual exclusion.

Semaphores can be counting semaphores or binary semaphores. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.
• **Counting semaphores** keep track of the number of times the semaphore has been posted with SEM_post. This is useful, for example, if you have a group of resources that are shared between tasks. Such tasks might call SEM_pend to see if a resource is available before using one. SEM_pend and SEM_post are for use with counting semaphores.

• **Binary semaphores** can have only two states: available and unavailable. They can be used to share a single resource between tasks. They can also be used for a basic signaling mechanism, where the semaphore can be posted multiple times and a subsequent call to SEM_pendBinary clears the count and returns. Binary semaphores do not keep track of the count; they simply track whether the semaphore has been posted or not. SEM_pendBinary and SEM_postBinary are for use with binary semaphores.

The MBX module uses a counting semaphore internally to manage the count of free (or full) mailbox elements. Another example of a counting semaphore is an ISR that might fill multiple buffers of data for consumption by a task. After filling each buffer, the ISR puts the buffer on a queue and calls SEM_post. The task waiting for the data calls SEM_pend, which simply decrements the semaphore count and returns or blocks if the count is 0. The semaphore count thus tracks the number of full buffers available for the task. The GIO and SIO modules follow this model and use counting semaphores.

The internal data structures used for binary and counting semaphores are the same; the only change is whether semaphore values are incremented and decremented or simply set to zero and non-zero. SEM_pend and SEM_pendBinary are used to wait for a semaphore. The timeout parameter allows the task to wait until a timeout, wait indefinitely, or not wait at all. The return value is used to indicate if the semaphore was signaled successfully.

SEM_post and SEM_postBinary are used to signal a semaphore. If a task is waiting for the semaphore, SEM_post/SEM_postBinary removes the task from the semaphore queue and puts it on the ready queue. If no tasks are waiting, SEM_post simply increments the semaphore count and returns. (SEM_postBinary sets the semaphore count to non-zero and returns.)

**SEM Manager Properties**

The following global property can be set for the SEM module in the SEM Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

• **Object Memory.** The memory segment that contains the SEM objects created with Tconf.
  
  Tconf Name: OBJMEMSEG Type: Reference
  
  Example: bios.SEM.OBJMEMSEG = prog.get("myMEM");

**SEM Object Properties**

To create a SEM object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```javascript
var mySem = bios.SEM.create("mySem");
```

The following properties can be set for a SEM object in the SEM Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

• **comment.** Type a comment to identify this SEM object.
  
  Tconf Name: comment Type: String
  
  Example: mySem.comment = "my SEM";

• **Initial semaphore count.** Set this property to the desired initial semaphore count.
  
  Tconf Name: count Type: Int16
  
  Example: mySem.count = 0;
SEM_count

Get current semaphore count

C Interface

Syntax

```c
count = SEM_count(sem);
```

Parameters

- `SEM_Handle sem;` /* semaphore handle */

Return Value

- `Int count;` /* current semaphore count */

Description

SEM_count returns the current value of the semaphore specified by `sem`. 
SEM_create

Create a semaphore

C Interface

Syntax

```c
sem = SEM_create(count, attrs);
```

Parameters

- `Int count; /* initial semaphore count */`
- `SEM_Attrs *attrs; /* pointer to semaphore attributes */`

Return Value

- `SEM_Handle sem; /* handle for new semaphore object */`

Description

SEM_create creates a new semaphore object which is initialized to count. If successful, SEM_create returns the handle of the new semaphore. If unsuccessful, SEM_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS_error, and SYS_error is configured to abort).

If `attrs` is NULL, the new semaphore is assigned a default set of attributes. Otherwise, the semaphore’s attributes are specified through a structure of type `SEM_Attrs`.

```c
struct SEM_Attrs { /* semaphore attributes */
    String name; /* printable name */
};
```

Default attribute values are contained in the constant `SEM_ATTRS`, which can be assigned to a variable of type `SEM_Attrs` before calling `SEM_create`.

```c
SEM_Attrs SEM_ATTRS = { /* default attribute values */
    "", /* name */
};
```

SEM_create calls `MEM_alloc` to dynamically create the object’s data structure. `MEM_alloc` must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module.

Constraints and Calling Context

- `count` must be greater than or equal to 0.
- SEM_create cannot be called from a SWI or HWI.
- You can reduce the size of your application by creating objects with Tconf rather than XXX_create functions.

See Also

- `MEM_alloc`
- `SEM_delete`
**SEM_delete**  
*Delete a semaphore*

**C Interface**

Syntax

```c
SEM_delete(sem);
```

Parameters

- `SEM_Handle sem; /* semaphore object handle */`

Return Value

`Void`

**Description**

SEM_delete uses MEM_free to free the semaphore object referenced by `sem`.

SEM_delete calls MEM_free to delete the SEM object. MEM_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- No tasks should be pending on `sem` when SEM_delete is called.
- SEM_delete cannot be called from a SWI or HWI.
- No check is performed to prevent SEM_delete from being used on a statically-created object. If a program attempts to delete a semaphore object that was created using Tconf, SYS_error is called.

**See Also**

SEM_create
SEM_new

Initialize semaphore object

C Interface

Syntax

Void SEM_new(sem, count);

Parameters

SEMHANDLE sem; /* pointer to semaphore object */
Int count;      /* initial semaphore count */

Return Value

Void

Description

SEM_new initializes the semaphore object pointed to by sem with count. The function should be used on a statically created semaphore for initialization purposes only. No task switch occurs when calling SEM_new.

Constraints and Calling Context

• count must be greater than or equal to 0
• no tasks should be pending on the semaphore when SEM_new is called

See Also

QUE_new
### SEM_pend

**Wait for a semaphore**

#### C Interface

**Syntax**

```c
status = SEM_pend(sem, timeout);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>SEM_Handle</td>
<td>sem;</td>
<td>/* semaphore object handle */</td>
</tr>
<tr>
<td>Uns</td>
<td>timeout;</td>
<td>/* return after this many system clock ticks */</td>
</tr>
</tbody>
</table>

**Return Value**

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bool</td>
<td>status;</td>
<td>/* TRUE if successful, FALSE if timeout */</td>
</tr>
</tbody>
</table>

#### Description

SEM_pend and SEM_post are for use with counting semaphores, which keep track of the number of times the semaphore has been posted. This is useful, for example, if you have a group of resources that are shared between tasks. In contrast, SEM_pendBinary and SEM_postBinary are for use with binary semaphores, which can have only an available or unavailable state. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.

If the semaphore count is greater than zero (available), SEM_pend decrements the count and returns TRUE. If the semaphore count is zero (unavailable), SEM_pend suspends execution of the current task until SEM_post is called or the timeout expires.

If timeout is SYSFOREVER, a task stays suspended until SEM_post is called on this semaphore. If timeout is 0, SEM_pend returns immediately. If timeout expires (or timeout is 0) before the semaphore is available, SEM_pend returns FALSE. Otherwise SEM_pend returns TRUE.

If timeout is not equal to SYSFOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

A task switch occurs when calling SEM_pend if the semaphore count is 0 and timeout is not zero.

#### Constraints and Calling Context

- SEM_pend can be called from a TSK with any timeout value, but if called from an HWI or SWI the timeout must be 0.
- SEM_pend cannot be called from the program’s main() function.
- If you need to call SEM_pend within a TSK_disable/TSK_enable block, you must use a timeout of 0.
- SEM_pend should not be called from within an IDL function. Doing so prevents analysis tools from gathering run-time information.

#### See Also

- SEM_pendBinary
- SEM_post
**SEM_pendBinary**  
*Wait for a binary semaphore*

### C Interface

**Syntax**

```c
status = SEM_pendBinary(sem, timeout);
```

**Parameters**

- `SEM_Handle sem;` /* semaphore object handle */
- `Uns timeout;` /* return after this many system clock ticks */

**Return Value**

- `Bool status;` /* TRUE if successful, FALSE if timeout */

**Description**

SEM_pendBinary and SEM_postBinary are for use with binary semaphores. These are semaphores that can have only two states: available and unavailable. They can be used to share a single resource between tasks. They can also be used for a basic signaling mechanism, where the semaphore can be posted multiple times and a subsequent call to SEM_pendBinary clears the count and returns. Binary semaphores do not keep track of the count; they simply track whether the semaphore has been posted or not.

In contrast, SEM_pend and SEM_post are for use with counting semaphores, which keep track of the number of times the semaphore has been posted. This is useful, for example, if you have a group of resources that are shared between tasks. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.

If the semaphore count is non-zero (available), SEM_pendBinary sets the count to zero (unavailable) and returns TRUE.

If the semaphore count is zero (unavailable), SEM_pendBinary suspends execution of this task until SEM_post is called or the timeout expires.

If timeout is SYS_FOREVER, a task remains suspended until SEM_postBinary is called on this semaphore. If timeout is 0, SEM_pendBinary returns immediately.

If timeout expires (or timeout is 0) before the semaphore is available, SEM_pendBinary returns FALSE. Otherwise SEM_pendBinary returns TRUE.

If timeout is not equal to SYS_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

A task switch occurs when calling SEM_pendBinary if the semaphore count is 0 and timeout is not zero.

**Constraints and Calling Context**

- This API can be called from a TSK with any timeout value, but if called from an HWI or SWI the timeout must be 0.
- This API cannot be called from the program’s main() function.
- If you need to call this API within a TSK_disable/TSK_enable block, you must use a timeout of 0.
- This API should not be called from within an IDL function. Doing so prevents analysis tools from gathering run-time information.

**See Also**

- SEM_pend
- SEM_postBinary
**SEM_post**  
*Signal a semaphore*

**C Interface**

**Syntax**

```c
SEM_post(sem);
```

**Parameters**

- `SEM_Handle sem; /* semaphore object handle */`

**Return Value**

`Void`

**Description**

SEM_pend and SEM_post are for use with counting semaphores, which keep track of the number of times the semaphore has been posted. This is useful, for example, if you have a group of resources that are shared between tasks.

In contrast, SEM_pendBinary and SEM_postBinary are for use with binary semaphores, which can have only an available or unavailable state. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.

SEM_post readies the first task waiting for the semaphore. If no task is waiting, SEM_post simply increments the semaphore count and returns.

A task switch occurs when calling SEM_post if a higher priority task is made ready to run.

**Constraints and Calling Context**

- When called within an HWI, the code sequence calling SEM_post must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.
- If SEM_post is called from within a TSK_disable/TSK_enable block, the semaphore operation is not processed until TSK_enable is called.

**See Also**

- SEM_pend
- SEM_postBinary
SEM_postBinary  

C Interface

Syntax

```c
SEM_postBinary(sem);
```

Parameters

```c
SEM_Handle sem; /* semaphore object handle */
```

Return Value

Void

Description

SEM_pendBinary and SEM_postBinary are for use with binary semaphores. These are semaphores that can have only two states: available and unavailable. They can be used to share a single resource between tasks. They can also be used for a basic signaling mechanism, where the semaphore can be posted multiple times and a subsequent call to SEM_pendBinary clears the count and returns. Binary semaphores do not keep track of the count; they simply track whether the semaphore has been posted or not.

In contrast, SEM_pend and SEM_post are for use with counting semaphores, which keep track of the number of times the semaphore has been posted. This is useful, for example, if you have a group of resources that are shared between tasks. The APIs for binary and counting semaphores cannot be mixed for a single semaphore.

SEM_postBinary readies the first task in the list if one or more tasks are waiting. SEM_postBinary sets the semaphore count to non-zero (available) if no tasks are waiting.

A task switch occurs when calling SEM_postBinary if a higher priority task is made ready to run.

Constraints and Calling Context

- When called within an HWI, the code sequence calling this API must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.
- If this API is called from within a TSK_disable/TSK_enable block, the semaphore operation is not processed until TSK_enable is called.

See Also

SEM_post
SEM_pendBinary
SEM_reset  
*Reset semaphore count*

**C Interface**

**Syntax**

```
SEM_reset(sem, count);
```

**Parameters**

- `SEM_Handle sem; /* semaphore object handle */`
- `Int count; /* semaphore count */`

**Return Value**

`Void`

**Description**

SEM_reset resets the semaphore count to count.

No task switch occurs when calling SEM_reset.

**Constraints and Calling Context**

- count must be greater than or equal to 0.
- No tasks should be waiting on the semaphore when SEM_reset is called.
- SEM_reset cannot be called by an HWI or a SWI.

**See Also**

SEM_create
2.24 SIO Module

The SIO module is the stream input and output manager.

Functions

- SIO_bufsize. Size of the buffers used by a stream
- SIO_create. Create stream
- SIO_ctrl. Perform a device-dependent control operation
- SIO_delete. Delete stream
- SIO_flush. Idle a stream by flushing buffers
- SIO_get. Get buffer from stream
- SIO_idle. Idle a stream
- SIO_issue. Send a buffer to a stream
- SIO_put. Put buffer to a stream
- SIO_ready. Determine if device is ready
- SIO_reclaim. Request a buffer back from a stream
- SIO_reclaimx. Request a buffer and frame status back from a stream
- SIO_segid. Memory segment used by a stream
- SIO_select. Select a ready device
- SIO_staticbuf. Acquire static buffer from stream

Constants, Types, and Structures

```c
#define SIO_STANDARD     0 /* open stream for */
/* standard streaming model */
#define SIO_ISSUERECLAIM 1 /* open stream for */
/* issue/reclaim streaming model */

#define SIO_INPUT       0  /* open for input */
#define SIO_OUTPUT      1  /* open for output */

typedef SIO_Handle;    /* stream object handle */

typedef DEV_Callback SIO_Callback;

struct SIO_Attrs { /* stream attributes */
    Int    nbufs;     /* number of buffers */
    Int    segid;     /* buffer segment ID */
    size_t align;     /* buffer alignment */
    Bool   flush;    /* TRUE->don't block in DEV_idle*/
    Uns    model;    /* SIO_STANDARD, SIO_ISSUERECLAIM* /
    Uns    timeout;   /* passed to DEV_reclaim */
    SIO_Callback *callback;
        /* initializes callback in DEV_Obj */
} SIO_Attrs;
```
SIO_Attrs SIO_ATTRS = {
    2,            /* nbufs */
    0,            /* segid */
    0,            /* align */
    FALSE,        /* flush */
    SIO_STANDARD, /* model */
    SYS_FOREVER,  /* timeout */
    NULL          /* callback */
};

**Configuration Properties**

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the SIO Manager Properties and SIO Object Properties headings. For descriptions of data types, see Section 1.4, *DSP/BIOS Tconf Overview*, page 1-10.

**Module Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>USEISSUERECLAIM</td>
<td>Bool</td>
<td>false</td>
</tr>
</tbody>
</table>

**Instance Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>deviceName</td>
<td>Reference</td>
<td>prog.get(&quot;dev-name&quot;)</td>
</tr>
<tr>
<td>controlParameter</td>
<td>String</td>
<td>&quot;=&quot;</td>
</tr>
<tr>
<td>mode</td>
<td>EnumString</td>
<td>&quot;input&quot; (&quot;output&quot;)</td>
</tr>
<tr>
<td>bufSize</td>
<td>Int16</td>
<td>0x80</td>
</tr>
<tr>
<td>numBufs</td>
<td>Int16</td>
<td>2</td>
</tr>
<tr>
<td>bufSegId</td>
<td>Reference</td>
<td>prog.get(&quot;SIO.OBJMEMSEG&quot;)</td>
</tr>
<tr>
<td>bufAlign</td>
<td>EnumInt</td>
<td>1 (2, 4, 8, 16, 32, 64, ..., 32768)</td>
</tr>
<tr>
<td>flush</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>modelName</td>
<td>EnumString</td>
<td>&quot;Standard&quot; (&quot;Issue/Reclaim&quot;)</td>
</tr>
<tr>
<td>allocStaticBuf</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>timeout</td>
<td>Int16</td>
<td>-1</td>
</tr>
<tr>
<td>useCallBackFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>callBackFxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>arg0</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>arg1</td>
<td>Arg</td>
<td>0</td>
</tr>
</tbody>
</table>

**Description**

The stream manager provides efficient real-time device-independent I/O through a set of functions that manipulate stream objects accessed through handles of type SIO_Handle. The device independence is afforded by having a common high-level abstraction appropriate for real-time applications, continuous streams of data, that can be associated with a variety of devices. All I/O programming is done in a high-level manner using these stream handles to the devices and the stream manager takes care of dispatching into the underlying device drivers.
For efficiency, streams are treated as sequences of fixed-size buffers of data rather than just sequences of MADUs.

Streams can be opened and closed during program execution using the functions SIO_create and SIO_delete, respectively.

The SIO_issue and SIO_reclaim function calls are enhancements to the basic DSP/BIOS device model. These functions provide a second usage model for streaming, referred to as the issue/reclaim model. It is a more flexible streaming model that allows clients to supply their own buffers to a stream, and to get them back in the order that they were submitted. The SIO_issue and SIO_reclaim functions also provide a user argument that can be used for passing information between the stream client and the stream devices.

Both SWI and TSK threads can be used with the SIO module. However, SWI threads can be used only with the issue/reclaim model, and only then if the timeout parameter is 0. TSK threads can be used with either model.

**SIO Manager Properties**

The following global properties can be set for the SIO module in the SIO Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the SIO objects created with Tconf.
  
  Tconf Name: OBJMEMSEG Type: Reference
  
  Example: bios.SIO.OBJMEMSEG = prog.get("myMEM");

- **Use Only Issue/Reclaim Model.** Enable this option if you want the SIO module to use only the issue/reclaim model. If this option is false (the default) you can also use the standard model.
  
  Tconf Name: USEISSUERECLAIM Type: Bool
  
  Example: bios.SIO.USEISSUERECLAIM = false;

**SIO Object Properties**

To create an SIO object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```java
var mySio = bios.SIO.create("mySio");
```

The following properties can be set for an SIO object in the SIO Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this SIO object.
  
  Tconf Name: comment Type: String
  
  Example: mySio.comment = "my SIO";

- **Device.** Select the device to which you want to bind this SIO object. User-defined devices are listed along with DGN and DPI devices.
  
  Tconf Name: deviceName Type: Reference
  
  Example: mySio.deviceName = prog.get("UDEV0");

- **Device Control String.** Type the device suffix to be passed to any devices stacked below the device connected to this stream.
  
  Tconf Name: controlParameter Type: String
  
  Example: mySio.controlParameter = "/split4/codec";
• **Mode.** Select input if this stream is to be used for input to the application program and output if this stream is to be used for output.
  
  Tconf Name: mode 
  Type: EnumString 
  Options: "input", "output" 
  Example: mySio.mode = "input";

• **Buffer size.** If this stream uses the Standard model, this property controls the size of buffers (in MADUs) allocated for use by the stream. If this stream uses the Issue/Reclaim model, the stream can handle buffers of any size.
  
  Tconf Name: bufSize 
  Type: Int16 
  Example: mySio.bufSize = 0x80;

• **Number of buffers.** If this stream uses the Standard model, this property controls the number of buffers allocated for use by the stream. If this stream uses the Issue/Reclaim model, the stream can handle up to the specified Number of buffers.
  
  Tconf Name: numBufs 
  Type: Int16 
  Example: mySio.numBufs = 2;

• **Place buffers in memory segment.** Select the memory segment to contain the stream buffers if Model is Standard.
  
  Tconf Name: bufSegId 
  Type: Reference 
  Example: mySio.bufSegId = prog.get("myMEM");

• **Buffer alignment.** Specify the memory alignment to use for stream buffers if Model is Standard. For example, if you select 16, the buffer must begin at an address that is a multiple of 16. The default is 1, which means the buffer can begin at any address.
  
  Tconf Name: bufAlign 
  Type: EnumInt 
  Options: 1, 2, 4, 8, 16, 32, 64, ..., 32768 
  Example: mySio.bufAlign = 1;

• **Flush.** Check this box if you want the stream to discard all pending data and return without blocking if this object is idled at run-time with SIO_idle.
  
  Tconf Name: flush 
  Type: Bool 
  Example: mySio.flush = false;

• **Model.** Select Standard if you want all buffers to be allocated when the stream is created. Select Issue/Reclaim if your program is to allocate the buffers and supply them using SIO_issue. Both SWI and TSK threads can be used with the SIO module. However, SWI threads can be used only with the issue/reclaim model, and only then if the timeout parameter is 0. TSK threads can be used with either model.
  
  Tconf Name: modelName 
  Type: EnumString 
  Options: "Standard", "Issue/Reclaim" 
  Example: mySio.modelName = "Standard";

• **Allocate Static Buffer(s).** If this property is set to true, the configuration allocates stream buffers for the user. The SIO_staticbuf function is used to acquire these buffers from the stream. When the Standard model is used, checking this box causes one buffer more than the Number of buffers property to be allocated. When the Issue/Reclaim model is used, buffers are not normally allocated. Checking this box causes the number of buffers specified by the Number of buffers property to be allocated.
  
  Tconf Name: allocStaticBuf 
  Type: Bool 
  Example: mySio.allocStaticBuf = false;
• **Timeout for I/O operation.** This parameter specifies the length of time the I/O operations SIO_get, SIO_put, and SIO_reclaim wait for I/O. The device driver’s Dxx_reclaim function typically uses this timeout while waiting for I/O. If the timeout expires before a buffer is available, the I/O operation returns (-1 * SYS_ETM OuT) and no buffer is returned.

  Tconf Name: timeout  
  Type: Int16
  Example:  
  ```c
  mySio.timeout = -1;
  ```

• **use callback function.** Check this box if you want to use this SIO object with a callback function. In most cases, the callback function is SWI_andnHook or a similar function that posts a SWI. Checking this box allows the SIO object to be used with SWI threads.

  Tconf Name: useCallBackFxn  
  Type: Bool
  Example:  
  ```c
  mySio.useCallBackFxn = false;
  ```

• **callback function.** A function for the SIO object to call. In most cases, the callback function is SWI_andnHook or a similar function that posts a SWI. This function gets called by the class driver (see the DIO Adapter) in the class driver's callback function. This callback function in the class driver usually gets called in the mini-driver code as a result of the HWI.

  Tconf Name: callBackFxn  
  Type: Extern
  Example:  
  ```c
  mySio.callBackFxn = prog.extern("SWI_andnHook");
  ```

• **argument 0.** The first argument to pass to the callback function. If the callback function is SWI_andnHook, this argument should be a SWI object handle.

  Tconf Name: arg0  
  Type: Arg
  Example:  
  ```c
  mySio.arg0 = prog.get("mySwi");
  ```

• **argument 1.** The second argument to pass to the callback function. If the callback function is SWI_andnHook, this argument should be a value mask.

  Tconf Name: arg1  
  Type: Arg
  Example:  
  ```c
  mySio.arg1 = 2;
  ```
**SIO_bufsize**  
*Return the size of the buffers used by a stream*

**C Interface**

**Syntax**
```
size = SIO_bufsize(stream);
```

**Parameters**
- `SIO_Handle stream;`

**Return Value**
- `size_t size;`

**Description**
SIO_bufsize returns the size of the buffers used by stream.

This API can be used only if the model is SIO_STANDARD.

**See Also**
- SIO_segid
SIO_create

Open a stream

C Interface

Syntax

stream = SIO_create(name, mode, bufsize, attrs);

Parameters

String name;    /* name of device */
Int   mode;     /* SIO_INPUT or SIO_OUTPUT */
size_t bufsize; /* stream buffer size */
SIO_Attrs *attrs; /* pointer to stream attributes */

Return Value

SIO_Handle stream; /* stream object handle */

Description

SIO_create creates a new stream object and opens the device specified by name. If successful, SIO_create returns the handle of the new stream object. If unsuccessful, SIO_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS_error, and SYS_error is configured to abort).

Internally, SIO_create calls Dxx_open to open a device.

The mode parameter specifies whether the stream is to be used for input (SIO_INPUT) or output (SIO_OUTPUT).

If the stream is being opened in SIO_STANDARD mode, SIO_create allocates buffers of size bufsize for use by the stream. Initially these buffers are placed on the device todevice queue for input streams, and the device fromdevice queue for output streams.

If the stream is being opened in SIO_ISSUERECLAIM mode, SIO_create does not allocate any buffers for the stream. In SIO_ISSUERECLAIM mode all buffers must be supplied by the client via the SIO_issue call. It does, however, prepare the stream for a maximum number of buffers of the specified size.

If the attrs parameter is NULL, the new stream is assigned the default set of attributes specified by SIO_ATTRS. The following stream attributes are currently supported:

struct SIO_Attrs {
    Int    nbufs;    /* number of buffers */
    Int    segid;   /* buffer segment ID */
    size_t align; /* buffer alignment */
    Bool   flush;  /* TRUE->don't block in DEV_idle */
    Uns   model;    /* SIO_STANDARD,SIO_ISSUERECLAIM */
    Uns timeout;    /* passed to DEV_reclaim */
    SIO_Callback *callback;
        /* initialize callback in DEV_Obj */
} SIO_Attrs;

- **nbufs.** Specifies the number of buffers allocated by the stream in the SIO_STANDARD usage model, or the number of buffers to prepare for in the SIO_ISSUERECLAIM usage model. The default value of nbufs is 2. In the SIO_ISSUERECLAIM usage model, nbufs is the maximum number of buffers that can be outstanding (that is, issued but not reclaimed) at any point in time.

- **segid.** Specifies the memory segment for stream buffers. Use the memory segment names defined in the configuration. The default value is 0, meaning that buffers are to be allocated from the "Segment for DSP/BIOS objects" property in the MEM Manager Properties.
• **align.** Specifies the memory alignment for stream buffers. The default value is 0, meaning that no alignment is needed.

• **flush.** Indicates the desired behavior for an output stream when it is deleted. If flush is TRUE, a call to SIO_delete causes the stream to discard all pending data and return without blocking. If flush is FALSE, a call to SIO_delete causes the stream to block until all pending data has been processed. The default value is FALSE.

• **model.** Indicates the usage model that is to be used with this stream. The two usage models are SIO_ISSUERECLAIM and SIO_STANDARD. The default usage model is SIO_STANDARD.

• **timeout.** Specifies the length of time the device driver waits for I/O completion before returning an error (for example, SYS_ETIMEOUT). timeout is usually passed as a parameter to SEM_pend by the device driver. The default is SYS_FOREVER which indicates that the driver waits forever. If timeout is SYS_FOREVER, the task remains suspended until a buffer is available to be returned by the stream. The timeout attribute applies to the I/O operations SIO_get, SIO_put, and SIO_reclaim. If timeout is 0, the I/O operation returns immediately. If the timeout expires before a buffer is available to be returned, the I/O operation returns the value of (-1 * SYS_ETIMEOUT). Otherwise the I/O operation returns the number of valid MADUs in the buffer, or -1 multiplied by an error code.

• **callback.** Specifies a pointer to channel-specific callback information. The SIO_Callback structure is defined by the SIO module to match the DEV_Callback structure. This structure contains the callback function and two function arguments. The callback function is typically SWI_andnHook or a similar function that posts a SWI. Callbacks can only be used with the SIO_ISSUERECLAIM model.

Existent DEV drivers do not use this callback function. While DEV drivers can be modified to use this callback, it is not recommended. Instead, the IOM device driver model is recommended for drivers that need the SIO callback feature. IOM drivers use the DIO module to interface with the SIO functions.

SIO_create calls MEM_alloc to dynamically create the object’s data structure. MEM_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is set by the "Segment for DSP/BIOS objects" property in the MEM Manager Properties.

**Constraints and Calling Context**

• A stream can only be used by one task simultaneously. Catastrophic failure can result if more than one task calls SIO_get (or SIO_issue / SIO_reclaim) on the same input stream, or more than one task calls SIO_put (or SIO_issue / SIO_reclaim) on the same output stream.

• SIO_create creates a stream dynamically. Do not call SIO_create on a stream that was created with Tconf.

• You can reduce the size of your application program by creating objects with Tconf rather than using the XXX_create functions. However, streams that are to be used with stacking drivers must be created dynamically with SIO_create.

• SIO_create cannot be called from a SWI or HWI.

**See Also**

Dxx_open
MEM_alloc
SEM_pend
SIO_delete
SIO_issue
SIO_reclaim
SYS_error
**SIO_ctrl**  
*Perform a device-dependent control operation*

**C Interface**

Syntax

```c
status = SIO_ctrl(stream, cmd, arg);
```

Parameters

```
SIO_Handle stream; /* stream handle */
Uns cmd; /* command to device */
Arg arg; /* arbitrary argument */
```

Return Value

```
Int status; /* device status */
```

**Description**

SIO_ctrl causes a control operation to be issued to the device associated with stream. cmd and arg are passed directly to the device.

SIO_ctrl returns SYS_OK if successful, and a non-zero device-dependent error value if unsuccessful.

Internally, SIO_ctrl calls Dxx_ctrl to send control commands to a device.

**Constraints and Calling Context**

- SIO_ctrl cannot be called from an HWI.

**See Also**

- Dxx_ctrl
**SIO_delete**  
*Close a stream and free its buffers*

**C Interface**

**Syntax**

```c
status = SIO_delete(stream);
```

**Parameters**

- `SIO_Handle stream; /* stream object */`

**Return Value**

- `Int status; /* result of operation */`

**Description**

SIO_delete idles the device before freeing the stream object and buffers.

If the stream being deleted was opened for input, then any pending input data is discarded. If the stream being deleted was opened for output, the method for handling data is determined by the value of the flush field in the SIO_Attrs structure (passed in with SIO_create). If flush is TRUE, SIO_delete discards all pending data and returns without blocking. If flush is FALSE, SIO_delete blocks until all pending data has been processed by the stream.

SIO_delete returns SYS_OK if and only if the operation is successful.

SIO_delete calls MEM_free to delete a stream. MEM_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

Internally, SIO_delete first calls Dxx_idle to idle the device. Then it calls Dxx_close.

**Constraints and Calling Context**

- SIO_delete cannot be called from a SWI or HWI.
- No check is performed to prevent SIO_delete from being used on a statically-created object. If a program attempts to delete a stream object that was created using Tconf, SYS_error is called.
- In SIO_ISSUERECLAIM mode, all buffers issued to a stream must be reclaimed before SIO_delete is called. Failing to reclaim such buffers causes a memory leak.

**See Also**

- SIO_create
- SIO_flush
- SIO_idle
- Dxx_idle
- Dxx_close
**SIO_flush**  
*Flush a stream*

**C Interface**

```c
status = SIO_flush(stream);
```

**Parameters**

- `SIO_Handle stream; /* stream handle */`

**Return Value**

- `Int status; /* result of operation */`

**Description**

SIO_flush causes all pending data to be discarded regardless of the mode of the stream. SIO_flush differs from SIO_idle in that SIO_flush never suspends program execution to complete processing of data, even for a stream created in output mode.

The underlying device connected to stream is idled as a result of calling SIO_flush. In general, the interrupt is disabled for the device.

One of the purposes of this function is to provide synchronization with the external environment.

SIO_flush returns SYS_OK if and only if the stream is successfully idled.

Internally, SIO_flush calls Dxx_idle and flushes all pending data.

If a callback was specified in the SIO_Attrs structure used with SIO_create, then SIO_flush performs no processing and returns SYS_OK.

**Constraints and Calling Context**

- SIO_flush cannot be called from an HWI.
- If SIO_flush is called from a SWI, no action is performed.

**See Also**

- Dxx_idle
- SIO_create
- SIO_idle
### SIO_get

**Get a buffer from stream**

#### C Interface

**Syntax**

```c
nmadus = SIO_get(stream, bufp);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>SIO_Handle</td>
<td>stream /* stream handle */</td>
</tr>
<tr>
<td>*bufp;</td>
<td>/* pointer to a buffer */</td>
</tr>
</tbody>
</table>

**Return Value**

| Int          | nmadus; /* number of MADUs read or error if negative */ |

#### Description

SIO_get exchanges an empty buffer with a non-empty buffer from stream. The bufp is an input/output parameter which points to an empty buffer when SIO_get is called. When SIO_get returns, bufp points to a new (different) buffer, and nmadus indicates success or failure of the call.

SIO_get blocks until a buffer can be returned to the caller, or until the stream's timeout attribute expires (see SIO_create). If a timeout occurs, the value (-1 * SYS_TIMEOUT) is returned. If timeout is not equal to SYS_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

To indicate success, SIO_get returns a positive value for nmadus. As a success indicator, nmadus is the number of MADUs received from the stream. To indicate failure, SIO_get returns a negative value for nmadus. As a failure indicator, nmadus is the actual error code multiplied by -1.

An inconsistency exists between the sizes of buffers in a stream and the return types corresponding to these sizes. While all buffer sizes in a stream are of type size_t, APIs that return a buffer size return a type of Int. The inconsistency is due to a change in stream buffer sizes and the need to retain the return type for backward compatibility. Because of this inconsistency, it is not possible to return the correct buffer size when the actual buffer size exceeds the size of an Int type. This issue has the following implications:

- **If the actual buffer size is less than/equal to the maximum positive Int value (15 bits).** Check the return value for negative values, which should be treated as errors. Positive values reflect the correct size.

- **If the actual buffer size is greater than the maximum positive Int value.** Ignore the return value. There is little room for this situation on 'C55x large model since size_t is the same as unsigned int. Since the sign in Int takes up one bit, the size_t type contains just one more bit than an int. If you are using the 'C55x huge model, size_t is 32 bits and Int allows positive integers only up to 15 bits.

For other architectures, size_t is:

- 'C28x - unsigned long
- 'C54x/'C55x/'C6x - unsigned int

Since this operation is generally accomplished by redirection rather than by copying data, references to the contents of the buffer pointed to by bufp must be recomputed after the call to SIO_get.

A task switch occurs when calling SIO_get if there are no non-empty data buffers in stream.

Internally, SIO_get calls Dxx_issue and Dxx_reclaim for the device.
Constraints and Calling Context

- The stream must not be created with attrs.model set to SIO_ISSUERECLAIM. The results of calling SIO_get on a stream created for the issue/reclaim streaming model are undefined.
- SIO_get cannot be called from a SWI or HWI.
- This API is callable from the program’s main() function only if the stream’s configured timeout attribute is 0, or if it is certain that there is a buffer available to be returned.

See Also
- Dxx_issue
- Dxx_reclaim
- SIO_put
**SIO_idle**  
_Idle a stream_

### C Interface

#### Syntax

```c
status = SIO_idle(stream);
```

#### Parameters

- `SIO_Handle stream; /* stream handle */`

#### Return Value

- `Int status; /* result of operation */`

### Description

If stream is being used for output, `SIO_idle` causes any currently buffered data to be transferred to the output device associated with stream. `SIO_idle` suspends program execution for as long as is required for the data to be consumed by the underlying device.

If stream is being used for input, `SIO_idle` causes any currently buffered data to be discarded. The underlying device connected to stream is idled as a result of calling `SIO_idle`. In general, the interrupt is disabled for this device.

If discarding of unrendered output is desired, use `SIO_flush` instead.

One of the purposes of this function is to provide synchronization with the external environment. `SIO_idle` returns SYS_OK if and only if the stream is successfully idled.

Internally, `SIO_idle` calls `Dxx_idle` to idle the device.

If a callback was specified in the `SIO_Attrs` structure used with `SIO_create`, then `SIO_idle` performs no processing and returns SYS_OK.

### Constraints and Calling Context

- `SIO_idle` cannot be called from an HWI.
- If `SIO_idle` is called from a SWI, no action is performed.

### See Also

- `Dxx_idle`
- `SIO_create`
- `SIO_flush`
**SIO_issue**

Send a buffer to a stream

**C Interface**

**Syntax**

```c
status = SIO_issue(stream, pbuf, nmadus, arg);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>SIO_Handle</td>
<td><code>stream</code>; /* stream handle */</td>
</tr>
<tr>
<td>Ptr</td>
<td><code>pbuf</code>; /* pointer to a buffer */</td>
</tr>
<tr>
<td>size_t</td>
<td><code>nmadus</code>; /* number of MADUs in the buffer */</td>
</tr>
<tr>
<td>Arg</td>
<td><code>arg</code>; /* user argument */</td>
</tr>
</tbody>
</table>

**Return Value**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Int</td>
<td><code>status</code>; /* result of operation */</td>
</tr>
</tbody>
</table>

**Description**

SIO_issue is used to send a buffer and its related information to a stream. The buffer-related information consists of the logical length of the buffer (nmadus), and the user argument to be associated with that buffer. SIO_issue sends a buffer to the stream and return to the caller without blocking. It also returns an error code indicating success (SYS_OK) or failure of the call.

Internally, SIO_issue calls Dxx_issue after placing a new input frame on the driver's device->todevice queue.

Failure of SIO_issue indicates that the stream was not able to accept the buffer being issued or that there was a device error when the underlying Dxx_issue was called. In the first case, the application is probably issuing more frames than the maximum MADUs allowed for the stream, before it reclaims any frames. In the second case, the failure reveals an underlying device driver or hardware problem. If SIO_issue fails, SIO_idle should be called for an SIO_INPUT stream, and SIO_flush should be called for an SIO_OUTPUT stream, before attempting more I/O through the stream.

The interpretation of nmadus, the logical size of a buffer, is direction-dependent. For a stream opened in SIO_OUTPUT mode, the logical size of the buffer indicates the number of valid MADUs of data it contains. For a stream opened in SIO_INPUT mode, the logical length of a buffer indicates the number of MADUs being requested by the client. In either case, the logical size of the buffer must be less than or equal to the physical size of the buffer.

The argument arg is not interpreted by DSP/BIOS, but is offered as a service to the stream client. DSP/BIOS and all DSP/BIOS-compliant device drivers preserve the value of arg and maintain its association with the data that it was issued with. arg provides a user argument as a method for a client to associate additional information with a particular buffer of data.

SIO_issue is used in conjunction with SIO_reclaim to operate a stream opened in SIO_ISSUERECLAIM mode. The SIO_issue call sends a buffer to a stream, and SIO_reclaim retrieves a buffer from a stream. In normal operation each SIO_issue call is followed by an SIO_reclaim call. Short bursts of multiple SIO_issue calls can be made without an intervening SIO_reclaim call. Short bursts of multiple SIO_issue calls can be made without an intervening SIO_reclaim call, but over the life of the stream SIO_issue and SIO_reclaim must be called the same number of times.

At any given point in the life of a stream, the number of SIO_issue calls can exceed the number of SIO_reclaim calls by a maximum of nbufs. The value of nbufs is determined by the SIO_create call or by setting the Number of buffers property for the object in the configuration.
Note: An SIO_reclaim call should not be made without at least one outstanding SIO_issue call. Calling SIO_reclaim with no outstanding SIO_issue calls has undefined results.

Constraints and Calling Context

- The stream must be created with attrs.model set to SIO_ISSUERECLAIM.
- SIO_issue cannot be called from an HWI.

See Also
Dxx_issue
SIO_create
SIO_reclaim
SIO_put

Put a buffer to a stream

C Interface

Syntax

\[ \text{nmadus} = \text{SIO\_put}(\text{stream}, \text{bufp}, \text{nmadus}); \]

Parameters

- \text{SIO\_Handle stream; /* stream handle */}
- \text{Ptr *bufp; /* pointer to a buffer */}
- \text{size\_t nmadus; /* number of MADUs in the buffer */}

Return Value

- \text{Int nmadus; /* number of MADUs, negative if error */}

Description

SIO_put exchanges a non-empty buffer with an empty buffer. The bufp parameter is an input/output parameter that points to a non-empty buffer when SIO_put is called. When SIO_put returns, bufp points to a new (different) buffer, and nmadus indicates success or failure of the call.

SIO_put blocks until a buffer can be returned to the caller, or until the stream's timeout attribute expires (see SIO_create). If a timeout occurs, the value (-1 * SYSETIMEOUT) is returned. If timeout is not equal to SYS_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

To indicate success, SIO_put returns a positive value for nmadus. As a success indicator, nmadus is the number of valid MADUs in the buffer returned by the stream (usually zero). To indicate failure, SIO_put returns a negative value (the actual error code multiplied by -1).

An inconsistency exists between the sizes of buffers in a stream and the return types corresponding to these sizes. While all buffer sizes in a stream are of type size_t, APIs that return a buffer size return a type of Int. The inconsistency is due to a change in stream buffer sizes and the need to retain the return type for backward compatibility. Because of this inconsistency, it is not possible to return the correct buffer size when the actual buffer size exceeds the size of an Int type. This issue has the following implications:

- **If the actual buffer size is less than/equal to the maximum positive Int value (15 bits).** Check the return value for negative values, which should be treated as errors. Positive values reflect the correct size.

- **If the actual buffer size is greater than the maximum positive Int value.** Ignore the return value. There is little room for this situation on 'C55x large model since size_t is the same as unsigned int. Since the sign in Int takes up one bit, the size_t type contains just one more bit than an Int. If you are using the 'C55x huge model, size_t is 32 bits and Int allows positive integers only up to 15 bits.

Since this operation is generally accomplished by redirection rather than by copying data, references to the contents of the buffer pointed to by bufp must be recomputed after the call to SIO_put.

A task switch occurs when calling SIO_put if there are no empty data buffers in the stream.

Internally, SIO_put calls Dxx_issue and Dxx_reclaim for the device.

Constraints and Calling Context

- The stream must not be created with attrs.model set to SIO_ISSUERECLAIM. The results of calling SIO_put on a stream created for the issue/reclaim model are undefined.
- SIO_put cannot be called from a SWI or HWI.
- This API is callable from the program’s main() function only if the stream's configured timeout attribute is 0, or if it is certain that there is a buffer available to be returned.

See Also
- Dxx_issue
- Dxx_reclaim
- SIO_get
SIO_ready

Determine if device for stream is ready

C Interface

Syntax

    status = SIO_ready(stream);

Parameters

    SIO_Handle stream;

Return Value

    Int status; /* result of operation */

Description

    SIO_ready returns TRUE if a stream is ready for input or output.

    If you are using SIO objects with SWI threads, you may want to use SIO_ready to avoid calling
    SIO_reclaim when it may fail because no buffers are available.

    SIO_ready is similar to SIO_select, except that it does not block. You can prevent SIO_select from
    blocking by setting the timeout to zero, however, SIO_ready is more efficient because SIO_select
    performs SEM_pend with a timeout of zero. SIO_ready simply polls the stream to see if the device is
    ready.

See Also

    SIO_select
**SIO_reclaim**  
*Request a buffer back from a stream*

### C Interface

**Syntax**

```c
nmadus = SIO_reclaim(stream, pbufp, parg);
```

**Parameters**

- **SIO_Handle stream; /* stream handle */**
- **Ptr *pbufp; /* pointer to the buffer */**
- **Arg *parg; /* pointer to a user argument */**

**Return Value**

- **Int nmadus; /* number of MADUs or error if negative */**

### Description

SIO_reclaim is used to request a buffer back from a stream. It returns a pointer to the buffer, the number of valid MADUs in the buffer, and a user argument (parg). After the SIO_reclaim call parg points to the same value that was passed in with this buffer using the SIO_issue call.

If you want to return a frame-specific status along with the buffer, use SIO_reclaimx instead of SIO_reclaim.

Internally, SIO_reclaim calls Dxx_reclaim, then it gets the frame from the driver's device->fromdevice queue.

If a stream was created in SIO_OUTPUT mode, then SIO_reclaim returns an empty buffer, and nmadus is zero, since the buffer is empty. If a stream was opened in SIO_INPUT mode, SIO_reclaim returns a non-empty buffer, and nmadus is the number of valid MADUs of data in the buffer.

If SIO_reclaim is called from a TSK thread, it blocks (in either mode) until a buffer can be returned to the caller, or until the stream's timeout attribute expires (see SIO_create), and it returns a positive number or zero (indicating success), or a negative number (indicating an error condition). If timeout is not equal to SYS_FOREVER or 0, the task suspension time can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

If SIO_reclaim is called from a SWI thread, it returns an error if it is called when no buffer is available. SIO_reclaim never blocks when called from a SWI.

To indicate success, SIO_reclaim returns a positive value for nmadus. As a success indicator, nmadus is the number of valid MADUs in the buffer. To indicate failure, SIO_reclaim returns a negative value for nmadus. As a failure indicator, nmadus is the actual error code multiplied by -1.

Failure of SIO_reclaim indicates that no buffer was returned to the client. Therefore, if SIO_reclaim fails, the client should not attempt to de-reference pbufp, since it is not guaranteed to contain a valid buffer pointer.

An inconsistency exists between the sizes of buffers in a stream and the return types corresponding to these sizes. While all buffer sizes in a stream are of type size_t, APIs that return a buffer size return a type of Int. The inconsistency is due to a change in stream buffer sizes and the need to retain the return type for backward compatibility. Because of this inconsistency, it is not possible to return the correct buffer size when the actual buffer size exceeds the size of an Int type. This issue has the following implications:
• **If the actual buffer size is less than/equal to the maximum positive Int value (15 bits).** Check the return value for negative values, which should be treated as errors. Positive values reflect the correct size.

• **If the actual buffer size is greater than the maximum positive Int value.** Ignore the return value. There is little room for this situation on 'C55x large model since size_t is the same as unsigned int. Since the sign in Int takes up one bit, the size_t type contains just one more bit than an Int. If you are using the 'C55x huge model, size_t is 32 bits and Int allows positive integers only up to 15 bits.

SIO_reclaim is used in conjunction with SIO_issue to operate a stream opened in SIO_ISSUERECLAIM mode. The SIO_issue call sends a buffer to a stream, and SIO_reclaim retrieves a buffer from a stream. In normal operation each SIO_issue call is followed by an SIO_reclaim call. Short bursts of multiple SIO_issue calls can be made without an intervening SIO_reclaim call, but over the life of the stream SIO_issue and SIO_reclaim must be called the same number of times. The number of SIO_issue calls can exceed the number of SIO_reclaim calls by a maximum of nbufs at any given time. The value of nbufs is determined by the SIO_create call or by setting the Number of buffers property for the object in the configuration.

**Note:** An SIO_reclaim call should not be made without at least one outstanding SIO_issue call. Calling SIO_reclaim with no outstanding SIO_issue calls has undefined results.

SIO_reclaim only returns buffers that were passed in using SIO_issue. It also returns the buffers in the same order that they were issued.

A task switch occurs when calling SIO_reclaim if timeout is not set to 0, and there are no data buffers available to be returned.

**Constraints and Calling Context**

• The stream must be created with attrs.model set to SIO_ISSUERECLAIM.

• There must be at least one outstanding SIO_issue when an SIO_reclaim call is made.

• SIO_reclaim returns an error if it is called from a SWI when no buffer is available. SIO_reclaim does not block if called from a SWI.

• All frames issued to a stream must be reclaimed before closing the stream.

• SIO_reclaim cannot be called from a HWI.

• This API is callable from the program’s main() function only if the stream's configured timeout attribute is 0, or if it is certain that there is a buffer available to be returned.

**See Also**

Dxx_reclaim
SIO_issue
SIO_create
SIO_reclaimx
SiO_reclaimx — Request a buffer back from a stream, including frame status

C Interface

Syntax

```c
nmadus = SIO_reclaimx(stream, *pbufp, *parg, *pfstatus);
```

Parameters

- **SIO_Handle stream;** /* stream handle */
- **Ptr *pbufp;** /* pointer to the buffer */
- **Arg *parg;** /* pointer to a user argument */
- **Int *pfstatus;** /* pointer to frame status */

Return Value

- **Int nmadus;** /* number of MADUs or error if negative */

Description

SiO_reclaimx is identical to SiO_reclaim, except that it also returns a frame-specific status in the Int pointed to by the pfstatus parameter.

The device driver can use the frame-specific status to pass frame-specific status information to the application. This allows the device driver to fill in the status for each frame, and gives the application access to that status.

The returned frame status is valid only if SiO_reclaimx() returns successfully. If the nmadus value returned is negative, the frame status should not be considered accurate.

Constraints and Calling Context

- The stream must be created with attrs.model set to SIO_ISSUERECLAIM.
- There must be at least one outstanding SiO_issue when an SiO_reclaimx call is made.
- SiO_reclaimx returns an error if it is called from a SWI when no buffer is available. SiO_reclaimx does not block if called from a SWI.
- All frames issued to a stream must be reclaimed before closing the stream.
- SiO_reclaimx cannot be called from a HWI.
- This API is callable from the program’s main() function only if the stream's configured timeout attribute is 0, or if it is certain that there is a buffer available to be returned.

See Also

- SiO_reclaim
SIO_segid  

Return the memory segment used by the stream

C Interface

Syntax

```c
segid = SIO_segid(stream);
```

Parameters

- `SIO_Handle stream`;

Return Value

- `Int segid; /* memory segment ID */`

Description

SIO_segid returns the identifier of the memory segment that stream uses for buffers.

See Also

- SIO_bufsize
**SIO_select**  
*Select a ready device*

**C Interface**

**Syntax**

```c
mask = SIO_select(streamtab, nstreams, timeout);
```

**Parameters**

- `SIO_Handle streamtab; /* stream table */`
- `Int nstreams; /* number of streams */`
- `Uns timeout; /* return after this many system clock ticks */`

**Return Value**

- `Uns mask; /* stream ready mask */`

**Description**

*SIO_select* waits until one or more of the streams in the `streamtab[]` array is ready for I/O (that is, it does not block when an I/O operation is attempted).

`streamtab[]` is an array of streams where `nstreams < 16`. The timeout parameter indicates the number of system clock ticks to wait before a stream becomes ready. If timeout is 0, *SIO_select* returns immediately. If timeout is SYS_FOREVER, *SIO_select* waits until one of the streams is ready. Otherwise, *SIO_select* waits for up to 1 system clock tick less than timeout due to granularity in system timekeeping.

The return value is a mask indicating which streams are ready for I/O. A 1 in bit position `j` indicates the stream `streamtab[j]` is ready.

*SIO_select* results in a context switch if no streams are ready for I/O.

Internally, *SIO_select* calls *Dxx_ready* to determine if the device is ready for an I/O operation.

*SIO_ready* is similar to *SIO_select*, except that it does not block. You can prevent *SIO_select* from blocking by setting the timeout to zero, however, *SIO_ready* is more efficient in this situation because *SIO_select* performs *SEM_pend* with a timeout of zero. *SIO_ready* simply polls the stream to see if the device is ready.

For the *SIO_STANDARD* model in *SIO_INPUT* mode only, if stream I/O has not been started (that is, if *SIO_get* has not been called), *SIO_select* calls *Dxx_issue* for all empty frames to start the device.

**Constraints and Calling Context**

- `streamtab[]` must contain handles of type `SIO_Handle` returned from prior calls to *SIO_create*.
- `streamtab[]` is an array of streams; `streamtab[i]` corresponds to bit position `i` in mask.
- *SIO_select* cannot be called from an HWI.
- *SIO_select* can only be called from a SWI if the timeout value is zero.

**See Also**

- *Dxx_ready*
- *SIO_get*
- *SIO_put*
- *SIO_ready*
- *SIO_reclaim*
SIO_staticbuf

Acquire static buffer from stream

C Interface

Syntax

```
nmadus = SIO_staticbuf(stream, bufp);
```

Parameters

- **SIO_Handle stream;** /* stream handle */
- **Ptr *bufp;** /* pointer to a buffer */

Return Value

- **Int nmadus;** /* number of MADUs in buffer */

Description

SIO_staticbuf returns buffers for static streams that were configured statically. Buffers are allocated for static streams by checking the Allocate Static Buffer(s) check box for the related SIO object.

SIO_staticbuf returns the size of the buffer or 0 if no more buffers are available from the stream.

An inconsistency exists between the sizes of buffers in a stream and the return types corresponding to these sizes. While all buffer sizes in a stream are of type size_t, APIs that return a buffer size return a type of Int. This due to a change in stream buffer sizes and the need to retain the return type for backward compatibility. Because of this inconsistency, it is not possible to return the correct buffer size when the actual buffer size exceeds the size of an Int type. This issue has the following implications:

- **If the actual buffer size is less than/equal to the maximum positive Int value (15 bits).** Check the return value for negative values, which indicate errors. Positive values reflect the correct size.

- **If the actual buffer size is greater than the maximum positive Int value.** Ignore the return value. There is little room for this situation on 'C55x large model since size_t is the same as unsigned int. Since the sign in Int takes up one bit, the size_t type contains just one more bit than an Int. If you are using the 'C55x huge model, size_t is 32 bits and Int allows positive integers only up to 15 bits.

SIO_staticbuf can be called multiple times for SIO_ISSUERECLAIM model streams.

SIO_staticbuf must be called to acquire all static buffers before calling SIO_get, SIO_put, SIO_issue or SIO_reclaim.

Constraints and Calling Context

- SIO_staticbuf should only be called for streams that are defined statically using Tconf.
- SIO_staticbuf should only be called for static streams whose "Allocate Static Buffer(s)" property has been set to true.
- SIO_staticbuf cannot be called after SIO_get, SIO_put, SIO_issue or SIO_reclaim have been called for the given stream.
- SIO_staticbuf cannot be called from an HWI.

See Also

- SIO_get
2.25 STS Module

The STS module is the statistics objects manager.

Functions

• STS_add. Update statistics using provided value
• STS_delta. Update statistics using difference between provided value and setpoint
• STS_reset. Reset values stored in STS object
• STS_set. Save a setpoint value

Constants, Types, and Structures

```c
struct STS_Obj {
    LgInt    num;     /* count */
    LgInt    acc;     /* total value */
    LgInt    max;     /* maximum value */
}
```

Note: STS objects should not be shared across threads. Therefore, STS_add, STS_delta, STS_reset, and STS_set are not reentrant.

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the STS Manager Properties and STS Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>previousVal</td>
<td>Int32</td>
<td>0</td>
</tr>
<tr>
<td>unitType</td>
<td>EnumString</td>
<td>&quot;Not time based&quot;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>(&quot;High resolution time based&quot;,</td>
</tr>
<tr>
<td></td>
<td></td>
<td>&quot;Low resolution time based&quot;)</td>
</tr>
<tr>
<td>operation</td>
<td>EnumString</td>
<td>&quot;Nothing&quot; (&quot;A * x&quot;, &quot;A * x + B&quot;,</td>
</tr>
<tr>
<td></td>
<td></td>
<td>(&quot;A * x + B) / C&quot;)</td>
</tr>
<tr>
<td>numA</td>
<td>Int32</td>
<td>1</td>
</tr>
<tr>
<td>numB</td>
<td>Int32</td>
<td>0</td>
</tr>
<tr>
<td>numC</td>
<td>Int32</td>
<td>1</td>
</tr>
</tbody>
</table>

Description

The STS module manages objects called statistics accumulators. Each STS object accumulates the following statistical information about an arbitrary 32-bit wide data series:

• **Count.** The number of values in an application-supplied data series
• **Total.** The sum of the individual data values in this series
• **Maximum.** The largest value already encountered in this series

Using the count and total, the Statistics View analysis tool calculates the average on the host.

Statistics are accumulated in 32-bit variables on the target and in 64-bit variables on the host. When the host polls the target for real-time statistics, it resets the variables on the target. This minimizes space requirements on the target while allowing you to keep statistics for long test runs.

**Default STS Tracing**

In the RTA Control Panel, you can enable statistics tracing for the following modules by marking the appropriate checkbox. You can also set the HWI Object Properties to perform various STS operations on registers, addresses, or pointers.

Except for tracing TSK execution, your program does not need to include any calls to STS functions in order to gather these statistics. The default units for the statistics values are shown in Table Table 2-6.

**Table 2-6: Statistics Units for HWI, PIP, PRD, and SWI Modules**

<table>
<thead>
<tr>
<th>Module</th>
<th>Units</th>
</tr>
</thead>
<tbody>
<tr>
<td>HWI</td>
<td>Gather statistics on monitored values within HWIs</td>
</tr>
<tr>
<td>PIP</td>
<td>Number of frames read from or written to data pipe (count only)</td>
</tr>
<tr>
<td>PRD</td>
<td>Number of ticks elapsed from time that the PRD object is ready to run to end of execution</td>
</tr>
<tr>
<td>SWI</td>
<td>Instruction cycles elapsed from time posted to completion</td>
</tr>
<tr>
<td>TSK</td>
<td>Instruction cycles elapsed from time TSK is made ready to run until the application calls TSK_deltatime.</td>
</tr>
</tbody>
</table>

**Custom STS Objects**

You can create custom STS objects using Tconf. The STS_add operation updates the count, total, and maximum using the value you provide. The STS_set operation sets a previous value. The STS_delta operation accumulates the difference between the value you pass and the previous value and updates the previous value to the value you pass.

By using custom STS objects and the STS operations, you can do the following:

• **Count the number of occurrences of an event.** You can pass a value of 0 to STS_add. The count statistic tracks how many times your program calls STS_add for this STS object.

• **Track the maximum and average values for a variable in your program.** For example, suppose you pass amplitude values to STS_add. The count tracks how many times your program calls STS_add for this STS object. The total is the sum of all the amplitudes. The maximum is the largest value. The Statistics View calculates the average amplitude.

• **Track the minimum value for a variable in your program.** Negate the values you are monitoring and pass them to STS_add. The maximum is the negative of the minimum value.

• **Time events or monitor incremental differences in a value.** For example, suppose you want to measure the time between hardware interrupts. You would call STS_set when the program begins running and STS_delta each time the interrupt routine runs, passing the result of CLK_gettime each time. STS_delta subtracts the previous value from the current value. The count tracks how many times the interrupt routine was performed. The maximum is the largest number of clock counts between interrupt routines. The Statistics View also calculates the average number of clock counts.
• **Monitor differences between actual values and desired values.** For example, suppose you want to make sure a value stays within a certain range. Subtract the midpoint of the range from the value and pass the absolute value of the result to **STS_add**. The count tracks how many times your program calls **STS_add** for this **STS** object. The total is the sum of all deviations from the middle of the range. The maximum is the largest deviation. The **Statistics View** calculates the average deviation.

You can further customize the statistics data by setting the **STS Object Properties** to apply a printf format to the **Total**, **Max**, and **Average** fields in the **Statistics View** window and choosing a formula to apply to the data values on the host.

### Statistics Data

#### Gathering by the Statistics View Analysis Tool

The statistics manager allows the creation of any number of statistics objects, which in turn can be used by the application to accumulate simple statistics about a time series. This information includes the 32-bit maximum value, the last 32-bit value passed to the object, the number of samples (up to \(2^{32} - 1\) samples), and the 32-bit sum of all samples.

These statistics are accumulated on the target in real-time until the host reads and clears these values on the target. The host, however, continues to accumulate the values read from the target in a host buffer which is displayed by the **Statistics View** real-time analysis tool. Provided that the host reads and clears the target statistics objects faster than the target can overflow the 32-bit wide values being accumulated, no information loss occurs.

Using **Tconf**, you can select a Host Operation for an **STS** object. The statistics are filtered on the host using the operation and variables you specify. Figure Figure 2-11 shows the effects of the \((A \times X + B) / C\) operation.

![Figure 2-11. Statistics Accumulation on the Host](image)

### STS Manager Properties

The following global property can be set for the **STS** module in the **STS Manager Properties** dialog of the DSP/BIOS Configuration Tool or in a **Tconf** script:

• **Object Memory.** The memory segment that contains **STS** objects.
  
  **Tconf Name:** OBJMEMSEG  
  **Type:** Reference  
  **Example:**  
  ```
  bios.STS.OBJMEMSEG = prog.get("myMEM");
  ```
To create an STS object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```javascript
var mySts = bios.STS.create("mySts");
```

The following properties can be set for an STS object in the STS Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this STS object.

<table>
<thead>
<tr>
<th>Tconf Name: comment</th>
<th>Type: String</th>
</tr>
</thead>
<tbody>
<tr>
<td>Example:</td>
<td></td>
</tr>
<tr>
<td></td>
<td>mySts.comment = &quot;my STS&quot;;</td>
</tr>
</tbody>
</table>

- **prev.** The initial 32-bit history value to use in this object.

<table>
<thead>
<tr>
<th>Tconf Name: previousVal</th>
<th>Type: Int32</th>
</tr>
</thead>
<tbody>
<tr>
<td>Example:</td>
<td></td>
</tr>
<tr>
<td></td>
<td>mySts.previousVal = 0;</td>
</tr>
</tbody>
</table>

- **unit type.** The unit type property enables you to choose the type of time base units.

  - Not time based. If you select this unit type, the values are displayed in the Statistics View without applying any conversion.
  - High-resolution time based. If you select this type, the Statistics View, by default, presents results in units of instruction cycles.
  - Low-resolution time based. If you select this unit type, the default Statistics View presents results in timer interrupt units.

<table>
<thead>
<tr>
<th>Tconf Name: unitType</th>
<th>Type: EnumString</th>
</tr>
</thead>
<tbody>
<tr>
<td>Options:</td>
<td>&quot;Not time based&quot;, &quot;High resolution time based&quot;, &quot;Low resolution time based&quot;</td>
</tr>
<tr>
<td>Example:</td>
<td>mySts.unitType = &quot;Not time based&quot;;</td>
</tr>
</tbody>
</table>

- **host operation.** The expression evaluated (by the host) on the data for this object before it is displayed by the Statistics View real-time analysis tool. The operation can be:

  - A \times X
  - A \times X + B
  - (A \times X + B) / C

<table>
<thead>
<tr>
<th>Tconf Name: operation</th>
<th>Type: EnumString</th>
</tr>
</thead>
<tbody>
<tr>
<td>Options:</td>
<td>&quot;Nothing&quot;, &quot;A \times X&quot;, &quot;A \times X + B&quot;, &quot;(A \times X + B) / C&quot;</td>
</tr>
<tr>
<td>Example:</td>
<td>mySts.operation = &quot;Nothing&quot;;</td>
</tr>
</tbody>
</table>

- **A, B, C.** The integer parameters used by the expression specified by the Host Operation property above.

<table>
<thead>
<tr>
<th>Tconf Name: numA</th>
<th>Type: Int32</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>mySts.numA = 1;</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Tconf Name: numB</th>
<th>Type: Int32</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>mySts.numB = 0;</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Tconf Name: numC</th>
<th>Type: Int32</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>mySts.numC = 1;</td>
</tr>
</tbody>
</table>
**STS_add**

*Update statistics using the provided value*

**C Interface**

**Syntax**

```c
STS_add(sts, value);
```

**Parameters**

- `STS_Handle sts; /* statistics object handle */`
- `LgInt value; /* new value to update statistics object */`

**Return Value**

- `Void`

**Reentrant**

- `no`

**Description**

`STS_add` updates a custom STS object's Total, Count, and Max fields using the data value you provide.

For example, suppose your program passes 32-bit amplitude values to `STS_add`. The Count field tracks how many times your program calls `STS_add` for this STS object. The Total field tracks the total of all the amplitudes. The Max field holds the largest value passed to this point. The Statistics View analysis tool calculates the average amplitude.

You can count the occurrences of an event by passing a dummy value (such as 0) to `STS_add` and watching the Count field.

You can view the statistics values with the Statistics View analysis tool by enabling statistics in the DSP/BIOS→RTA Control Panel window and choosing your custom STS object in the DSP/BIOS→Statistics View window.

**See Also**

- `_STS_delta`
- `STS_reset`
- `STS_set`
- `TRC_disable`
- `TRC_enable`
**STS_delta**  
*Update statistics using difference between provided value & setpoint*

**C Interface**

**Syntax**

```c
STS_delta(sts,value);
```

**Parameters**

- `STH_Handle sts;` /* statistics object handle */
- `LgInt value;` /* new value to update statistics object */

**Return Value**

Void

**Reentrant**

no

**Description**

Each STS object contains a previous value that can be initialized with Tconf or with a call to STS_set. A call to STS_delta subtracts the previous value from the value it is passed and then invokes STS_add with the result to update the statistics. STS_delta also updates the previous value with the value it is passed.

STS_delta can be used in conjunction with STS_set to monitor the difference between a variable and a desired value or to benchmark program performance. You can benchmark code by using paired calls to STS_set and STS_delta that pass the value provided by CLK_gethtime.

```c
STS_set(&sts, CLK_gethtime());
   "processing to be benchmarked"
STS_delta(&sts, CLK_gethtime());
```

**Constraints and Calling Context**

- Before the first call to STS_delta is made, the previous value of the STS object should be initialized either with a call to STS_set or by setting the prev property of the STS object using Tconf.

**Example**

```c
STS_set(&sts, targetValue);
   "processing"
STS_delta(&sts, currentValue);
   "processing"
STS_delta(&sts, currentValue);
```

**See Also**

- STS_add
- STS_reset
- STS_set
- CLK_gethtime
- CLK_getltime
- PRD_getticks
- TRC_disable
- TRC_enable
**STS_reset**  
Reset the values stored in an STS object

### C Interface

**Syntax**

```c
STS_reset(sts);
```

**Parameters**

- `STS_Handle sts; /* statistics object handle */`

**Return Value**

`Void`

**Reentrant**

`no`

**Description**

STS_reset resets the values stored in an STS object. The Count and Total fields are set to 0 and the Max field is set to the largest negative number. STS_reset does not modify the value set by STS_set.

After the Statistics View analysis tool polls statistics data on the target, it performs STS_reset internally. This keeps the 32-bit total and count values from wrapping back to 0 on the target. The host accumulates these values as 64-bit numbers to allow a much larger range than can be stored on the target.

**Example**

```c
STS_reset(&sts);
STS_set(&sts, value);
```

**See Also**

- `STS_add`
- `STS_delta`
- `STS_set`
- `TRC_disable`
- `TRC_enable`
**STS_set**  
*Save a value for STS_delta*

**C Interface**

**Syntax**

```c
STS_set(sts, value);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>STS_Handle</td>
<td>/* statistics object handle */</td>
</tr>
<tr>
<td>LgInt value</td>
<td>/* new value to update statistics object */</td>
</tr>
</tbody>
</table>

**Return Value**

*Void*

**Reentrant**

*no*

**Description**

STS_set can be used in conjunction with STS_delta to monitor the difference between a variable and a desired value or to benchmark program performance. STS_set saves a value as the previous value in an STS object. STS_delta subtracts this saved value from the value it is passed and invokes STS_add with the result.

STS_delta also updates the previous value with the value it was passed. Depending on what you are measuring, you can need to use STS_set to reset the previous value before the next call to STS_delta.

You can also set a previous value for an STS object in the configuration. STS_set changes this value.

See STS_delta for details on how to use the value you set with STS_set.

**Example**

This example gathers performance information for the processing between STS_set and STS_delta.

```c
STS_set(&sts, CLK_getltime());
   "processing to be benchmarked"
STS_delta(&sts, CLK_getltime());
```

This example gathers information about a value’s deviation from the desired value.

```c
STS_set(&sts, targetValue);
   "processing"
STS_delta(&sts, currentValue);
   "processing"
STS_delta(&sts, currentValue);
   "processing"
STS_delta(&sts, currentValue);
```

This example gathers information about a value’s difference from a base value.

```c
STS_set(&sts, baseValue);
   "processing"
STS_delta(&sts, currentValue);
STS_set(&sts, baseValue);
   "processing"
STS_delta(&sts, currentValue);
STS_set(&sts, baseValue);
```
See Also

- STS_add
- STS_delta
- STS_reset
- TRC_disable
- TRC_enable
2.26 SWI Module

The SWI module is the software interrupt manager.

Functions

- SWI_andn. Clear bits from SWI's mailbox; post if becomes 0.
- SWI_andnHook. Specialized version of SWI_andn for use as hook function for configured DSP/BIOS objects. Both its arguments are of type (Arg).
- SWI_create. Create a software interrupt.
- SWI_dec. Decrement SWI's mailbox value; post if becomes 0.
- SWI_delete. Delete a software interrupt.
- SWI_disable. Disable software interrupts.
- SWI_enable. Enable software interrupts.
- SWI_getattrs. Get attributes of a software interrupt.
- SWI_getmbox. Return the mailbox value of the SWI when it started running.
- SWI_getpri. Return a SWI's priority mask.
- SWI_inc. Increment SWI's mailbox value and post the SWI.
- SWI_isSWI. Check current thread calling context.
- SWI_or. Or mask with value contained in SWI's mailbox and post the SWI.
- SWI_orHook. Specialized version of SWI_or for use as hook function for configured DSP/BIOS objects. Both its arguments are of type (Arg).
- SWI_post. Post a software interrupt.
- SWI_raisepri. Raise a SWI's priority.
- SWI_restorepri. Restore a SWI's priority.
- SWI_self. Return address of currently executing SWI object.
- SWI_setattrs. Set attributes of a software interrupt.

Constants, Types, and Structures

typedef struct SWI_Obj SWI_Handle;

SWI_MINPRI  = 1;  /* Minimum execution priority */
SWI_MAXPRI  = 14   /* Maximum execution priority */

struct SWI_Attrs {    /* SWI attributes */
  SWI_Fxn  fxn;      /* address of SWI function */
  Arg      arg0;     /* first arg to function */
  Arg      arg1;     /* second arg to function */
  Int      priority; /* Priority of SWI object */
  Uns      mailbox;  /* check for SWI posting */
};
SWI_Attrs SWI_ATTRS = { /* Default attribute values */
    (SWI_Fxn)FXN_F_nop,    /* SWI function */
    0,                      /* arg0 */
    0,                      /* arg1 */
    1,                      /* priority */
    0                       /* mailbox */
};

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the SWI Manager Properties and SWI Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>fxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>priority</td>
<td>EnumInt</td>
<td>1 (0 to 14)</td>
</tr>
<tr>
<td>mailbox</td>
<td>Int16</td>
<td>0</td>
</tr>
<tr>
<td>arg0</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>arg1</td>
<td>Arg</td>
<td>0</td>
</tr>
</tbody>
</table>

Description

The SWI module manages software interrupt service routines, which are patterned after HWI hardware interrupt service routines.

DSP/BIOS manages four distinct levels of execution threads: hardware interrupt service routines, software interrupt routines, tasks, and background idle functions. A software interrupt is an object that encapsulates a function to be executed and a priority. Software interrupts are prioritized, preempt tasks, and are preempted by hardware interrupt service routines.

Note: SWI functions are called after the processor register state has been saved. SWI functions can be written in C or assembly and must follow the C calling conventions described in the compiler manual.

Note: RTS Functions Callable from TSK Threads Only. Many runtime support (RTS) functions use lock and unlock functions to prevent reentrancy. However, DSP/BIOS SWI and HWI threads cannot call LCK_pend and LCK_post. As a result, RTS functions that call LCK_pend or LCK_post must not be called in the context of a SWI or HWI thread. For a list of RTS functions that should not be called from a SWI or an HWI function, see "LCK_pend" on page 181.
The C++ new operator calls malloc, which in turn calls LCK_pend. As a result, the new operator cannot be used in the context of a SWI or HWI thread.

Each software interrupt has a priority level. A software interrupt preempts any lower-priority software interrupt currently executing.

A target program uses an API call to post a SWI object. This causes the SWI module to schedule execution of the software interrupt's function. When a SWI is posted by an API call, the SWI object's function is not executed immediately. Instead, the function is scheduled for execution. DSP/BIOS uses the SWI's priority to determine whether to preempt the thread currently running. Note that if a SWI is posted several times before it begins running, (because HWIs and higher priority interrupts are running,) when the SWI does eventually run, it will run only one time.

Software interrupts can be posted for execution with a call to SWI_post or a number of other SWI functions. Each SWI object has a 16-bit mailbox which is used either to determine whether to post the SWI or as a value that can be evaluated within the SWI's function. SWI_andn and SWI_dec post the SWI if the mailbox value transitions to 0. SWI_or and SWI_inc also modify the mailbox value. (SWI_or sets bits, and SWI_andn clears bits.)

<table>
<thead>
<tr>
<th></th>
<th>Treat mailbox as bitmask</th>
<th>Treat mailbox as counter</th>
<th>Does not modify mailbox</th>
</tr>
</thead>
<tbody>
<tr>
<td>Always post</td>
<td>SWI_or</td>
<td>SWI_inc</td>
<td>SWI_post</td>
</tr>
<tr>
<td>Post if becomes 0</td>
<td>SWI_andn</td>
<td>SWI_dec</td>
<td></td>
</tr>
</tbody>
</table>

The SWI_disable and SWI_enable operations allow you to post several SWIs and enable them all for execution at the same time. The SWI priorities then determine which SWI runs first.

All SWIs run to completion; you cannot suspend a SWI while it waits for something (for example, a device) to be ready. So, you can use the mailbox to tell the SWI when all the devices and other conditions it relies on are ready. Within a SWI function, a call to SWI_getmbox returns the value of the mailbox when the SWI started running. Note that the mailbox is automatically reset to its original value when a SWI runs; however, SWI_getmbox will return the saved mailbox value from when the SWI started execution.

Software interrupts can have up to 15 priority levels. The highest level is SWI_MAXPRI (14). The lowest is SWI_MINPRI (0). The priority level of 0 is reserved for the KNL_swili object, which runs the task (TSK) scheduler.

A SWI preempts any currently running SWI with a lower priority. If two SWIs with the same priority level have been posted, the SWI that was posted first runs first. HWIs in turn preempt any currently running SWI, allowing the target to respond quickly to hardware peripherals.

Interrupt threads (including HWIs and SWIs) are all executed using the same stack. A context switch is performed when a new thread is added to the top of the stack. The SWI module automatically saves the processor's registers before running a higher-priority SWI that preempts a lower-priority SWI. After the higher-priority SWI finishes running, the registers are restored and the lower-priority SWI can run if no other higher-priority SWI has been posted. (A separate task stack is used by each task thread.)

See the Code Composer Studio online tutorial for more information on how to post SWIs and scheduling issues for the Software Interrupt manager.
SWI Manager Properties

The following global property can be set for the SWI module in the SWI Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Object Memory.** The memory segment that contains the SWI objects.
  
  *Tconf Name:* OBJMEMSEG  
  *Type:* Reference  
  *Example:*  
  ```
  bios.SWI.OBJMEMSEG = prog.get("myMEM");
  ```

SWI Object Properties

To create a SWI object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```javascript
var mySwi = bios.SWI.create("mySwi");
```

If you cannot create a new SWI object (an error occurs or the Insert SWI item is inactive in the DSP/BIOS Configuration Tool), try increasing the Stack Size property in the MEM Manager Properties before adding a SWI object or a SWI priority level.

The following properties can be set for a SWI object in the SWI Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **comment.** Type a comment to identify this SWI object.
  
  *Tconf Name:* comment  
  *Type:* String  
  *Example:*  
  ```
  mySwi.comment = "my SWI";
  ```

- **function.** The function to execute. If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. (The DSP/BIOS Configuration Tool generates assembly code, which must use leading underscores when referencing C functions or labels.) If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally.
  
  *Tconf Name:* fxn  
  *Type:* Extern  
  *Example:*  
  ```
  mySwi.fxn = prog.extern("swiFxn");
  ```

- **priority.** This property shows the numeric priority level for this SWI object. SWIs can have up to 15 priority levels. The highest level is SWI_MAXPRI (14). The lowest is SWI_MINPRI (0). The priority level of 0 is reserved for the KNL_swi object, which runs the task scheduler. Instead of typing a number in the DSP/BIOS Configuration Tool, you change the relative priority levels of SWI objects by dragging the objects in the ordered collection view.
  
  *Tconf Name:* priority  
  *Type:* EnumInt  
  *Options:* 0 to 14  
  *Example:*  
  ```
  mySwi.priority = 1;
  ```

- **mailbox.** The initial value of the 16-bit word used to determine if this SWI should be posted.
  
  *Tconf Name:* mailbox  
  *Type:* Int16  
  *Example:*  
  ```
  mySwi.mailbox = 7;
  ```

- **arg0, arg1.** Two arbitrary pointer type (Arg) arguments to the above configured user function.
  
  *Tconf Name:* arg0  
  *Type:* Arg  
  *Tconf Name:* arg1  
  *Type:* Arg  
  *Example:*  
  ```
  mySwi.arg0 = 0;
  ```
**SWI_andn**  
*Clear bits from SWI’s mailbox and post if mailbox becomes 0*

**C Interface**

**Syntax**
```c
SWI_andn(swi, mask);
```

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>SWI_Handle</td>
<td>swi;</td>
<td>/* SWI object handle*/</td>
</tr>
<tr>
<td>Uns</td>
<td>mask</td>
<td>/* inverse value to be ANDed */</td>
</tr>
</tbody>
</table>

**Return Value**

Void

**Reentrant**

yes

**Description**

SWI_andn is used to conditionally post a software interrupt. SWI_andn clears the bits specified by a mask from SWI’s internal mailbox. If SWI’s mailbox becomes 0, SWI_andn posts the SWI. The bitwise logical operation performed is:

```
mailbox = mailbox AND (NOT MASK)
```

For example, if multiple conditions that all be met before a SWI can run, you should use a different bit in the mailbox for each condition. When a condition is met, clear the bit for that condition.

SWI_andn results in a context switch if the SWI’s mailbox becomes zero and the SWI has higher priority than the currently executing thread.

You specify a SWI’s initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes.

**Note:** Use the specialized version, SWI_andnHook, when SWI_andn functionality is required for a DSP/BIOS object hook function.
The following figure shows an example of how a mailbox with an initial value of 3 can be cleared by two calls to SWI_andn with values of 2 and 1. The entire mailbox could also be cleared with a single call to SWI_andn with a value of 3.

Constraints and Calling Context

- If this function is invoked outside the context of an HWI, interrupts must be enabled.
- When called within an HWI, the code sequence calling SWI_andn must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.

Example

```c
/* ======== ioReady ======== */

Void ioReady(unsigned int mask)
{
    /* clear bits of "ready mask" */
    SWI_andn(&copySWI, mask);
}
```

See Also

SWI_andnHook
SWI_dec
SWI_getmbox
SWI_inc
SWI_or
SWI_orHook
SWI_post
SWI_self
### SWI\_andnHook

**Clear bits from SWI’s mailbox and post if mailbox becomes 0**

#### C Interface

**Syntax**

```c
SWI\_andnHook(swi, mask);
```

**Parameters**

- `Arg swi; /* SWI object handle*/`
- `Arg mask /* value to be ANDed */`

**Return Value**

Void

**Reentrant**

yes

#### Description

SWI\_andnHook is a specialized version of SWI\_andn for use as hook function for configured DSP/BIOS objects. SWI\_andnHook clears the bits specified by a mask from SWI’s internal mailbox and also moves the arguments to the correct registers for proper interface with low level DSP/BIOS assembly code. If SWI’s mailbox becomes 0, SWI\_andnHook posts the SWI. The bitwise logical operation performed is:

```
mailbox = mailbox AND (NOT MASK)
```

For example, if there are multiple conditions that must all be met before a SWI can run, you should use a different bit in the mailbox for each condition. When a condition is met, clear the bit for that condition.

SWI\_andnHook results in a context switch if the SWI’s mailbox becomes zero and the SWI has higher priority than the currently executing thread.

You specify a SWI’s initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes.

#### Constraints and Calling Context

- If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- When called within an HWI, the code sequence calling SWI\_andnHook must be either wrapped within an HWI\_enter/HWI\_exit pair or invoked by the HWI dispatcher.

#### Example

```c
/* ======== ioReady ======== */

Void ioReady(unsigned int mask)
{
    /* clear bits of "ready mask" */
    SWI\_andnHook(&copySWI, mask);
}
```

#### See Also

- SWI\_andn
- SWI\_orHook
**SWI_create**

Create a software interrupt

**C Interface**

Syntax

```c
swi = SWI_create(attrs);
```

Parameters

- `SWI_Attrs *attrs; /* pointer to swi attributes */`

Return Value

- `SWI_Handle swi; /* handle for new swi object */`

**Description**

`SWI_create` creates a new SWI object. If successful, `SWI_create` returns the handle of the new SWI object. If unsuccessful, `SWI_create` returns NULL unless it aborts. For example, `SWI_create` can abort if it directly or indirectly calls `SYS_error`, and `SYS_error` is configured to abort.

The `attrs` parameter, which can be either NULL or a pointer to a structure that contains attributes for the object to be created, facilitates setting the SWI object’s attributes. The SWI object’s attributes are specified through a structure of type `SWI_Attrs` defined as follows:

```c
struct SWI_Attrs {
    SWI_Fxn  fxn;
    Arg      arg0;
    Arg      arg1;
    Int      priority;
    Uns      mailbox;
};
```

If `attrs` is NULL, the new SWI object is assigned the following default attributes.

```c
SWI_Attrs SWI_ATTRS = { /* Default attribute values */
    (SWI_Fxn)FXN_F_nop,     /* SWI function */
    0,                        /* arg0 */
    0,                        /* arg1 */
    1,                        /* priority */
    0                         /* mailbox */
};
```

The `fxn` attribute, which is the address of the SWI function, serves as the entry point of the software interrupt service routine.

The `arg0` and `arg1` attributes specify the arguments passed to the SWI function, `fxn`.

The `priority` attribute specifies the SWI object’s execution priority and must range from 0 to 14. The highest level is `SWI_MAXPRI` (14). The lowest is `SWI_MINPRI` (0). The priority level of 0 is reserved for the `KNL_swi` object, which runs the task scheduler.

The `mailbox` attribute is used either to determine whether to post the SWI or as a value that can be evaluated within the SWI function.

All default attribute values are contained in the constant `SWI_ATTRS`, which can be assigned to a variable of type `SWI_Attrs` prior to calling `SWI_create`. 
SWI_create calls MEM_alloc to dynamically create the object's data structure. MEM_alloc must acquire a lock to the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2–204.

Constraints and Calling Context

- SWI_create cannot be called from a SWI or HWI.
- The fxn attribute cannot be NULL.
- The priority attribute must be less than or equal to 14 and greater than or equal to 1.

See Also

SWI_delete
SWI_getattrs
SWI_setattrs
SYS_error
SWI_dec

Decrement SWI’s mailbox value and post if mailbox becomes 0

C Interface

Syntax

SWI_dec(swi);

Parameters

SWI_Handle swi; /* SWI object handle*/

Return Value

Void

Reentrant

yes

Description

SWI_dec is used to conditionally post a software interrupt. SWI_dec decrements the value in SWI’s mailbox by 1. If SWI’s mailbox value becomes 0, SWI_dec posts the SWI. You can increment a mailbox value by using SWI_inc, which always posts the SWI.

For example, you would use SWI_dec if you wanted to post a SWI after a number of occurrences of an event.

You specify a SWI’s initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes.

SWI_dec results in a context switch if the SWI’s mailbox becomes zero and the SWI has higher priority than the currently executing thread.

Constraints and Calling Context

• If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
• When called within an HWI, the code sequence calling SWI_dec must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.

Example

/* ======== strikeOrBall ======== */

Void strikeOrBall(unsigned int call)
{
    if (call == 1) {
        /* initial mailbox value is 3 */
        SWI_dec(&strikeoutSwi);
    }
    if (call == 2) {
        /* initial mailbox value is 4 */
        SWI_dec(&walkSwi);
    }
}

See Also

SWI_inc
**SWI_delete**  
*Delete a software interrupt*

### C Interface

**Syntax**

```c
SWI_delete(swi);
```

**Parameters**

- `SWI_Handle swi; /* SWI object handle */`

**Return Value**

`Void`

**Description**

SWI_delete uses MEM_free to free the SWI object referenced by `swi`.

SWI_delete calls MEM_free to delete the SWI object. MEM_free must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Constraints and Calling Context**

- `swi` cannot be the currently executing SWI object (`SWI_self`)
- SWI_delete cannot be called from a SWI or HWI.
- SWI_delete must not be used to delete a statically-created SWI object. No check is performed to prevent SWI_delete from being used on a statically-created object. If a program attempts to delete a SWI object that was created using `Tconf`, `SYS_error` is called.

**See Also**

- SWI_create
- SWI_getattrs
- SWI_setattrs
- SYS_error
**SWI_disable**  *Disable software interrupts*

**C Interface**

**Syntax**

```c
SWI_disable();
```

**Parameters**

Void

**Return Value**

Void

**Reentrant**

yes

**Description**

SWI_disable and SWI_enable control software interrupt processing. SWI_disable disables all other SWI functions from running until SWI_enable is called. Hardware interrupts can still run.

SWI_disable and SWI_enable let you ensure that statements that must be performed together during critical processing are not interrupted. In the following example, the critical section is not preempted by any SWIs.

```c
SWI_disable();
`critical section`
SWI_enable();
```

You can also use SWI_disable and SWI_enable to post several SWIs and have them performed in priority order. See the following example.

SWI_disable calls can be nested. The number of nesting levels is stored internally. SWI handling is not reenabled until SWI_enable has been called as many times as SWI_disable.

**Constraints and Calling Context**

- The calls to HWI_enter and HWI_exit required in any HWIs that schedule SWIs automatically disable and reenable SWI handling. You should not call SWI_disable or SWI_enable within a HWI.
- SWI_disable cannot be called from the program’s main() function.
- Do not call SWI_enable when SWIs are already enabled. If you do, a subsequent call to SWI_disable does not disable SWI processing.

**Example**

```c
/* ======== postEm ======== */
Void postEm
{
    SWI_disable();
    SWI_post(&encoderSwi);
    SWI_andn(&copySwi, mask);
    SWI_dec(&strikeoutSwi);
    SWI_enable();
}
```

**See Also**

HWI_disable

SWI_enable
**SWI_enable**  
*Enable software interrupts*

**C Interface**

**Syntax**

```c
SWI_enable();
```

**Parameters**

`Void`

**Return Value**

`Void`

**Reentrant**

`yes`

**Description**

SWI_disable and SWI_enable control software interrupt processing. SWI_disable disables all other SWI functions from running until SWI_enable is called. Hardware interrupts can still run. See the SWI_disable section for details.

SWI_disable calls can be nested. The number of nesting levels is stored internally. SWI handling is not be reenabled until SWI_enable has been called as many times as SWI_disable.

SWI_enable results in a context switch if a higher-priority SWI is ready to run.

**Constraints and Calling Context**

- The calls to HWI_enter and HWI_exit are required in any HWI that schedules SWIs. They automatically disable and reenable SWI handling. You should not call SWI_disable or SWI_enable within a HWI.

- SWI_enable cannot be called from the program's main() function.

- Do not call SWI_enable when SWIs are already enabled. If you do so, the subsequent call to SWI_disable will not disable SWI processing.

**See Also**

- HWI_disable
- HWI_enable
- SWI_disable
**SWI_getattrs**  
*Get attributes of a software interrupt*

**C Interface**

**Syntax**

```c
SWI_getattrs(swi, attrs);
```

**Parameters**

- `SWI_Handle swi; /* handle of the swi */`
- `SWI_Attrs *attrs; /* pointer to swi attributes */`

**Return Value**

`Void`

**Description**

`SWI_getattrs` retrieves attributes of an existing SWI object.

The `swi` parameter specifies the address of the SWI object whose attributes are to be retrieved. The `attrs` parameter, which is the pointer to a structure that contains the retrieved attributes for the SWI object, facilitates retrieval of the attributes of the SWI object.

The SWI object’s attributes are specified through a structure of type `SWI_Attrs` defined as follows:

```c
struct SWI_Attrs {
    SWI_Fxn   fxn;
    Arg       arg0;
    Arg       arg1;
    Int       priority;
    Uns       mailbox;
};
```

The `fxn` attribute, which is the address of the SWI function, serves as the entry point of the software interrupt service routine.

The `arg0` and `arg1` attributes specify the arguments passed to the SWI function, `fxn`.

The priority attribute specifies the SWI object’s execution priority and ranges from 0 to 14. The highest level is `SWI_MAXPRI` (14). The lowest is `SWI_MINPRI` (0). The priority level of 0 is reserved for the `KNL_swi` object, which runs the task scheduler.

The mailbox attribute is used either to determine whether to post the SWI or as a value that can be evaluated within the SWI function.

The following example uses `SWI_getattrs`:

```c
extern  SWI_Handle swi;
SWI_Attrs attrs;

SWI_getattrs(swi, &attrs);
attrs.priority = 5;
SWI_setattrs(swi, &attrs);
```
Constraints and Calling Context

- SWI_getattrs cannot be called from a SWI or HWI.
- The attrs parameter cannot be NULL.

See Also

- SWI_create
- SWI_delete
- SWI_setattrs
SWI_getmbox  

Return a SWI’s mailbox value

C Interface

Syntax

```c
num = Uns SWI_getmbox();
```

Parameters

```c
Void
```

Return Value

```c
Uns num /* mailbox value */
```

Reentrant

```c
yes
```

Description

SWI_getmbox returns the value that SWI’s mailbox had when the SWI started running. DSP/BIOS saves the mailbox value internally so that SWI_getmbox can access it at any point within a SWI object’s function. DSP/BIOS then automatically resets the mailbox to its initial value (defined with Tconf) so that other threads can continue to use the SWI’s mailbox.

SWI_getmbox should only be called within a function run by a SWI object.

When called from with the context of a SWI, the value returned by SWI_getmbox is zero if the SWI was posted by a call to SWI_andn, SWI_andnHook, or SWI_dec. Therefore, SWI_getmbox provides relevant information only if the SWI was posted by a call to SWI_inc, SWI_or, SWI_orHook, or SWI_post.

Constraints and Calling Context

- SWI_getmbox cannot be called from the context of an HWI or TSK.
- SWI_getmbox cannot be called from a program's main() function.

Example

This call could be used within a SWI object’s function to use the mailbox value within the function. For example, if you use SWI_or or SWI_inc to post a SWI, different mailbox values can require different processing.

```c
swicount = SWI_getmbox();
```

See Also

SWI_andn
SWI_andnHook
SWI_dec
SWI_inc
SWI_or
SWI_orHook
SWI_post
SWI_self
**SWI_getpri**  
*Return a SWI's priority mask*

**C Interface**

Syntax
```
key = SWI_getpri(swi);
```

Parameters
- `SWI_Handle swi; /* SWI object handle*/`

Return Value
- `Uns key /* Priority mask of swi */`

Reentrant
  yes

Description
SWI_getpri returns the priority mask of the SWI passed in as the argument.

Example
```
/* Get the priority key of swi1 */
key = SWI_getpri(&swi1);

/* Get the priorities of swi1 and swi3 */
key = SWI_getpri(&swi1) | SWI_getpri(&swi3);
```

See Also
- SWI_raisepri
- SWI_restorepri
**SWI_inc**  
*Increment SWI's mailbox value and post the SWI*

**C Interface**

**Syntax**
```
SWI_inc(swi);
```

**Parameters**
- **SWI_Handle** `swi;` /* SWI object handle*/

**Return Value**
`Void`

**Reentrant**
`no`

**Description**
SWI_inc increments the value in SWI's mailbox by 1 and posts the SWI regardless of the resulting mailbox value. You can decrement a mailbox value using SWI_dec, which only posts the SWI if the mailbox value is 0.

If a SWI is posted several times before it has a chance to begin executing, because HWIs and higher priority SWIs are running, the SWI only runs one time. If this situation occurs, you can use SWI_inc to post the SWI. Within the SWI's function, you could then use SWI_getmbox to find out how many times this SWI has been posted since the last time it was executed.

You specify a SWI's initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes. To get the mailbox value, use SWI_getmbox.

SWI_inc results in a context switch if the SWI is higher priority than the currently executing thread.

**Constraints and Calling Context**
- If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- When called within an HWI, the code sequence calling SWI_inc must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.

**Example**
```
extern SWI_ObjMySwi;
/* ======== AddAndProcess ======== */
Void AddAndProcess(int count)
{
    int i;
    for (i = 1; I <= count; ++i)
        SWI_inc(&MySwi);
}
```

**See Also**
- SWI_dec
- SWI_getmbox
SWI_isSWI

Check to see if called in the context of a SWI

C Interface

Syntax

result = SWI_isSWI(Void);

Parameters

Void

Return Value

Bool result; /* TRUE if in SWI context, FALSE otherwise */

Reentrant

yes

Description

This macro returns TRUE when it is called within the context of a SWI or PRD function. This applies no matter whether the SWI was posted by an HWI, TSK, or IDL thread. This macro returns FALSE in all other contexts.

In previous versions of DSP/BIOS, calling SWI_isSWI() from a task switch hook resulted in TRUE. This is no longer the case; task switch hooks are identified as part of the TSK context.

See Also

HWI_isHWI
TSK_isTSK
### SWI_or

**OR mask with the value contained in SWI’s mailbox field**

**C Interface**

**Syntax**

```c
SWI_or(swi, mask);
```

**Parameters**

- `SWI_Handle swi; /* SWI object handle*/`
- `Uns mask; /* value to be ORed */`

**Return Value**

`Void`

**Reentrant**

`no`

**Description**

`SWI_or` is used to post a software interrupt. `SWI_or` sets the bits specified by a mask in SWI's mailbox. `SWI_or` posts the SWI regardless of the resulting mailbox value. The bitwise logical operation performed on the mailbox value is:

```
mailbox = mailbox OR mask
```

You specify a SWI's initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes. To get the mailbox value, use `SWI_getmbox`.

For example, you might use `SWI_or` to post a SWI if any of three events should cause a SWI to be executed, but you want the SWI's function to be able to tell which event occurred. Each event would correspond to a different bit in the mailbox.

`SWI_or` results in a context switch if the SWI is higher priority than the currently executing thread.

**Note:**

Use the specialized version, `SWI_orHook`, when `SWI_or` functionality is required for a DSP/BIOS object hook function.

**Constraints and Calling Context**

- If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- When called within an HWI, the code sequence calling `SWI_or` must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.

**See Also**

- `SWI_andn`
- `SWI_orHook`
SWI_orHook

OR mask with the value contained in SWI’s mailbox field

C Interface

Syntax

    SWI_orHook(swi, mask);

Parameters

Arg swi;  /* SWI object handle*/
Arg mask;  /* value to be ORed */

Return Value

Void

Reentrant

no

Description

SWI_orHook is used to post a software interrupt, and should be used when hook functionality is required for DSP/BIOS hook objects. SWI_orHook sets the bits specified by a mask in SWI’s mailbox and also moves the arguments to the correct registers for interfacing with low level DSP/BIOS assembly code. SWI_orHook posts the SWI regardless of the resulting mailbox value. The bitwise logical operation performed on the mailbox value is:

    mailbox = mailbox OR mask

You specify a SWI’s initial mailbox value in the configuration. The mailbox value is automatically reset when the SWI executes. To get the mailbox value, use SWI_getmbox.

For example, you might use SWI_orHook to post a SWI if any of three events should cause a SWI to be executed, but you want the SWI’s function to be able to tell which event occurred. Each event would correspond to a different bit in the mailbox.

SWI_orHook results in a context switch if the SWI is higher priority than the currently executing thread.

Note:

Use the specialized version, SWI_orHook, when SWI_or functionality is required for a DSP/BIOS object hook function.

Constraints and Calling Context

- If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- When called within an HWI, the code sequence calling SWI_orHook must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.

See Also

SWI_andnHook
SWI_or
**SWI_post**  
*Post a software interrupt*

**C Interface**

**Syntax**

```c
SWI_post(swi);
```

**Parameters**

- `SWI_Handle swi; /* SWI object handle*/`

**Return Value**

- `Void`

**Reentrant**

- `yes`

**Description**

`SWI_post` is used to post a software interrupt regardless of the mailbox value. No change is made to the SWI object's mailbox value.

To have a PRD object post a SWI object's function, you can set `_SWI_post` as the function property of a PRD object and the name of the SWI object you want to post its function as the arg0 property.

`SWI_post` results in a context switch if the SWI is higher priority than the currently executing thread.

**Constraints and Calling Context**

- If this macro (API) is invoked outside the context of an HWI, interrupts must be enabled.
- When called within an HWI, the code sequence calling `SWI_post` must be either wrapped within an `HWI_enter/HWI_exit` pair or invoked by the HWI dispatcher.

**See Also**

- `SWI_andn`
- `SWI_dec`
- `SWI_getmbox`
- `SWI_inc`
- `SWI_or`
- `SWI_self`
SWI_raisepri Raise a SWI’s priority

C Interface

Syntax

```c
key = SWI_raisepri(mask);
```

Parameters

```c
Uns mask; /* mask of desired priority level */
```

Return Value

```c
Uns key; /* key for use with SWI_restorepri */
```

Reentrant

yes

Description

SWI_raisepri is used to raise the priority of the currently running SWI to the priority mask passed in as the argument. SWI_raisepri can be used in conjunction with SWI_restorepri to provide a mutual exclusion mechanism without disabling SWIs.

SWI_raisepri should be called before a shared resource is accessed, and SWI_restorepri should be called after the access to the shared resource.

A call to SWI_raisepri not followed by a SWI_restorepri keeps the SWI’s priority for the rest of the processing at the raised level. A SWI_post of the SWI posts the SWI at its original priority level.

A SWI object’s execution priority must range from 0 to 14. The highest level is SWI_MAXPRI (14). The lowest is SWI_MINPRI (0). Priority zero (0) is reserved for the KNL_swi object, which runs the task scheduler.

SWI_raisepri never lowers the current SWI priority.

Constraints and Calling Context

- SWI_raisepri cannot be called from an HWI or TSK level.

Example

```c
/* raise priority to the priority of swi_1 */
key = SWI_raisepri(SWI_getpri(&swi_1));
--- access shared resource ---
SWI_restore(key);
```

See Also

SWI_getpri
SWI_restorepri
SWI_restorepri  

**Restore a SWI’s priority**

C Interface

**Syntax**

```
SWI_restorepri(key);
```

**Parameters**

- **Uns** `key`; /* key to restore original priority level */

**Return Value**

Void

**Reentrant**

yes

**Description**

SWI_restorepri restores the priority to the SWI’s priority prior to the SWI_raisepri call returning the key. SWI_restorepri can be used in conjunction with SWI_raisepri to provide a mutual exclusion mechanism without disabling all SWIs.

SWI_raisepri should be called right before the shared resource is referenced, and SWI_restorepri should be called after the reference to the shared resource.

**Constraints and Calling Context**

- SWI_restorepri cannot be called from an HWI or TSK level.
- SWI_restorepri must be called with interrupts (HWI and SWI) enabled.
- SWI_restorepri cannot be called from the program’s main() function.

**Example**

```c
/* raise priority to the priority of swi_1 */
key = SWI_raisepri(SWI_getpri(&swi_1));
--- access shared resource ---
SWI_restore(key);
```

**See Also**

- SWI_getpri
- SWI_raisepri
**SWI_self**  
*Return address of currently executing SWI object*

### C Interface

#### Syntax

```c
SWI_Handle curswi = SWI_self();
```

#### Parameters

- **Void**

#### Return Value

- **SWI_Handle** `swi;` /* handle for current swi object */

#### Reentrant

**yes**

#### Description

`SWI_self` returns the address of the currently executing SWI.

#### Constraints and Calling Context

- `SWI_self` cannot be called from an HWI or TSK level.
- `SWI_self` cannot be called from the program’s main() function.

#### Example

You can use `SWI_self` if you want a SWI to repost itself:

```c
SWI_post(SWI_self());
```

#### See Also

- `SWI_andn`
- `SWI_getmbox`
- `SWI_post`
**SWI_setattrs**  
*Set attributes of a software interrupt*

**C Interface**

**Syntax**

```c
SWI_setattrs(swi, attrs);
```

**Parameters**

- **SWI_Handle** swi; /* handle of the swi */
- **SWI_Attrs** *attrs; /* pointer to swi attributes */

**Return Value**

Void

**Description**

*SWI_setattrs* sets attributes of an existing SWI object.

The *swi* parameter specifies the address of the SWI object whose attributes are to be set.

The *attrs* parameter, which can be either NULL or a pointer to a structure that contains attributes for the SWI object, facilitates setting the attributes of the SWI object. If *attrs* is NULL, the new SWI object is assigned a default set of attributes. Otherwise, the SWI object’s attributes are specified through a structure of type **SWI_Attrs** defined as follows:

```c
define struct SWI_Attrs {
    SWI_Fxn fxn;
    Arg arg0;
    Arg arg1;
    Int priority;
    Uns mailbox;
};
```

The *fxn* attribute, which is the address of the swi function, serves as the entry point of the software interrupt service routine.

The *arg0* and *arg1* attributes specify the arguments passed to the swi function, *fxn*.

The *priority* attribute specifies the SWI object’s execution priority and must range from 1 to 14. Priority 14 is the highest priority. You cannot use a priority of 0; that priority is reserved for the system SWI that runs the TSK scheduler.

The *mailbox* attribute is used either to determine whether to post the SWI or as a value that can be evaluated within the SWI function.

All default attribute values are contained in the constant **SWI_ATTRS**, which can be assigned to a variable of type **SWI_Attrs** prior to calling *SWI_setattrs*.

The following example uses *SWI_setattrs*:

```c
extern SWI_Handle swi;
SWI_Attrs attrs;

SWI_setattrs(swi, &attrs);
attrs.priority = 5;
SWI_setattrs(swi, &attrs);
```
Constraints and Calling Context

- SWI_setattrs must not be used to set the attributes of a SWI that is preempted or is ready to run.
- The fxn attribute cannot be NULL.
- The priority attribute must be less than or equal to 14 and greater than or equal to 1.

See Also

SWI_create
SWI_delete
SWI_getattrs
2.27 SYS Module

The SYS modules manages system settings.

Functions

- SYS_abort. Abort program execution
- SYS_atexit. Stack an exit handler
- SYS_error. Flag error condition
- SYS_exit. Terminate program execution
- SYS_printf. Formatted output
- SYS_putchar. Output a single character
- SYS_sprintf. Formatted output to string buffer
- SYS_vprintf. Formatted output, variable argument list
- SYS_vsprintf. Output formatted data

Constants, Types, and Structures

```c
#define SYS_FOREVER  (Uns)-1 /* wait forever */
#define SYS_POLL     (Uns)0  /* don't wait */
#define SYS_OK         0  /* no error */
#define SYS_EALLOC     1  /* memory alloc error */
#define SYS_EFREE      2  /* memory free error */
#define SYS_ENODEV     3  /* dev driver not found */
#define SYS_EBUSY      4  /* device driver busy */
#define SYS EINVAL     5  /* invalid parameter */
#define SYS EBADIO     6  /* I/O failure */
#define SYS EMODE      7  /* bad mode for driver */
#define SYS EDOMAIN    8  /* domain error */
#define SYS ETIMOUT    9  /* call timed out */
#define SYS_EUSER  256  /* user errors start here */
#define SYS NUMHANDLERS  8 /* # of atexit handlers */

extern String SYS_errors[]; /* error string array */
```

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the SYS Manager Properties heading. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.

Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>TRACESIZE</td>
<td>Numeric</td>
<td>512</td>
</tr>
<tr>
<td>TRACESEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>
Description

The SYS module makes available a set of general-purpose functions that provide basic system services, such as halting program execution and printing formatted text. In general, each SYS function is patterned after a similar function normally found in the standard C library.

SYS does not directly use the services of any other DSP/BIOS module and therefore resides at the bottom of the system. Other DSP/BIOS modules use the services provided by SYS in lieu of similar C library functions. The SYS module provides hooks for binding system-specific code. This allows programs to gain control wherever other DSP/BIOS modules call one of the SYS functions.

SYS Manager Properties

The following global properties can be set for the SYS module in the SYS Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script.

- **Trace Buffer Size.** The size of the buffer that contains system trace information. This system trace buffer can be viewed only by looking for the SYS_PUTCBEG symbol in the CCS Memory view. For example, by default the Putc function writes to the trace buffer.
  
  **Tconf Name:** TRACESIZE  
  **Type:** Numeric  
  **Example:**
  ```
  bios.SYS.TRACESIZE = 512;
  ```

- **Trace Buffer Memory.** The memory segment that contains system trace information.
  
  **Tconf Name:** TRACESEG  
  **Type:** Reference  
  **Example:**
  ```
  bios.SYS.TRACESEG = prog.get("myMEM");
  ```

- **Abort Function.** The function to run if the application aborts by calling SYS_abort. The default function is _UTL_doAbort, which logs an error message and calls _halt. If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally. The prototype for this function should be:
  
  ```
  Void myAbort(String fmt, va_list ap);
  ```

- **Error Function.** The function to run if an error flagged by SYS_error occurs. The default function is _UTL_doError, which logs an error message and returns. The prototype for this function should be:
  
  ```
  Void myError(String s, Int errno, va_list ap);
  ```

- **Exit Function.** The function to run when the application exits by calling SYS_exit. The default function is _UTL_halt, which loops forever with interrupts disabled and prevents other processing. The prototype for this function should be:
  
  ```
  Void myExit(Int status);
  ```

### Table

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>ABORTFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;UTL_doAbort&quot;)</td>
</tr>
<tr>
<td>ERRORFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;UTL_doError&quot;)</td>
</tr>
<tr>
<td>EXITFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;UTL_halt&quot;)</td>
</tr>
<tr>
<td>PUTCFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;UTL_doPutc&quot;)</td>
</tr>
</tbody>
</table>
SYS Module

- **Putc Function.** The function to run if the application calls SYS_putchar, SYS_printf, or SYS_vprintf. The default function is _UTL_doPutc, which writes a character to the system trace buffer. This system trace buffer can be viewed only by looking for the SYS_PUTCBEG symbol in the CCS Memory view. The prototype for this function should be:

```c
Void myPutc(Char c);
```

Tconf Name: PUTCFXN Type: Extern

Example: `bios.SYS.PUTCFXN = prog.extern("myPutc");`

SYS Object Properties

The SYS module does not support the creation of individual SYS objects.


**SYS_abort**  
*Abort program execution*

**C Interface**

Syntax

```c
SYS_abort(format, [arg,] ...);
```

Parameters

- **String** `format;` /* format specification string */
- **Arg** `arg;` /* optional argument */

Return Value

- **Void**

**Description**

SYS_abort aborts program execution by calling the function bound to the configuration parameter Abort function, where `vargs` is of type `va_list` (a void pointer which can be interpreted as an argument list) and represents the sequence of arg parameters originally passed to SYS_abort.


```c
(*(Abort_function))(format, vargs)
```

The function bound to Abort function can elect to pass the format and `vargs` parameters directly to SYS_vprintf or SYS_vsprintf prior to terminating program execution.

The default Abort function for the SYS manager is `_UTL_doAbort`, which logs an error message and calls UTL_halt, which is defined in the boot.c file. The UTL_halt function performs an infinite loop with all processor interrupts disabled.

**Constraints and Calling Context**

- If the function bound to Abort function is not reentrant, SYS_abort must be called atomically.

**See Also**

- SYS_exit
- SYS_printf

---

**FIGURE**

- **A**

**TABLE**

- | Column 1 | Column 2 |
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Data 1</td>
<td>Data 2</td>
</tr>
</tbody>
</table>

---

**FIGURE**

- **B**

**TABLE**

- | Column 1 | Column 2 |
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Data 1</td>
<td>Data 2</td>
</tr>
</tbody>
</table>

---

**FIGURE**

- **C**

**TABLE**

- | Column 1 | Column 2 |
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Data 1</td>
<td>Data 2</td>
</tr>
</tbody>
</table>

---

**FIGURE**

- **D**

**TABLE**

- | Column 1 | Column 2 |
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Data 1</td>
<td>Data 2</td>
</tr>
</tbody>
</table>

---

**FIGURE**

- **E**

**TABLE**

- | Column 1 | Column 2 |
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Data 1</td>
<td>Data 2</td>
</tr>
</tbody>
</table>
**SYS_atexit**  
*Stack an exit handler*

**C Interface**

```c
success = SYS_atexit(handler);
```

**Parameters**

<table>
<thead>
<tr>
<th>Fxn</th>
<th>handler /* exit handler function */</th>
</tr>
</thead>
</table>

**Return Value**

<table>
<thead>
<tr>
<th>Bool</th>
<th>success /* handler successfully stacked */</th>
</tr>
</thead>
</table>

**Description**

SYS_atexit pushes handler onto an internal stack of functions to be executed when SYS_exit is called. Up to SYS_NUMHANDLERS(8) functions can be specified in this manner. SYS_exit pops the internal stack until empty and calls each function as follows, where status is the parameter passed to SYS_exit:

```c
(*handler)(status)
```

SYS_atexit returns TRUE if handler has been successfully stacked; FALSE if the internal stack is full.

The handlers on the stack are called only if either of the following happens:

- SYS_exit is called.
- All tasks for which the Don’t shut down system while this task is still running property is TRUE have exited. (By default, this includes the TSK_idle task, which manages communication between the target and analysis tools.)

**Constraints and Calling Context**

- handler cannot be NULL.
SYS_error

Flag error condition

C Interface

Syntax

    SYS_error(s, errno, [arg], ...);

Parameters

- **String**
  - `s; /* error string */`
- **Int**
  - `errno; /* error code */`
- **Arg**
  - `arg; /* optional argument */`

Return Value

- **Void**

Description

SYS_error is used to flag DSP/BIOS error conditions. Application programs should call SYS_error to handle program errors. Internal functions also call SYS_error.

SYS_error calls a function to handle errors. The default error function for the SYS manager is _UTL_doError, which logs an error message and returns. The default function can be replaced with your own error function by setting the SYS.ERRORFXN configuration property.

The default error function or an alternate configured error function is called as follows, where vargs is of type `va_list` (a void pointer which can be interpreted as an argument list) and represents the sequence of arg parameters originally passed to SYS_error.

    (*(Error_function))(s, errno, vargs)

Constraints and Calling Context

- The only valid error numbers are the error constants defined in sys.h (SYS_E*) or numbers greater than or equal to SYS_EUSER. Passing any other error values to SYS_error can cause DSP/BIOS to crash.
SYS_exit

Terminate program execution

C Interface

Syntax
SYS_exit(status);

Parameters
Int status; /* termination status code */

Return Value
Void

Description
SYS_exit first pops a stack of handlers registered through the function SYS_atexit, and then terminates
program execution by calling the function bound to the configuration parameter Exit function, passing on
its original status parameter.

(*handlerN)(status)
...
(*handler2)(status)
(*handler1)(status)

(*Remaining_function)(status)

The default Exit function for the SYS manager is UTL_halt, which performs an infinite loop with all
processor interrupts disabled.

Constraints and Calling Context

• If the function bound to Exit function or any of the handler functions is not reentrant, SYS_exit must
be called atomically.

See Also
SYS_abort
SYS_atexit
**SYS_printf** *Output formatted data*

**C Interface**

Syntax

```
SYS_printf(format, [arg,] ...);
```

Parameters

- **String format;** /* format specification string */
- **Arg arg;** /* optional argument */

Return Value

Void

**Description**

SYS_printf provides a subset of the capabilities found in the standard C library function printf.

---

**Note:**

SYS_printf and the related functions are code-intensive. If possible, applications should use the LOG Module functions to reduce code size and execution time.

---

Conversion specifications begin with a % and end with a conversion character. The conversion characters recognized by SYS_printf are limited to the characters shown in Table 2-7.

**Table 2-7: Conversion Characters Recognized by SYS_printf**

<table>
<thead>
<tr>
<th>Character</th>
<th>Corresponding Output Format</th>
</tr>
</thead>
<tbody>
<tr>
<td>d</td>
<td>signed decimal integer</td>
</tr>
<tr>
<td>u</td>
<td>unsigned decimal integer</td>
</tr>
<tr>
<td>o</td>
<td>octal integer</td>
</tr>
<tr>
<td>x</td>
<td>hexadecimal integer</td>
</tr>
<tr>
<td>c</td>
<td>single character</td>
</tr>
<tr>
<td>s</td>
<td>NULL-terminated string</td>
</tr>
<tr>
<td>p</td>
<td>data pointer</td>
</tr>
</tbody>
</table>

Between the % and the conversion character, the following symbols or specifiers contained in square brackets can appear, in the order shown.

- `%[-][0][width]type`

A dash (-) symbol causes the converted argument to be left-justified within a field of width characters with blanks following. A 0 (zero) causes the converted argument to be right-justified within a field of size width with leading 0s. If neither a dash nor 0 are given, the converted argument is right-justified in a field of size width, with leading blanks. The width is a decimal integer. The converted argument is not modified if it has more than width characters, or if width is not given.

The length modifier l can precede %d, %u, %o, and %x if the corresponding argument is a long integer.

SYS_vprintf is equivalent to SYS_printf, except that the optional set of arguments is replaced by a va_list on which the standard C macro va_start has already been applied. SYS_printf and SYS_vsprintf are counterparts of SYS_printf and SYS_vprintf, respectively, in which output is placed in a specified buffer.
Both SYS_printf and SYS_vprintf internally call the function SYS_putchar to output individual characters via the Putc function configured in the SYS Manager Properties. The default Putc function is _UTL_doPutc, which writes a character to the system trace buffer. The size and memory segment for the system trace buffer can also be set in the SYS Manager Properties. This system trace buffer can be viewed only by looking for the SYS_PUTCBEG symbol in the CCS Memory view.

Constraints and Calling Context

- The function bound to Exit function or any of the handler functions are not reentrant; SYS_exit must be called atomically.

See Also

SYS_sprintf
SYS_vprintf
SYS_vsprintf
SYS_sprintf

Output formatted data

C Interface

Syntax

SYS_sprintf (buffer, format, [arg,] ...);

Parameters

- String buffer; /* output buffer */
- String format; /* format specification string */
- Arg arg; /* optional argument */

Return Value

Void

Description

SYS_sprintf provides a subset of the capabilities found in the standard C library function printf.

Note:
SYS_sprintf and the related functions are code-intensive. If possible, applications should use LOG Module functions to reduce code size and execution time.

Conversion specifications begin with a % and end with a conversion character. The conversion characters recognized by SYS_sprintf are limited to the characters in Table 2-8.

Table 2-8: Conversion Characters Recognized by SYS_sprintf

<table>
<thead>
<tr>
<th>Character</th>
<th>Corresponding Output Format</th>
</tr>
</thead>
<tbody>
<tr>
<td>d</td>
<td>signed decimal integer</td>
</tr>
<tr>
<td>u</td>
<td>unsigned decimal integer</td>
</tr>
<tr>
<td>o</td>
<td>octal integer</td>
</tr>
<tr>
<td>x</td>
<td>hexadecimal integer</td>
</tr>
<tr>
<td>c</td>
<td>single character</td>
</tr>
<tr>
<td>s</td>
<td>NULL-terminated string</td>
</tr>
<tr>
<td>p</td>
<td>data pointer</td>
</tr>
</tbody>
</table>

Between the % and the conversion character, the following symbols or specifiers contained within square brackets can appear, in the order shown.

%[-][0][width]type

A dash (-) symbol causes the converted argument to be left-justified within a field of width characters with blanks following. A 0 (zero) causes the converted argument to be right-justified within a field of size width with leading 0s. If neither a dash nor 0 are given, the converted argument is right-justified in a field of size width, with leading blanks. The width is a decimal integer. The converted argument is not modified if it has more than width characters, or if width is not given.

The length modifier l can precede %d, %u, %o, and %x if the corresponding argument is a long integer.
SYS_vprintf is equivalent to SYS_printf, except that the optional set of arguments is replaced by a va_list on which the standard C macro va_start has already been applied. SYS_sprintf and SYS_vsprintf are counterparts of SYS_printf and SYS_vprintf, respectively, in which output is placed in a specified buffer.

Both SYS_printf and SYS_vprintf internally call the function SYS_putchar to output individual characters in a system-dependent fashion via the configuration parameter Putc function. This parameter is bound to a function that displays output on a debugger if one is running, or places output in an output buffer between PUTCEND and PUTCBEG.

**Constraints and Calling Context**

- The function bound to Exit function or any of the handler functions are not reentrant; SYS_exit must be called atomically.

**See Also**

- SYS_printf
- SYS_vprintf
- SYS_vsprintf
SYS_vprintf

Output formatted data

C Interface

Syntax

SYS_vprintf(format, vargs);

Parameters

String format; /* format specification string */
va_list vargs; /* variable argument list reference */

Return Value

Void

Description

SYS_vprintf provides a subset of the capabilities found in the standard C library function printf.

Note:

SYS_vprintf and the related functions are code-intensive. If possible, applications should use LOG Module functions to reduce code size and execution time.

Conversion specifications begin with a % and end with a conversion character. The conversion characters recognized by SYS_vprintf are limited to the characters in Table Table 2-9.

Table 2-9: Conversion Characters Recognized by SYS_vprintf

<table>
<thead>
<tr>
<th>Character</th>
<th>Corresponding Output Format</th>
</tr>
</thead>
<tbody>
<tr>
<td>d</td>
<td>signed decimal integer</td>
</tr>
<tr>
<td>u</td>
<td>unsigned decimal integer</td>
</tr>
<tr>
<td>o</td>
<td>octal integer</td>
</tr>
<tr>
<td>x</td>
<td>hexadecimal integer</td>
</tr>
<tr>
<td>c</td>
<td>single character</td>
</tr>
<tr>
<td>s</td>
<td>NULL-terminated string</td>
</tr>
<tr>
<td>p</td>
<td>data pointer</td>
</tr>
</tbody>
</table>

Between the % and the conversion character, the following symbols or specifiers contained within square brackets can appear, in the order shown.

%[-][0][width]type

A dash (-) symbol causes the converted argument to be left-justified within a field of width characters with blanks following. A 0 (zero) causes the converted argument to be right-justified within a field of size width with leading 0s. If neither a dash nor 0 are given, the converted argument is right-justified in a field of size width, with leading blanks. The width is a decimal integer. The converted argument is not modified if it has more than width characters, or if width is not given.

The length modifier l can precede %d, %u, %o, and %x if the corresponding argument is a long integer.

SYS_vprintf is equivalent to SYS_printf, except that the optional set of arguments is replaced by a va_list on which the standard C macro va_start has already been applied. SYS_printf and SYS_vsprintf are counterparts of SYS_printf and SYS_vprintf, respectively, in which output is placed in a specified buffer.
Both SYS_printf and SYS_vprintf internally call the function SYS_putchar to output individual characters via the Putc function configured in the SYS Manager Properties. The default Putc function is _UTL_doPutc, which writes a character to the system trace buffer. The size and memory segment for the system trace buffer can also be set in the SYS Manager Properties. This system trace buffer can be viewed only by looking for the SYS_PUTCBEG symbol in the CCS Memory view.

Constraints and Calling Context

- The function bound to Exit function or any of the handler functions are not reentrant; SYS_exit must be called atomically.

See Also

SYS_printf
SYS_sprintf
SYS_vsprintf
SYS_vsprintf

Output formatted data

C Interface

Syntax
   SYS_vsprintf(buffer, format, vargs);

Parameters
   String buffer; /* output buffer */
   String format; /* format specification string */
   va_list vargs; /* variable argument list reference */

Return Value
   Void

Description
SYS_vsprintf provides a subset of the capabilities found in the standard C library function printf.

Note: SYS_vsprintf and the related functions are code-intensive. If possible, applications should use LOG Module functions to reduce code size and execution time.

Conversion specifications begin with a % and end with a conversion character. The conversion characters recognized by SYS_vsprintf are limited to the characters in Table Table 2-10.

Table 2-10: Conversion Characters Recognized by SYS_vsprintf

<table>
<thead>
<tr>
<th>Character</th>
<th>Corresponding Output Format</th>
</tr>
</thead>
<tbody>
<tr>
<td>d</td>
<td>signed decimal integer</td>
</tr>
<tr>
<td>u</td>
<td>unsigned decimal integer</td>
</tr>
<tr>
<td>o</td>
<td>octal integer</td>
</tr>
<tr>
<td>x</td>
<td>hexadecimal integer</td>
</tr>
<tr>
<td>c</td>
<td>single character</td>
</tr>
<tr>
<td>s</td>
<td>NULL-terminated string</td>
</tr>
<tr>
<td>p</td>
<td>data pointer</td>
</tr>
</tbody>
</table>

Between the % and the conversion character, the following symbols or specifiers contained within square brackets can appear, in the order shown.

%[-][0][width]type

A dash (-) symbol causes the converted argument to be left-justified within a field of width characters with blanks following. A 0 (zero) causes the converted argument to be right-justified within a field of size width with leading 0s. If neither a dash nor 0 are given, the converted argument is right-justified in a field of size width, with leading blanks. The width is a decimal integer. The converted argument is not modified if it has more than width characters, or if width is not given.

The length modifier l can precede %d, %u, %o, and %x if the corresponding argument is a long integer.
SYS_vprintf is equivalent to SYS_printf, except that the optional set of arguments is replaced by a va_list on which the standard C macro va_start has already been applied. SYS_sprintf and SYS_vsprintf are counterparts of SYS_printf and SYS_vprintf, respectively, in which output is placed in a specified buffer.

Both SYS_printf and SYS_vprintf internally call the function SYS_putchar to output individual characters in a system-dependent fashion via the configuration parameter Putc function. This parameter is bound to a function that displays output on a debugger if one is running, or places output in an output buffer between PUTCEND and PUTCBEG.

Constraints and Calling Context

- The function bound to Exit function or any of the handler functions are not reentrant; SYS_exit must be called atomically.

See Also

SYS_printf
SYS_sprintf
SYS_vprintf
SYS_putchar

**Output a single character**

**C Interface**

Syntax

```c
SYS_putchar(c);
```

Parameters

- **Char c; /* next output character */**

Return Value

- **Void**

**Description**

SYS_putchar outputs the character c by calling the system-dependent function bound to the configuration parameter Putc function.

```c
((Putc function))(c)
```

For systems with limited I/O capabilities, the function bound to Putc function might simply place c into a global buffer that can be examined after program termination.

The default Putc function for the SYS manager is _UTL_doPutc, which writes a character to the system trace buffer. The size and memory segment for the system trace buffer can be set in the SYS Manager Properties. This system trace buffer can be viewed only by looking for the SYS_PUTCBEG symbol in the CCS Memory view.

SYS_putchar is also used internally by SYS_printf and SYS_vprintf when generating their output.

**Constraints and Calling Context**

- If the function bound to Putc function is not reentrant, SYS_putchar must be called atomically.

**See Also**

- SYS_printf
TRC Module

2.28 TRC Module

The TRC module is the trace manager.

Functions

- TRC_disable. Disable trace class(es)
- TRC_enable. Enable trace type(s)
- TRC_query. Query trace class(es)

Description

The TRC module manages a set of trace control bits which control the real-time capture of program information through event logs and statistics accumulators. For greater efficiency, the target does not store log or statistics information unless tracing is enabled.

Table Table 2-11 lists events and statistics that can be traced. The constants defined in trc.hand trc.h55 are shown in the left column.

Table 2-11: Events and Statistics Traced by TRC

<table>
<thead>
<tr>
<th>Constant</th>
<th>Tracing Enabled/Disabled</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>TRC_LOGCLK</td>
<td>Log timer interrupts</td>
<td>off</td>
</tr>
<tr>
<td>TRC_LOGPRD</td>
<td>Log periodic ticks and start of periodic functions</td>
<td>off</td>
</tr>
<tr>
<td>TRC_LOGSWI</td>
<td>Log events when a SWI is posted and completes</td>
<td>off</td>
</tr>
<tr>
<td>TRC_LOGTSK</td>
<td>Log events when a task is made ready, starts, becomes blocked, resumes execution,</td>
<td>off</td>
</tr>
<tr>
<td>TRC_STSHWI</td>
<td>Gather statistics on monitored values within HWIs</td>
<td>off</td>
</tr>
<tr>
<td>TRC_STSPIP</td>
<td>Count number of frames read from or written to data pipe</td>
<td>off</td>
</tr>
<tr>
<td>TRC_STSPRD</td>
<td>Gather statistics on number of ticks elapsed during execution</td>
<td>off</td>
</tr>
<tr>
<td>TRC_STSSWI</td>
<td>Gather statistics on length of SWI execution</td>
<td>off</td>
</tr>
<tr>
<td>TRC_STSTSK</td>
<td>Gather statistics on length of TSK execution. Statistics are gathered from the time TSK is made ready to run until the application calls TSK_deltatime.</td>
<td>off</td>
</tr>
<tr>
<td>TRC_USER0</td>
<td>Your program can use these bits to enable or disable sets of explicit instrumentation actions. You can use TRC_query to check the settings of these bits and either perform or omit instrumentation calls based on the result. DSP/BIOS does not use or set these bits.</td>
<td>off</td>
</tr>
<tr>
<td>TRC_USER1</td>
<td></td>
<td></td>
</tr>
<tr>
<td>TRC_GBLHOST</td>
<td>This bit must be set in order for any implicit instrumentation to be performed. Simultaneously starts or stops gathering of all enabled types of tracing. This can be important if you are trying to correlate events of different types. This bit is usually set at run time on the host in the RTA Control Panel.</td>
<td>off</td>
</tr>
<tr>
<td>TRC_GBLTARG</td>
<td>This bit must also be set for any implicit instrumentation to be performed. This bit can only be set by the target program and is enabled by default.</td>
<td>on</td>
</tr>
<tr>
<td>TRC_STSSWI</td>
<td>Gather statistics on length of SWI execution</td>
<td></td>
</tr>
</tbody>
</table>

All trace constants except TRC_GBLTARG are switched off initially. To enable tracing you can use calls to TRC_enable or the DSP/BIOS->RTA Control Panel, which uses the TRC module internally. You do not need to enable tracing for messages written with LOG_printf or LOG_event and statistics added with STS_add or STS_delta.

Your program can call the TRC_enable and TRC_disable operations to explicitly start and stop event logging or statistics accumulation in response to conditions encountered during real-time execution. This enables you to preserve the specific log or statistics information you need to see.
TRC_disable

Disable trace class(es)

C Interface

Syntax

TRC_disable(mask);

Parameters

Uns mask; /* trace type constant mask */

Return Value

Void

Reentrant

no

Description

TRC_disable disables tracing of one or more trace types. Trace types are specified with a 32-bit mask. (See the TRC Module topic for a list of constants to use in the mask.)

The following C code would disable tracing of statistics for software interrupts and periodic functions:

TRC_disable(TRC_LOGSWI | TRC_LOGPRD);

Internally, DSP/BIOS uses a bitwise AND NOT operation to disable multiple trace types.

For example, you might want to use TRC_disable with a circular log and disable tracing when an unwanted condition occurs. This allows test equipment to retrieve the log events that happened just before this condition started.

See Also

TRC_enable
TRC_query
LOG_printf
LOG_event
STS_add
STS_delta
TRC_enable

Enable trace type(s)

C Interface

Syntax

TRC_enable(mask);

Parameters

Uns mask; /* trace type constant mask */

Return Value

Void

Reentrant

no

Description

TRC_enable enables tracing of one or more trace types. Trace types are specified with a 32-bit mask. (See the TRC Module topic for a list of constants to use in the mask.)

The following C code would enable tracing of statistics for software interrupts and periodic functions:

TRC_enable(TRC_STSSWI | TRC_STSPRD);

Internally, DSP/BIOS uses a bitwise OR operation to enable multiple trace types.

For example, you might want to use TRC_enable with a fixed log to enable tracing when a specific condition occurs. This allows test equipment to retrieve the log events that happened just after this condition occurred.

See Also

TRC_disable
TRC_query
LOG_printf
LOG_event
STS_add
STS_delta
**TRC_query**  
*Query trace class(es)*

**C Interface**

**Syntax**

```c
result = TRC_query(mask);
```

**Parameters**

- `Uns mask; /* trace type constant mask */`

**Return Value**

- `Int result /* indicates whether all trace types enabled */`

**Reentrant**

- `yes`

**Description**

TRC_query determines whether particular trace types are enabled. TRC_query returns 0 if all trace types in the mask are enabled. If any trace types in the mask are disabled, TRC_query returns a value with a bit set for each trace type in the mask that is disabled. (See the TRC Module topic for a list of constants to use in the mask.)

Trace types are specified with a 16-bit mask. The full list of constants you can use is included in the description of the TRC module.

For example, the following C code returns 0 if statistics tracing for the PRD class is enabled:

```c
result = TRC_query(TRC_STSPRD);
```

The following C code returns 0 if both logging and statistics tracing for the SWI class are enabled:

```c
result = TRC_query(TRC_LOGSWI | TRC_STSSWI);
```

Note that TRC_query does not return 0 unless the bits you are querying and the TRC_GBLHOST and TRC_GBLTARG bits are set. TRC_query returns non-zero if either TRC_GBLHOST or TRC_GBLTARG are disabled. This is because no tracing is done unless these bits are set.

For example, if the TRC_GBLHOST, TRC_GBLTARG, and TRC_LOGSWI bits are set, this C code returns the results shown:

```c
result = TRC_query(TRC_LOGSWI); /* returns 0 */
result = TRC_query(TRC_LOGPRD); /* returns non-zero */
```

However, if only the TRC_GBLHOST and TRC_LOGSWI bits are set, the same C code returns the results shown:

```c
result = TRC_query(TRC_LOGSWI); /* returns non-zero */
result = TRC_query(TRC_LOGPRD); /* returns non-zero */
```

**See Also**

- TRC_enable
- TRC_disable
2.29 TSK Module

The TSK module is the task manager.

Functions

- TSK_checkstacks. Check for stack overflow
- TSK_create. Create a task ready for execution
- TSK_delete. Delete a task
- TSK_deltatime. Update task STS with time difference
- TSK_disable. Disable DSP/BIOS task scheduler
- TSK_enable. Enable DSP/BIOS task scheduler
- TSK_exit. Terminate execution of the current task
- TSK_getenv. Get task environment
- TSK_geterr. Get task error number
- TSK_getname. Get task name
- TSK_getpri. Get task priority
- TSK_getsts. Get task STS object
- TSK_isTSK. Check current thread calling context
- TSK_itick. Advance system alarm clock (interrupt only)
- TSK_self. Get handle of currently executing task
- TSK_setenv. Set task environment
- TSK_seterr. Set task error number
- TSK_setpri. Set a task's execution priority
- TSK_settime. Set task STS previous time
- TSK_sleep. Delay execution of the current task
- TSK_stat. Retrieve the status of a task
- TSK_tick. Advance system alarm clock
- TSK_time. Return current value of system clock
- TSK_yield. Yield processor to equal priority task

Task Hook Functions

Void TSK_createFxns(TSK_Handle task);
Void TSK_deleteFxns(TSK_Handle task);
Void TSK_exitFxns(Void);
Void TSK_readyFxns(TSK_Handle newtask);
Void TSK_switchFxns(TSK_Handle oldtask,
   TSK_Handle newtask);
Constants, Types, and Structures

typedef struct TSK_OBJ *TSK_Handle; /* task object handle*/

struct TSK_Attrs {  /* task attributes */
  Int   priority;    /* execution priority */
  Ptr    stack;      /* pre-allocated stack */
  size_t stacksize;  /* stack size in MADUs */
#ifdef _55_
  size_t sysstacksize; /*C55x system stack in MADUs */
#endif
  Int    stackseg;   /* mem seg for stack allocation */
  Ptr    environ;    /* global environment data struct */
  String name;       /* printable name */
  Bool   exitflag;   /* program termination requires */
  /* this task to terminate */
  Bool   initstackflag;  /* initialize task stack? */
};

Int TSK_pid;          /* MP processor ID */

Int TSK_MAXARGS = 8;  /* max number of task arguments */
Int TSK_IDLEPRI = 0;  /* used for idle task */
Int TSK_MINPRI = 1;   /* minimum execution priority */
Int TSK_MAXPRI = 15;  /* maximum execution priority */
Int TSK_STACKSTAMP =

TSK_Attrs TSK_ATTRS = { /* default attribute values */
  TSK->PRIORITY,    /* priority */
  NULL,             /* stack */
  TSK->STACKSIZE,   /* stacksize */
#ifdef _55_
  TSK->SYSSTACKSIZE, /* system stacksize in MADUs */
#endif
  TSK->STACKSEG,    /* stackseg */
  NULL,             /* environ */
  "",               /* name */
  TRUE,             /* exitflag */
  TRUE,             /* initstackflag */
};

eenum TSK_Mode {     /* task execution modes */
  TSK_RUNNING,      /* task currently executing */
  TSK_READY,        /* task scheduled for execution */
  TSK_BLOCKED,      /* task suspended from execution */
  TSK_TERMINATED,   /* task terminated from execution */
};

struct TSK_Stat {    /* task status structure */
  TSK_Attrs  attrs;   /* task attributes */
  TSK_Mode   mode;    /* task execution mode */
  Ptr        sp;      /* task stack pointer */
#ifdef _55_
  Ptr        ssp;     /* task system stack pointer */
#endif
  size_t     used;    /* task stack used */
#ifdef _55_
  size_t     sysused; /* task system stack used */
#endif
};

Configuration Properties

The following list shows the properties that can be configured in a Tconf script, along with their types and default values. For details, see the TSK Manager Properties and TSK Object Properties headings. For descriptions of data types, see Section 1.4, DSP/BIOS Tconf Overview, page 1-10.
Module Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>ENABLETSK</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>OBJMEMSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>STACKSIZE</td>
<td>Int16</td>
<td>1024</td>
</tr>
<tr>
<td>SYSSTACKSIZE</td>
<td>Int16</td>
<td>256</td>
</tr>
<tr>
<td>STACKSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>PRIORITY</td>
<td>EnumInt</td>
<td>1 (1 to 15)</td>
</tr>
<tr>
<td>DRIVETSKTICK</td>
<td>EnumString</td>
<td>&quot;PRD&quot; (&quot;User&quot;)</td>
</tr>
<tr>
<td>CREATEFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>DELETEFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>EXITFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>CALLSWITCHFXN</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>SWITCHFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>CALLREADYFXN</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>READYFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
</tbody>
</table>

Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>comment</td>
<td>String</td>
<td>&quot;&lt;add comments here&gt;&quot;</td>
</tr>
<tr>
<td>autoAllocateStack</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>manualStack</td>
<td>Extern</td>
<td>prog.extern(&quot;null&quot;,&quot;asm&quot;)</td>
</tr>
<tr>
<td>stackSize</td>
<td>Int16</td>
<td>1024</td>
</tr>
<tr>
<td>sysStackSize</td>
<td>Int16</td>
<td>256</td>
</tr>
<tr>
<td>stackMemSeg</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>priority</td>
<td>EnumInt</td>
<td>0 (-1, 0, 1 to 15)</td>
</tr>
<tr>
<td>fxn</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>arg0</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>arg7</td>
<td>Arg</td>
<td>0</td>
</tr>
<tr>
<td>envPointer</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>exitFlag</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>allocateTaskName</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>order</td>
<td>Int16</td>
<td>0</td>
</tr>
</tbody>
</table>

Description

The TSK module makes available a set of functions that manipulate task objects accessed through handles of type TSK_Handle. Tasks represent independent threads of control that conceptually execute functions in parallel within a single C program; in reality, concurrency is achieved by switching the processor from one task to the next.
When you create a task, it is provided with its own run-time stack, used for storing local variables as well as for further nesting of function calls. The TSK_STACKSTAMP value is used to initialize the run-time stack. When creating a task dynamically, you need to initialize the stack with TSK_STACKSTAMP only if the stack is allocated manually and TSK_checkstacks or TSK_stat is to be called. Each stack must be large enough to handle normal subroutine calls as well as a single task preemption context. A task preemption context is the context that gets saved when one task preempts another as a result of an interrupt thread readying a higher-priority task. All tasks executing within a single program share a common set of global variables, accessed according to the standard rules of scope defined for C functions.

Each task is in one of four modes of execution at any point in time: running, ready, blocked, or terminated. By design, there is always one (and only one) task currently running, even if it is a dummy idle task managed internally by TSK. The current task can be suspended from execution by calling certain TSK functions, as well as functions provided by other modules like the SEM Module and the SIO Module; the current task can also terminate its own execution. In either case, the processor is switched to the next task that is ready to run.

You can assign numeric priorities to tasks through TSK. Tasks are readied for execution in strict priority order; tasks of the same priority are scheduled on a first-come, first-served basis. As a rule, the priority of the currently running task is never lower than the priority of any ready task. Conversely, the running task is preempted and re-scheduled for execution whenever there exists some ready task of higher priority.

You can use Tconf to specify one or more sets of application-wide hook functions that run whenever a task state changes in a particular way. For the TSK module, these functions are the Create, Delete, Exit, Switch, and Ready functions. The HOOK module adds an additional Initialization function.

A single set of hook functions can be specified for the TSK module itself. To create additional sets of hook functions, use the HOOK Module. When you create the first HOOK object, any TSK module hook functions you have specified are automatically placed in a HOOK object called HOOK_KNL. To set any properties of this object other than the Initialization function, use the TSK module properties. To set the Initialization function property of the HOOK_KNL object, use the HOOK object properties. If you configure only a single set of hook functions using the TSK module, the HOOK module is not used.

The TSK_create topic describes the Create function. The TSK_delete topic describes the Delete function. The TSK_exit topic describes the Exit function.

If a Switch function is specified, it is invoked when a new task becomes the TSK_RUNNING task. The Switch function gives the application access to both the current and next task handles at task switch time. The function should use these argument types:

```c
Void mySwitchFxn(TSK_Handle currTask,
                  TSK_Handle nextTask);
```

This function can be used to save/restore additional task context (for example, external hardware registers), to check for task stack overflow, to monitor the time used by each task, etc.
If a Ready function is specified, it is invoked whenever a task is made ready to run. Even if a higher-priority thread is running, the Ready function runs. The Ready function is called with a handle to the task being made ready to run as its argument. This example function prints the name of both the task that is ready to run and the task that is currently running:

```c
Void myReadyFxnn(TSK_Handle task)
{
    String      nextName, currName;
    TSK_Handle  currTask = TSK_self();

    nextName = TSK_getname(task);
    LOG_printf(&trace, “Task %s Ready”, nextName);

    currName = TSK_getname(currTask);
    LOG_printf(&trace, “Task %s Running”, currName);
}
```

The Switch function and Ready function are called in such a way that they can use only functions allowed within a SWI handler. See Appendix A, Function Callability Table, for a list of functions that can be called by SWI handlers. There are no real constraints on what functions are called via the Create function, Delete function, or Exit function.

### TSK Manager Properties

The following global properties can be set for the TSK module in the TSK Manager Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

- **Enable TSK Manager.** If no tasks are used by the program other than TSK_idle, you can optimize the program by disabling the task manager. The program must then not use TSK objects created with either Tconf or the TSK_create function. If the task manager is disabled, the idle loop still runs and uses the system stack instead of a task stack.
  
  **Tconf Name:** ENABLETSK  
  **Type:** Bool  
  **Example:** bios.TSK.ENABLETSK = true;

- **Object Memory.** The memory segment that contains the TSK objects created with Tconf.
  
  **Tconf Name:** OBJMEMSEG  
  **Type:** Reference  
  **Example:** bios.TSK.OBJMEMSEG = prog.get("myMEM");

- **Default stack size.** The default size of the stack (in MADUs) used by tasks. You can override this value for an individual task you create with Tconf or TSK_create. The estimated minimum task size is shown in the status bar of the DSP/BIOS Configuration Tool. This property applies to TSK objects created both with Tconf and with TSK_create.
  
  **Tconf Name:** STACKSIZE  
  **Type:** Int16  
  **Example:** bios.TSK.STACKSIZE = 1024;

- **Default systack size.** This property defines the size (in MADUs) of the system stack.
  
  **Tconf Name:** SYSSTACKSIZE  
  **Type:** Int16  
  **Example:** bios.TSK.SYSSTACKSIZE = 256;
- **Stack segment for dynamic tasks.** The default memory segment to contain task stacks created at run-time with the TSK_create function. The TSK_Attrs structure passed to the TSK_create function can override this default. If you select MEM_NULL for this property, creation of task objects at run-time is disabled.

  Tconf Name: STACKSEG       Type: Reference
  Example: bios.TSK.STACKSEG = prog.get("myMEM");

- **Default task priority.** The default priority level for tasks that are created dynamically with TSK_create. This property applies to TSK objects created both with Tconf and with TSK_create.

  Tconf Name: PRIORITY       Type: EnumInt
  Options: 1 to 15
  Example: bios.TSK.PRIORITY = 1;

- **TSK tick driven by.** Choose whether you want the system clock to be driven by the PRD module or by calls to TSK_tick and TSK_itick. This clock is used by TSK_sleep and functions such as SEM_pend that accept a timeout argument.

  Tconf Name: DRIVETSKTICK   Type: EnumString
  Options: "PRD", "User"
  Example: bios.TSK.DRIVETSKTICK = "PRD";

- **Create function.** The name of a function to call when any task is created. This includes tasks that are created statically and those created dynamically using TSK_create. If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally. The TSK_create topic describes the Create function.

  Tconf Name: CREATEFXN      Type: Extern
  Example: bios.TSK.CREATEFXN = prog.extern("tskCreate");

- **Delete function.** The name of a function to call when any task is deleted at run-time with TSK_delete. The TSK_delete topic describes the Delete function.

  Tconf Name: DELETEFXN      Type: Extern
  Example: bios.TSK.DELETEFXN = prog.extern("tskDelete");

- **Exit function.** The name of a function to call when any task exits. The TSK_exit topic describes the Exit function.

  Tconf Name: EXITFXN        Type: Extern
  Example: bios.TSK.EXITFXN = prog.extern("tskExit");

- **Call switch function.** Check this box if you want a function to be called when any task switch occurs.

  Tconf Name: CALLSWITCHFXN  Type: Bool
  Example: bios.TSK.CALLSWITCHFXN = false;

- **Switch function.** The name of a function to call when any task switch occurs. This function can give the application access to both the current and next task handles. The TSK Module topic describes the Switch function.

  Tconf Name: SWITCHFXN      Type: Extern
  Example: bios.TSK.SWITCHFXN = prog.extern("tskSwitch");

- **Call ready function.** Check this box if you want a function to be called when any task becomes ready to run.

  Tconf Name: CALLREADYFXN   Type: Bool
  Example: bios.TSK.CALLREADYFXN = false;
• **Ready function.** The name of a function to call when any task becomes ready to run. The TSK Module topic describes the Ready function.

   **Tconf Name:** READYFXN  
   **Type:** Extern  
   **Example:**
   ```c
   bios.TSK.READYFXN = prog.extern("tskReady");
   ```

**TSK Object Properties**

To create a TSK object in a configuration script, use the following syntax. The Tconf examples that follow assume the object has been created as shown here.

```c
var myTsk = bios.TSK.create("myTsk");
```

The following properties can be set for a TSK object in the TSK Object Properties dialog of the DSP/BIOS Configuration Tool or in a Tconf script:

**General tab**

- **comment.** Type a comment to identify this TSK object.
  
  **Tconf Name:** comment  
  **Type:** String  
  **Example:**
  ```c
  myTsk.comment = "my TSK";
  ```

- **Automatically allocate stack.** Check this box if you want the task’s private stack space to be allocated automatically when this task is created. The task’s context is saved in this stack before any higher-priority task is allowed to block this task and run.

  **Tconf Name:** autoAllocateStack  
  **Type:** Bool  
  **Example:**
  ```c
  myTsk.autoAllocateStack = true;
  ```

- **Manually allocated stack.** If you did not check the box to Automatically allocate stack, type the name of the manually allocated stack to use for this task.

  For ‘C55x, the manually allocated stack must be large enough to accommodate both the stack and the system stack (sysstack) on the same page. Automatically allocating the stack is recommended, since TSK_create makes sure this condition is satisfied.

  **Tconf Name:** manualStack  
  **Type:** Extern  
  **Example:**
  ```c
  myTsk.manualStack = prog.extern("myStack");
  ```

- **Stack size.** Enter the size (in MADUs) of the stack space to allocate for this task. You must enter the size whether the application allocates the stack manually or automatically. Each stack must be large enough to handle normal subroutine calls as well as a single task preemption context. A task preemption context is the context that gets saved when one task preempts another as a result of an interrupt thread readying a higher priority task.

  **Tconf Name:** stackSize  
  **Type:** Int16  
  **Example:**
  ```c
  myTsk.stackSize = 1024;
  ```

- **System stack size.** This specifies the size (in MADUs) of the task’s system stack. The stackSize + sysStackSize must be less than or equal to 0xFFFF. That is, they should be on the same page because the stack pointer and system stack pointer share the same register for their upper bits.

  **Tconf Name:** sysStackSize  
  **Type:** Int16  
  **Example:**
  ```c
  myTsk.sysStackSize = 256;
  ```

- **Stack Memory Segment.** If you set the "Automatically allocate stack" property to true, specify the memory segment to contain the stack space for this task.

  **Tconf Name:** stackMemSeg  
  **Type:** Reference  
  **Example:**
  ```c
  myTsk.stackMemSeg = prog.get("myMEM");
  ```
- **Priority.** The priority level for this task. A priority of -1 causes a task to be suspended until its priority is raised programmatically.
  - **Tconf Name:** priority
  - **Type:** EnumInt
  - **Options:** -1, 0, 1 to 15
  - **Example:** `myTsk.priority = 1;`

**Function tab**

- **Task function.** The function to be executed when the task runs. If this function is written in C and you are using the DSP/BIOS Configuration Tool, use a leading underscore before the C function name. (The DSP/BIOS Configuration Tool generates assembly code which must use the leading underscore when referencing C functions or labels.) If you are using Tconf, do not add an underscore before the function name; Tconf adds the underscore needed to call a C function from assembly internally. If you compile C programs with the -pm or -op2 options, you should precede C functions called by task threads with the FUNC_EXT_CALLED pragma. See the online help for the C compiler for details.
  - **Tconf Name:** fxn
  - **Type:** Extern
  - **Example:** `myTsk.fxn = prog.extern("tskFxn");`

- **Task function argument 0-7.** The arguments to pass to the task function. Arguments can be integers or labels.
  - **Tconf Name:** arg0 to arg7
  - **Type:** Arg
  - **Example:** `myTsk.arg0 = 0;`

**Advanced tab**

- **Environment pointer.** A pointer to a globally-defined data structure this task can access. The task can get and set the task environment pointer with the TSK_getenv and TSK_setenv functions. If your program uses multiple HOOK objects, HOOK_setenv allows you to set individual environment pointers for each HOOK and TSK object combination.
  - **Tconf Name:** envPointer
  - **Type:** Arg
  - **Example:** `myTsk.envPointer = 0;`

- **Don’t shut down system while this task is still running.** Check this box if you do not want the application to be able to end if this task is still running. The application can still abort. For example, you might clear this box for a monitor task that collects data whenever all other tasks are blocked. The application does not need to explicitly shut down this task.
  - **Tconf Name:** exitFlag
  - **Type:** Bool
  - **Example:** `myTsk.exitFlag = true;`

- **Allocate Task Name on Target.** Check this box if you want the name of this TSK object to be retrievable by the TSK_getname function. Clearing this box saves a small amount of memory. The task name is available in analysis tools in either case.
  - **Tconf Name:** allocateTaskName
  - **Type:** Bool
  - **Example:** `myTsk.allocateTaskName = false;`

- **order.** Set this property for all TSK objects so that the numbers match the sequence in which TSK functions with the same priority level should be executed.
  - **Tconf Name:** order
  - **Type:** Int16
  - **Example:** `myTsk.order = 2;`
**TSK_checkstacks**  *Check for stack overflow*

**C Interface**

Syntax

```c
TSK_checkstacks(oldtask, newtask);
```

Parameters

- **TSK_Handle oldtask;** /* handle of task switched from */
- **TSK_Handle newtask;** /* handle of task switched to */

Return Value

**Void**

Description

`TSK_checkstacks` calls SYS_abort with an error message if either `oldtask` or `newtask` has a stack in which the last location no longer contains the initial value TSK_STACKSTAMP. The presumption in one case is that `oldtask`'s stack overflowed, and in the other that an invalid store has corrupted `newtask`'s stack.

`TSK_checkstacks` requires that the stack was initialized by DSP/BIOS. For dynamically-created tasks, initialization is controlled by the initstackflag attribute in the TSK_Attrs structure passed to TSK_create. Statically configured tasks always initialize the stack.

You can call `TSK_checkstacks` directly from your application. For example, you can check the current task's stack integrity at any time with a call like the following:

```c
TSK_checkstacks(TSK_self(), TSK_self());
```

However, it is more typical to call `TSK_checkstacks` in the task Switch function specified for the TSK manager in your configuration file. This provides stack checking at every context switch, with no alterations to your source code.

If you want to perform other operations in the Switch function, you can do so by writing your own function (`myswitchfxn`) and then calling `TSK_checkstacks` from it.

```c
Void myswitchfxn(TSK_Handle oldtask,
                 TSK_Handle newtask)
{
    `your additional context switch operations`
    TSK_checkstacks(oldtask, newtask);
    ...
}
```

**Constraints and Calling Context**

- `TSK_checkstacks` cannot be called from an HWI or SWI.
**TSK_create**

*Create a task ready for execution*

**C Interface**

Syntax

```c
task = TSK_create(fxn, attrs, [arg,] ...);
```

Parameters

- `Fxn fxn; /* pointer to task function */`
- `TSK_Attrs *attrs; /* pointer to task attributes */`
- `Arg arg; /* task arguments */`

Return Value

- `TSK_Handle task; /* task object handle */`

**Description**

TSK_create creates a new task object. If successful, TSK_create returns the handle of the new task object. If unsuccessful, TSK_create returns NULL unless it aborts (for example, because it directly or indirectly calls SYS_error, and SYS_error is configured to abort).

The `fxn` parameter uses the `Fxn` type to pass a pointer to the function the TSK object should run. For example, if `myFxn` is a function in your program, you can create a TSK object to call that function as follows:

```c
task = TSK_create((Fxn)myFxn, NULL);
```

You can use `Tconf` to specify an application-wide Create function that runs whenever a task is created. This includes tasks that are created statically and those created dynamically using TSK_create. The default Create function is a no-op function.

For TSK objects created statically, the Create function is called during the BIOS_start portion of the program startup process, which runs after the `main()` function and before the program drops into the idle loop.

For TSK objects created dynamically, the Create function is called after the task handle has been initialized but before the task has been placed on its ready queue.

Any DSP/BIOS function can be called from the Create function. DSP/BIOS passes the task handle of the task being created to the Create function. The Create function declaration should be similar to this:

```c
Void myCreateFxn(TSK_Handle task);
```

The new task is placed in TSK_READY mode, and is scheduled to begin concurrent execution of the following function call:

```c
(*fxn)(arg1, arg2, ... argN) /* N = TSK_MAXARGS = 8 */
```

As a result of being made ready to run, the task runs the application-wide Ready function if one has been specified.

TSK_exit is automatically called if and when the task returns from `fxn`. 
If attrs is NULL, the new task is assigned a default set of attributes. Otherwise, the task's attributes are specified through a structure of type TSK_Attrs, which is defined as follows.

```c
struct TSK_Attrs { /* task attributes */
    Int    priority;  /* execution priority */
    Ptr    stack;     /* pre-allocated stack */
    size_t stacksize; /* stack size in MADUs */
    #ifdef _55_
    size_t sysstacksize; /*C55x sysstack in MADUs */
    #endif
    Int    stackseg; /* mem seg for stack alloc */
    Ptr    environ;  /* global environ data struct */
    String name;     /* printable name */
    Bool   exitflag; /* prog termination requires */
                      /* this task to terminate */
    Bool   initstackflag;  /* initialize task stack? */
};
```

The priority attribute specifies the task's execution priority and must be less than or equal to TSK_MAXPRI (15); this attribute defaults to the value of the configuration parameter Default task priority (preset to TSK_MINPRI). If priority is less than 0, the task is barred from execution until its priority is raised at a later time by TSK_setpri. A priority value of 0 is reserved for the TSK_idle task defined in the default configuration. You should not use a priority of 0 for any other tasks.

The stack attribute specifies a pre-allocated block of stacksize MADUs to be used for the task's private stack; this attribute defaults to NULL, in which case the task's stack is automatically allocated using MEM_alloc from the memory segment given by the stackseg attribute. If you specify a pre-allocated stack for C55x, the buffer must be attrs.stacksize plus attrs.sysstacksize in length.

The stacksize attribute specifies the number of MADUs to be allocated for the task's private stack; this attribute defaults to the value of the configuration parameter Default stack size. Each stack must be large enough to handle normal subroutine calls as well as a single task preemption context. A task preemption context is the context that gets saved when one task preempts another as a result of an interrupt thread readying a higher priority task.

The sysstacksize attribute specifies a pre-allocated block of the specified number of MADUs to be used for the task's private system stack. This attribute defaults to NULL, in which case the task's system stack is automatically allocated using MEM_alloc from the memory segment given by the stackseg attribute. The sysstacksize attribute specifies the number of MADUs to be allocated for the task's private system stack. This attribute defaults to the value of the configuration parameter Default system stack size (preset to 256).

The stackseg attribute specifies the memory segment to use when allocating the task stack with MEM_alloc; this attribute defaults to the value of the configuration parameter Default stack segment.

The environ attribute specifies the task's global environment through a generic pointer that references an arbitrary application-defined data structure; this attribute defaults to NULL.

The name attribute specifies the task's printable name, which is a NULL-terminated character string; this attribute defaults to the empty string "". This name can be returned by TSK_getname.

The exitflag attribute specifies whether the task must terminate before the program as a whole can terminate; this attribute defaults to TRUE.
The initstackflag attribute specifies whether the task stack is initialized to enable stack depth checking by TSK_checkstacks. This attribute applies both in cases where the stack attribute is NULL (stack is allocated by TSK_create) and where the stack attribute is used to specify a pre-allocated stack. If your application does not call TSK_checkstacks, you can reduce the time consumed by TSK_create by setting this attribute to FALSE.

All default attribute values are contained in the constant TSK_ATTRS, which can be assigned to a variable of type TSK_Attrs prior to calling TSK_create.

A task switch occurs when calling TSK_create if the priority of the new task is greater than the priority of the current task.

TSK_create calls MEM_alloc to dynamically create an object's data structure. MEM_alloc must lock the memory before proceeding. If another thread already holds a lock to the memory, then there is a context switch. The segment from which the object is allocated is described by the DSP/BIOS objects property in the MEM Module, page 2–204.

### Constraints and Calling Context

- TSK_create cannot be called from a SWI or HWI.
- The fxn parameter and the name attribute cannot be NULL.
- The priority attribute must be less than or equal to TSK_MAXPRI and greater than or equal to TSK_MINPRI. The priority can be less than zero (0) for tasks that should not execute.
- The string referenced through the name attribute cannot be allocated locally.
- The stackseg attribute must identify a valid memory segment.
- You can reduce the size of your application program by creating objects with Tconf rather than using the XXX_create functions.

### See Also
- MEM_alloc
- SYS_error
- TSK_delete
- TSK_exit
**TSK_delete**

*Delete a task*

**C Interface**

**Syntax**

```c
TSK_delete(task);
```

**Parameters**

- `TSK_Handle task; /* task object handle */`

**Return Value**

`Void`

**Description**

`TSK_delete` removes the task from all internal queues and calls `MEM_free` to free the task object and stack. `task` should be in a state that does not violate any of the listed constraints.

If all remaining tasks have their `exitflag` attribute set to `FALSE`, DSP/BIOS terminates the program as a whole by calling `SYS_exit` with a status code of 0.

You can use `Tconf` to specify an application-wide `Delete` function that runs whenever a task is deleted. The default `Delete` function is a no-op function. The `Delete` function is called before the task object has been removed from any internal queues and its object and stack are freed. Any DSP/BIOS function can be called from the `Delete` function. DSP/BIOS passes the task handle of the task being deleted to your `Delete` function. Your `Delete` function declaration should be similar to the following:

```c
Void myDeleteFxn(TSK_Handle task);
```

`TSK_delete` calls `MEM_free` to delete the TSK object. `MEM_free` must acquire a lock to the memory before proceeding. If another task already holds a lock to the memory, then there is a context switch.

**Note:** Unless the mode of the deleted task is `TSK_TERMINATED`, `TSK_delete` should be called with care. For example, if the task has obtained exclusive access to a resource, deleting the task makes the resource unavailable.

**Constraints and Calling Context**

- The task cannot be the currently executing task (`TSK_self`).
- `TSK_delete` cannot be called from a SWI or HWI.
- No check is performed to prevent `TSK_delete` from being used on a statically-created object. If a program attempts to delete a task object that was created using `Tconf`, `SYS_error` is called.

**See Also**

- `MEM_free`
- `TSK_create`
**TSK_deltatime**  
*Update task statistics with time difference*

**C Interface**

**Syntax**

```c
TSK_deltatime(task);
```

**Parameters**

```c
TSK_Handle task; // task object handle
```

**Return Value**

`Void`

**Description**

This function accumulates the time difference from when a task is made ready to the time `TSK_deltatime` is called. These time differences are accumulated in the task's internal STS object and can be used to determine whether or not a task misses real-time deadlines.

If `TSK_deltatime` is not called by a task, its STS object is never updated in the Statistics View, even if TSK accumulators are enabled in the RTA Control Panel.

TSK statistics are handled differently than other statistics because TSK functions typically run an infinite loop that blocks when waiting for other threads. In contrast, HWI and SWI functions run to completion without blocking. Because of this difference, DSP/BIOS allows programs to identify the "beginning" of a TSK function's processing loop by calling `TSK_settime` and the "end" of the loop by calling `TSK_deltatime`.

For example, if a task waits for data and then processes the data, you want to ensure that the time from when the data is made available until the processing is complete is always less than a certain value. A loop within the task can look something like the following:

```c
Void task
{
    "do some startup work"
    /* Initialize time in task's STS object to current time */
    TSK_settime(TSK_self());

    for (;;) {
        /* Get data */
        SIO_get(...);
        "process data"
        /* Get time difference and add it to task's STS object */
        TSK_deltatime(TSK_self());
    }
}
```
In the example above, the task blocks on SIO_get and the device driver posts a semaphore that readies the task. DSP/BIOS sets the task's statistics object with the current time when the semaphore becomes available and the task is made ready to run. Thus, the call to TSK_deltatime effectively measures the processing time of the task.

**Constraints and Calling Context**

- The results of calls to TSK_deltatime and TSK_settime are displayed in the Statistics View only if Enable TSK accumulators is selected in the RTA Control Panel.

**See Also**

- TSK_getsts
- TSK_settime
**TSK_disable**  
*Disable DSP/BIOS task scheduler*

### C Interface

**Syntax**

```c
TSK_disable();
```

**Parameters**

- **Void**

**Return Value**

- **Void**

**Description**

`TSK_disable` disables the DSP/BIOS task scheduler. The current task continues to execute (even if a higher priority task can become ready to run) until `TSK_enable` is called.

`TSK_disable` does not disable interrupts, but is instead used before disabling interrupts to make sure a context switch to another task does not occur when interrupts are disabled.

`TSK_disable` maintains a count which allows nested calls to `TSK_disable`. Task switching is not reenabled until `TSK_enable` has been called as many times as `TSK_disable`. Calls to `TSK_disable` can be nested.

Since `TSK_disable` can prohibit ready tasks of higher priority from running it should not be used as a general means of mutual exclusion. SEM Module semaphores should be used for mutual exclusion when possible.

**Constraints and Calling Context**

- Do not call any function that can cause the current task to block or otherwise affect the state of the scheduler within a `TSK_disable/TSK_enable` block. For example, `SEM_pend` (if timeout is non-zero), `TSK_sleep`, `TSK_yield`, and `MEM_alloc` can all cause blocking. Similarly, any MEM module call and any call that dynamically creates or deletes an object (`XXX_create` or `XXX_delete`) can affect the state of the scheduler. For a complete list, see the "Possible Context Switch" column in Section A.1, `Function Callability Table`.

- `TSK_disable` cannot be called from a SWI or HWI.

- `TSK_disable` cannot be called from the program’s main() function.

- Do not call `TSK_enable` when TSKs are already enabled. If you do so, the subsequent call to `TSK_disable` will not disable TSK processing.

**See Also**

- SEM Module
- `TSK_enable`
**TSK_enable**  
*Enable DSP/BIOS task scheduler*

**C Interface**

**Syntax**

```c
TSK_enable();
```

**Parameters**

- **Void**

**Return Value**

- **Void**

**Description**

TSK_enable is used to reenable the DSP/BIOS task scheduler after TSK_disable has been called. Since TSK_disable calls can be nested, the task scheduler is not enabled until TSK_enable is called the same number of times as TSK_disable.

A task switch occurs when calling TSK_enable only if there exists a TSK_READY task whose priority is greater than the currently executing task.

**Constraints and Calling Context**

- Do not call any function that can cause the current task to block or otherwise affect the state of the scheduler within a TSK_disable/TSK_enable block. For example, SEM_pend (if timeout is non-zero), TSK_sleep, TSK_yield, and MEM_alloc can all cause blocking. Similarly, any MEM module call and any call that dynamically creates or deletes an object (XXX_create or XXX_delete) can affect the state of the scheduler. For a complete list, see the "Possible Context Switch" column in Section A.1, *Function Callability Table*.

- TSK_enable cannot be called from a SWI or HWI.

- TSK_enable cannot be called from the program’s main() function.

- Do not call TSK_enable when TSKs are already enabled. If you do so, the subsequent call to TSK_disable will not disable TSK processing.

**See Also**

- SEM Module
- TSK_disable
C Interface

Syntax

TSK_exit();

Parameters

Void

Return Value

Void

Description

TSK_exit terminates execution of the current task, changing its mode from TSK_RUNNING to TSK_TERMINATED. If all tasks have been terminated, or if all remaining tasks have their exitflag attribute set to FALSE, then DSP/BIOS terminates the program as a whole by calling the function SYS_exit with a status code of 0.

TSK_exit is automatically called whenever a task returns from its top-level function.

You can use Tconf to specify an application-wide Exit function that runs whenever a task is terminated. The default Exit function is a no-op function. The Exit function is called before the task has been blocked and marked TSK_TERMINATED. Any DSP/BIOS function can be called from an Exit function. Calling TSK_self within an Exit function returns the task being exited. Your Exit function declaration should be similar to the following:

Void myExitFxn(Void);

A task switch occurs when calling TSK_exit unless the program as a whole is terminated.

Constraints and Calling Context

- TSK_exit cannot be called from a SWI or HWI.
- TSK_exit cannot be called from the program's main() function.

See Also

MEM_free
TSK_create
TSK_delete
**TSK_getenv**  Get task environment pointer

**C Interface**

Syntax

```c
environ = TSK_getenv(task);
```

Parameters

- `TSK_Handle task;` /* task object handle */

Return Value

- `Ptr environ;` /* task environment pointer */

**Description**

TSK_getenv returns the environment pointer of the specified task. The environment pointer, environ, references an arbitrary application-defined data structure.

If your program uses multiple HOOK objects, HOOK_getenv allows you to get environment pointers you have set for a particular HOOK and TSK object combination.

**See Also**

- HOOK_getenv
- HOOK_setenv
- TSK_setenv
- TSK_seterr
- TSK_setpri
**TSK_geterr**  
*Get task error number*

### C Interface

**Syntax**

```c
errno = TSK_geterr(task);
```

**Parameters**

- `TSK_Handle task; /* task object handle */`

**Return Value**

- `Int errno; /* error number */`

### Description

Each task carries a task-specific error number. This number is initially SYS_OK, but it can be changed by `TSK_seterr`. `TSK_geterr` returns the current value of this number.

### See Also

- `SYS_error`
- `TSK_setenv`
- `TSK_seterr`
- `TSK_setpri`
**TSK_getname**  Get task name

**C Interface**

Syntax

```c
name = TSK_getname(task);
```

**Parameters**

- `TSK_Handle task;` /* task object handle */

**Return Value**

- `String name;` /* task name */

**Description**

`TSK_getname` returns the task’s name.

For tasks created with Tconf, the name is available to this function only if the "Allocate Task Name on Target" property is set to true for this task. For tasks created with `TSK_create`, `TSK_getname` returns the attrs.name field value, or an empty string if this attribute was not specified.

**See Also**

- `TSK_setenv`
- `TSK_seterr`
- `TSK_setpri`
**TSK_getpri**  Get task priority

### C Interface

**Syntax**

```c
priority = TSK_getpri(task);
```

**Parameters**

- `TSK_Handle task;` /* task object handle */

**Return Value**

- `Int priority;` /* task priority */

### Description

`TSK_getpri` returns the priority of task.

### See Also

- `TSK_setenv`
- `TSK_seterr`
- `TSK_setpri`
**TSK_getsts**  
Get the handle of the task’s STS object

**C Interface**

Syntax

```
sts = TSK_getsts(task);
```

Parameters

```
TSK_Handle task; /* task object handle */
```

Return Value

```
STS_Handle sts; /* statistics object handle */
```

**Description**

This function provides access to the task’s internal STS object. For example, you can want the program to check the maximum value to see if it has exceeded some value.

**See Also**

- TSK_deltatime
- TSK_settime
**TSK_isTSK**  
Check to see if called in the context of a TSK

**C Interface**

Syntax

```c
result = TSK_isTSK(Void);
```

Parameters

- `Void`

Return Value

- `Bool` `result; /* TRUE if in TSK context, FALSE otherwise */`

Reentrant

- yes

Description

This macro returns TRUE when it is called within the context of a TSK or IDL function. It returns FALSE in all other contexts.

`TSK_isTSK()` API returns TRUE when the current thread is neither a HWI nor a SWI. Thus, `TSK_isTSK()` returns TRUE when it is invoked within a task thread, `main()`, or a task switch hook.

In previous versions of DSP/BIOS, calling the context checking functions from `main()` resulted in TRUE for `HWI_isHWI()`. And, calling the context checking functions from a task switch hook resulted in TRUE for `SWI_isSWI()`. This is no longer the case; they are identified as part of the TSK context.

In applications that contain no task threads, `TSK_isTSK()` now returns TRUE from `main()` and from the IDL threads.

See Also

- `HWI_isHWI`
- `SWI_isSWI`
**TSK_itick**  
*Advance the system alarm clock (interrupt use only)*

**C Interface**

**Syntax**

```c
TSK_itick();
```

**Parameters**

`Void`

**Return Value**

`Void`

**Description**

TSK_itick increments the system alarm clock, and readies any tasks blocked on TSK_sleep or SEM_pend whose timeout intervals have expired.

**Constraints and Calling Context**

- TSK_itick cannot be called by a TSK object.
- TSK_itick cannot be called from the program’s main() function.
- When called within an HWI, the code sequence calling TSK_itick must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.

**See Also**

- SEM_pend
- TSK_sleep
- TSK_tick
TSK_self  
Returns handle to the currently executing task

C Interface

Syntax
    curtask = TSK_self();

Parameters
    Void

Return Value
    TSK_Handle curtask; /* handle for current task object */

Description
    TSK_self returns the object handle for the currently executing task. This function is useful when inspecting the object or when the current task changes its own priority through TSK_setpri.

    No task switch occurs when calling TSK_self.

See Also
    TSK_setpri
TSK_setenv  Set task environment

C Interface

Syntax
    TSK_setenv(task, environ);

Parameters
    TSK_Handle task;  /* task object handle */
    Ptr environ;      /* task environment pointer */

Return Value
    Void

Description
    TSK_setenv sets the task environment pointer to environ. The environment pointer, environ, references
an arbitrary application-defined data structure.

    If your program uses multiple HOOK objects, HOOK_setenv allows you to set individual environment
pointers for each HOOK and TSK object combination.

See Also
    HOOK_getenv
    HOOK_setenv
    TSK_getenv
    TSK_geterr
TSK_seterr  Set task error number

C Interface

Syntax

TSK_seterr(task, errno);

Parameters

TSK_Handle task; /* task object handle */
Int errno; /* error number */

Return Value

Void

Description

Each task carries a task-specific error number. This number is initially SYS_OK, but can be changed to
errno by calling TSK_seterr. TSK_geterr returns the current value of this number.

See Also

TSK_getenv
TSK_geterr
**TSK_setpri**  
*Set a task’s execution priority*

### C Interface

**Syntax**

```c
oldpri = TSK_setpri(task, newpri);
```

**Parameters**

- `TSK_Handle task; /* task object handle */`
- `Int newpri; /* task’s new priority */`

**Return Value**

- `Int oldpri; /* task’s old priority */`

### Description

`TSK_setpri` sets the execution priority of task to `newpri`, and returns that task’s old priority value. Raising or lowering a task’s priority does not necessarily force preemption and re-scheduling of the caller: tasks in the TSK_BLOCKED mode remain suspended despite a change in priority; and tasks in the TSK_READY mode gain control only if their (new) priority is greater than that of the currently executing task.

The maximum value of `newpri` is `TSK_MAXPRI(15)`. If the minimum value of `newpri` is `TSK_MINPRI(0)`. If `newpri` is less than 0, the task is barred from further execution until its priority is raised at a later time by another task; if `newpri` equals `TSK_MAXPRI`, execution of the task effectively locks out all other program activity, except for the handling of interrupts.

The current task can change its own priority (and possibly preempt its execution) by passing the output of `TSK_self` as the value of the task parameter.

A context switch occurs when calling `TSK_setpri` if a task makes its own priority lower than the priority of another currently ready task, or if the currently executing task makes a ready task’s priority higher than its own priority. `TSK_setpri` can be used for mutual exclusion.

### Constraints and Calling Context

- `newpri` must be less than or equal to `TSK_MAXPRI`.
- The task cannot be `TSK_TERMINATED`.
- The new priority should not be zero (0). This priority level is reserved for the `TSK_idle` task.

### See Also

- `TSK_self`
- `TSK_sleep`
TSK_settime

Reset task statistics previous value to current time

C Interface

Syntax

TSK_settime(task);

Parameters

TSK_Handle task; /* task object handle */

Return Value

Void

Description

Your application can call TSK_settime before a task enters its processing loop in order to ensure your first call to TSK_deltatime is as accurate as possible and doesn’t reflect the time difference since the time the task was created. However, it is only necessary to call TSK_settime once for initialization purposes. After initialization, DSP/BIOS sets the time value of the task’s STS object every time the task is made ready to run.

TSK statistics are handled differently than other statistics because TSK functions typically run an infinite loop that blocks when waiting for other threads. In contrast, HWI and SWI functions run to completion without blocking. Because of this difference, DSP/BIOS allows programs to identify the “beginning” of a TSK function’s processing loop by calling TSK_settime and the “end” of the loop by calling TSK_deltatime.

For example, a loop within the task can look something like the following:

Void task
{
    'do some startup work'

    /* Initialize task's STS object to current time */
    TSK_settime(TSK_self());

    for (;;) {
        /* Get data */
        SIO_get(...);

        'process data'

        /* Get time difference and
        add it to task's STS object */
        TSK_deltatime(TSK_self());
    }
}

In the previous example, the task blocks on SIO_get and the device driver posts a semaphore that readies the task. DSP/BIOS sets the task’s statistics object with the current time when the semaphore becomes available and the task is made ready to run. Thus, the call to TSK_deltatime effectively measures the processing time of the task.
 Constraints and Calling Context

- TSK_settime cannot be called from the program's main() function.
- The results of calls to TSK_deltatime and TSK_settime are displayed in the Statistics View only if Enable TSK accumulators is selected within the RTA Control Panel.

See Also

- TSK_deltatime
- TSK_getsts
**C Interface**

Syntax

```
TSK_sleep(nticks);
```

Parameters

- `Uns nticks; /* number of system clock ticks to sleep */`

Return Value

Void

**Description**

`TSK_sleep` changes the current task's mode from TSK_RUNNING to TSK_BLOCKED, and delays its execution for `nticks` increments of the system clock. The actual time delayed can be up to 1 system clock tick less than timeout due to granularity in system timekeeping.

After the specified period of time has elapsed, the task reverts to the TSK_READY mode and is scheduled for execution.

A task switch always occurs when calling `TSK_sleep` if `nticks` > 0.

**Constraints and Calling Context**

- `TSK_sleep` cannot be called from a SWI or HWI, or within a TSK_disable / TSK_enable block.
- `TSK_sleep` cannot be called from the program's main() function.
- `TSK_sleep` should not be called from within an IDL function. Doing so prevents analysis tools from gathering run-time information.
- `nticks` cannot be SYS_FOREVER.
**TSK_stat**  
*Retrieve the status of a task*

**C Interface**

**Syntax**

```c
TSK_stat(task, statbuf);
```

**Parameters**

- `TSK_Handle task;` /* task object handle */
- `TSK_Stat *statbuf;` /* pointer to task status structure */

**Return Value**

Void

**Description**

TSK_stat retrieves attribute values and status information about a task.

Status information is returned through `statbuf`, which references a structure of type `TSK_Stat` defined as follows:

```c
struct TSK_Stat {     /* task status structure */
    TSK_Attrs  attrs; /* task attributes */
    TSK_Mode   mode;  /* task execution mode */
    Ptr        sp;    /* task stack pointer */
    #ifdef _55_
    Ptr        ssp;   /* task system stack pointer */
    #endif
    size_t     used;  /* task stack used */
    #ifdef _55_
    size_t     sysused; /* task system stack used */
    #endif
};
```

When a task is preempted by a software or hardware interrupt, the task execution mode returned for that task by TSK_stat is still TSK_RUNNING because the task runs when the preemption ends.

The current task can inquire about itself by passing the output of TSK_self as the first argument to TSK_stat. However, the task stack pointer (sp) in the TSK_Stat structure is the value from the previous context switch. In addition, the task system stack pointer (ssp) provided for ‘C55x is invalid when calling TSK_stat for the current task.

TSK_stat has a non-deterministic execution time. As such, it is not recommended to call this API from SWIs or HWIs.

**Constraints and Calling Context**

- `statbuf` cannot be NULL.

**See Also**

TSK_create
**TSK_tick**  
*Advance the system alarm clock*

**C Interface**

**Syntax**

```c
TSK_tick();
```

**Parameters**

- Void

**Return Value**

- Void

**Description**

TSK_tick increments the system clock, and readies any tasks blocked on TSK_sleep or SEM_pend whose timeout intervals have expired. TSK_tick can be invoked by an HWI or by the currently executing task. The latter is particularly useful for testing timeouts in a controlled environment.

A task switch occurs when calling TSK_tick if the priority of any of the readied tasks is greater than the priority of the currently executing task.

**Constraints and Calling Context**

- When called within an HWI, the code sequence calling TSK_tick must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.

**See Also**

- CLK Module
- SEM_pend
- TSK_itick
- TSK_sleep
**TSK_time**

*Return current value of system clock*

**C Interface**

**Syntax**

```c
curtime = TSK_time();
```

**Parameters**

Void

**Return Value**

Uns  

```c
curtime; /* current time */
```

**Description**

TSK_time returns the current value of the system alarm clock.

Note that since the system clock is usually updated asynchronously via TSK_itick or TSK_tick, curtime can lag behind the actual system time. This lag can be even greater if a higher priority task preempts the current task between the call to TSK_time and when its return value is used. Nevertheless, TSK_time is useful for getting a rough idea of the current system time.
**TSK_yield**  
*Yield processor to equal priority task*

**C Interface**

**Syntax**

```c
TSK_yield();
```

**Parameters**

- **Void**

**Return Value**

- **Void**

**Description**

TSK_yield yields the processor to another task of equal priority.

A task switch occurs when you call TSK_yield if there is an equal priority task ready to run.

Tasks of higher priority preempt the currently running task without the need for a call to TSK_yield. If only lower-priority tasks are ready to run when you call TSK_yield, the current task continues to run. Control does not pass to a lower-priority task.

**Constraints and Calling Context**

- When called within an HWI, the code sequence calling TSK_yield must be either wrapped within an HWI_enter/HWI_exit pair or invoked by the HWI dispatcher.
- TSK_yield cannot be called from the program’s main() function.

**See Also**

- TSK_sleep
2.30 std.h and stdlib.h functions

This section contains descriptions of special utility macros found in std.h and DSP/BIOS standard library functions found in stdlib.h.

Macros

- **ArgToInt**: Cast an Arg type parameter as an integer type.
- **ArgToPtr**: Cast an Arg type parameter as a pointer type.

Functions

- **atexit**: Register an exit function.
- **calloc**: Allocate and clear memory.
- **exit**: Call the exit functions registered by atexit.
- **free**: Free memory.
- **getenv**: Get environmental variable.
- **malloc**: Allocate memory.
- **realloc**: Reallocate a memory packet.

Syntax

```c
#include <std.h>
ArgToInt(arg)
ArgToPtr(arg)
```

```c
#include <stdlib.h>
int atexit(void (*fcn)(void));
void *calloc(size_t nobj, size_t size);
void exit(int status);
void free(void *p);
char *getenv(char *name);
void *malloc(size_t size);
void *realloc(void *p, size_t size);
```

Description

The DSP/BIOS library contains some C standard library functions which supersede the library functions bundled with the C compiler. These functions follow the ANSI C specification for parameters and return values. Consult Kernighan and Ritchie for a complete description of these functions.

The functions calloc, free, malloc, and realloc use MEM_alloc and MEM_free (with segid = Segment for malloc/free) to allocate and free memory.

getenv uses the _environ variable defined and initialized in the boot file to search for a matching environment string.

exit calls the exit functions registered by atexit before calling SYS_exit.
Note: RTS Functions Callable from TSK Threads Only. Many runtime support (RTS) functions use lock and unlock functions to prevent reentrancy. However, DSP/BIOS SWI and HWI threads cannot call LCK_pend and LCK_post. As a result, RTS functions that call LCK_pend or LCK_post must not be called in the context of a SWI or HWI thread. For a list of RTS functions that should not be called from a SWI or an HWI function, see “LCK_pend” on page 181.

To determine whether a particular RTS function uses LCK_pend, refer to the source code for that function shipped with Code Composer Studio. The following table shows some of the RTS functions that call LCK_pend in certain versions of Code Composer Studio:

<table>
<thead>
<tr>
<th>Function</th>
<th>Function</th>
<th>Function</th>
<th>Function</th>
</tr>
</thead>
<tbody>
<tr>
<td>fprintf</td>
<td>printf</td>
<td>vfprintf</td>
<td>sprintf</td>
</tr>
<tr>
<td>vprintf</td>
<td>vsprintf</td>
<td>clock</td>
<td>strftime</td>
</tr>
<tr>
<td>minit</td>
<td>malloc</td>
<td>realloc</td>
<td>free</td>
</tr>
<tr>
<td>calloc</td>
<td>rand</td>
<td>srand</td>
<td>getenv</td>
</tr>
</tbody>
</table>

The C++ new operator calls malloc, which in turn calls LCK_pend. As a result, the new operator cannot be used in the context of a SWI or HWI thread.
This appendix provides tables describing TMS320C55x errors and function callability.

### A.1 Function Callability Table

The following table indicates what types of threads can call each of the DSP/BIOS functions. The Possible Context Switch column indicates whether another thread may be run as a result of this function. For example, the function may block on a resource or it may make another thread ready to run. The Possible Context Switch column does not indicate whether the function disables interrupts that might schedule higher-priority threads.

**Table A-1 Function Callability**

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<th>Callable by SWIs?</th>
<th>Callable by HWIs?</th>
<th>Possible Context Switch?</th>
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### Function Callability Table

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<td>TRC_query</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_checkstacks</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>TSK_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_delete</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>TSK_deltatime</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>TSK_disable</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>TSK_enable</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>TSK_exit</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>TSK_getenv</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_geterror</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_getname</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_getpriority</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_getstats</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_isTSK</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_itick</td>
<td>No</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_self</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>TSK_setenv</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_seterror</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_setpriority</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_settime</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>TSK_sleep</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>TSK_stat</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_tick</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>TSK_time</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>TSK_yield</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
</tbody>
</table>

**Note:** *See the appropriate API reference page for more information.*
### Table A-2 RTS Function Calls

<table>
<thead>
<tr>
<th>Function</th>
<th>Callable by TSKs?</th>
<th>Callable by SWIs?</th>
<th>Callable by HWIs?</th>
<th>Possible Context Switch?</th>
</tr>
</thead>
<tbody>
<tr>
<td>calloc</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>clock</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>fprintf</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>free</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>getenv</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>malloc</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>minit</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>printf</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>rand</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>realloc</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>sprintf</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>srand</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>strftime</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>vfprintf</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>vprintf</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
<tr>
<td>vsprintf</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
</tr>
</tbody>
</table>

Note: *See Section 2.30, std.h and stdlib.h functions, page 2-482 for more information.

### A.2 DSP/BIOS Error Codes

#### Table A-3 Error Codes

<table>
<thead>
<tr>
<th>Name</th>
<th>Value</th>
<th>SYS_Errors[Value]</th>
</tr>
</thead>
<tbody>
<tr>
<td>SYS_OK</td>
<td>0</td>
<td>&quot;(SYS_OK)&quot;</td>
</tr>
<tr>
<td>SYS_EALLOC</td>
<td>1</td>
<td>&quot;(SYS_EALLOC): segid = %d, size = %u, align = %u&quot;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Memory allocation error.</td>
</tr>
<tr>
<td>SYS_EFREE</td>
<td>2</td>
<td>&quot;(SYS_EFREE): segid = %d, ptr = ox%x, size = %u&quot;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>The memory free function associated with the indicated memory segment was unable to free the indicated size of memory at the address indicated by ptr.</td>
</tr>
<tr>
<td>SYS_ENODEV</td>
<td>3</td>
<td>&quot;(SYS_ENODEV): device not found&quot;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>The device being opened is not configured into the system.</td>
</tr>
<tr>
<td>SYS_EBUSY</td>
<td>4</td>
<td>&quot;(SYS_EBUSY): device in use&quot;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>The device is already opened by the maximum number of users.</td>
</tr>
<tr>
<td>SYS_EINVAL</td>
<td>5</td>
<td>&quot;(SYS_EINVAL): invalid parameter&quot;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>An invalid parameter was passed.</td>
</tr>
<tr>
<td>SYS_EBADIO</td>
<td>6</td>
<td>&quot;(SYS_EBADIO): device failure&quot;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>The device was unable to support the I/O operation.</td>
</tr>
<tr>
<td>SYS_EMODE</td>
<td>7</td>
<td>&quot;(SYS_EMODE): invalid mode&quot;</td>
</tr>
<tr>
<td></td>
<td></td>
<td>An attempt was made to open a device in an improper mode; e.g., an attempt to open an input device for output.</td>
</tr>
<tr>
<td>Name</td>
<td>Value</td>
<td>SYS_Errors[Value]</td>
</tr>
<tr>
<td>--------------</td>
<td>-------</td>
<td>----------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>SYS_EDOMAIN</td>
<td>8</td>
<td>&quot;SYS_EDOMAIN): domain error&quot; &lt;br&gt;Used by SPOX-MATH when type of operation does not match vector or filter type.</td>
</tr>
<tr>
<td>SYS_ETIMEOUT</td>
<td>9</td>
<td>&quot;SYS_ETIMEOUT): timeout error&quot; &lt;br&gt;Used by device drivers to indicate that reclaim timed out.</td>
</tr>
<tr>
<td>SYS_EEOF</td>
<td>10</td>
<td>&quot;SYS_EEOF): end-of-file error&quot; &lt;br&gt;Used by device drivers to indicate the end of a file.</td>
</tr>
<tr>
<td>SYS_EDEAD</td>
<td>11</td>
<td>&quot;SYS_EDEAD): previously deleted object&quot;&lt;br&gt;An attempt was made to use an object that has been deleted.</td>
</tr>
<tr>
<td>SYS_EBADOBJ</td>
<td>12</td>
<td>&quot;SYS_EBADOBJ): invalid object&quot;&lt;br&gt;An attempt was made to use an object that does not exist.</td>
</tr>
<tr>
<td>SYS_ENOTIMPL</td>
<td>13</td>
<td>&quot;SYS_ENOTIMPL): action not implemented&quot;&lt;br&gt;An attempt was made to use an action that is not implemented.</td>
</tr>
<tr>
<td>SYS_ENOTFOUND</td>
<td>14</td>
<td>&quot;SYS_ENOTFOUND): resource not found&quot;&lt;br&gt;An attempt was made to use a resource that could not be found.</td>
</tr>
<tr>
<td>SYS_EUSER</td>
<td>&gt;=256</td>
<td>&quot;SYS_EUSER): &lt;user-defined string&gt;&quot;&lt;br&gt;User-defined error.</td>
</tr>
</tbody>
</table>
This appendix provides tables describing the TMS320C55x register conventions in terms of preservation across multi-threaded context switching and preconditions.

<table>
<thead>
<tr>
<th>Topic</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>B.1 Overview</td>
<td>493</td>
</tr>
<tr>
<td>B.2 Register Conventions</td>
<td>493</td>
</tr>
<tr>
<td>B.3 Status Register Conventions</td>
<td>495</td>
</tr>
</tbody>
</table>

**B.1 Overview**

In a multi-threaded application using DSP/BIOS, it is necessary to know which registers can or cannot be modified. Furthermore, users need to understand which registers are preserved across task context switches and interrupts.

**B.2 Register Conventions**

The following definitions describe the various possible register handling behaviors:

- **H - HWI.** These registers are saved/restored by the HWI dispatcher and HWI_enter/HWI_exit. In general, the "child" function register set (as defined by the C compiler) is not preserved by the HWI dispatcher or the HWI_enter macro since it is assumed that the HWI function called is written in C and will therefore preserve any "child" registers it uses.

- **T - TSK.** These registers are saved/restored during a TSK context switch. In general, only the "child" function register set is actively preserved in the task's execution context during a synchronous context switch. This is because it is assumed that the function that invoked the task switch has already saved its "parent" register set. Task context switches that result from preemption by an interrupt will preserve the entire processor state so that execution can safely resume at the instruction following the interrupted instruction.

- **G - Global.** These registers are shared across all threads in the system. They are not saved and restored during interrupt handling nor during task context switching. To make a temporary change, save the register, make the change, and then restore it.

- **I - Initialized register.** These registers are set to a particular value during HWI processing and are restored to their incoming value upon return to the interrupted routine.
<table>
<thead>
<tr>
<th>Register</th>
<th>Register Name</th>
<th>Type</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>AC0-AC3</td>
<td>Accumulators</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>(X)AR0-(X)AR4</td>
<td>Auxiliary Registers</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>(X)AR5-(X)AR7</td>
<td>Auxiliary Registers</td>
<td>T</td>
<td>These &quot;child&quot; registers are presumed to be saved by an HWI that uses them.</td>
</tr>
<tr>
<td>BK03, BK47, BKC</td>
<td>Circular Buffer Size Registers</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>BRC0, BRC1</td>
<td>Block-repeat counters</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>BRS1</td>
<td>BRC1 save register</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>BSA01, BSA23, BSA45, BSA67, BSAC</td>
<td>Circular Buffer Start Address Registers</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>(X)CDP</td>
<td>Coefficient Data Pointer</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>CFCT</td>
<td>Control-flow context register</td>
<td>H, T</td>
<td></td>
</tr>
<tr>
<td>CSR</td>
<td>Computed Single Repeat</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>DBIER0, DBIER1</td>
<td>Debug Interrupt Enable Registers</td>
<td>G</td>
<td>DSP/BIOS does not touch these registers.</td>
</tr>
<tr>
<td>(X)DP</td>
<td>Data Page Register</td>
<td>H, T</td>
<td></td>
</tr>
<tr>
<td>IER0, IER1</td>
<td>Interrupt Enable Registers</td>
<td>I</td>
<td>Modified by interrupt handlers, and may not be fully restored upon return.</td>
</tr>
<tr>
<td>IFR0, IFR1</td>
<td>Interrupt Flag Registers</td>
<td>G</td>
<td>Initialized by DSP/BIOS at boot time, untouched thereafter.</td>
</tr>
<tr>
<td>IVPD, IVPH</td>
<td>Interrupt Vector Table Pointers</td>
<td>G</td>
<td>Initialized by DSP/BIOS at boot time, untouched thereafter.</td>
</tr>
<tr>
<td>PC</td>
<td>Program Counter</td>
<td>H, T</td>
<td></td>
</tr>
<tr>
<td>RPTC</td>
<td>Single Repeat Counter</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>RSA0, RSA1</td>
<td>Block-repeat start address registers</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>REA0, REA1</td>
<td>Block-repeat end address registers</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>RETA</td>
<td>Return Address Register</td>
<td>H,T</td>
<td></td>
</tr>
<tr>
<td>(X)SP</td>
<td>Stack Pointer</td>
<td>H,T</td>
<td>Changed to ISR SP during HWI execution, restored upon return.</td>
</tr>
<tr>
<td>(X)SSP</td>
<td>System Stack Pointer</td>
<td>H,T</td>
<td>Changed to ISR SSP during HWI execution, restored upon return.</td>
</tr>
<tr>
<td>T0, T1</td>
<td>Temporary Registers</td>
<td>H,T</td>
<td></td>
</tr>
<tr>
<td>T2, T3</td>
<td>Temporary Registers</td>
<td>T</td>
<td>These &quot;child&quot; registers are presumed to be saved by an HWI that uses them.</td>
</tr>
<tr>
<td>TRN0, TRN1</td>
<td>Transition Registers</td>
<td>H</td>
<td></td>
</tr>
</tbody>
</table>
B.3 Status Register Conventions

The status registers (ST0-ST2) are automatically preserved by hardware during interrupt processing such that upon return from an HWI, these status registers are returned to the state they were in prior to the interrupt. ST3 bits are generally propagated except as shown below.

At system boot time and prior to entering an HWI thread handled by the DSP/BIOS HWI dispatcher or coded using HWI_enter/HWI_exit, some status bits are configured by DSP/BIOS in order to establish a C-compatible and DSP/BIOS-compatible runtime context for DSP/BIOS functions and HWIs. These settings are consistent with those presumed by the C/C++ compiler.

The following definitions describe the various possible status register bit handling behaviors:

- **X - Untouched.** DSP/BIOS does not manipulate these bits nor depend on their values.
- **B-n - BIOS.** DSP/BIOS sets the bit(s) to the value n at boot time and before entering a HWI that uses the HWI dispatcher or HWI_enter/HWI_exit. Proper operation of DSP/BIOS is not guaranteed if an application changes these status bit settings.
- **P - Propagated.** These bits are not restored upon returning from an interrupt or task context switch. Instead, they are propagated through all context switches. (That is, once they are changed, they remain changed through all contexts.)

<table>
<thead>
<tr>
<th>Register</th>
<th>Status Bit</th>
<th>Status Bit Name</th>
<th>Type</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>ST0</td>
<td>AC0V2</td>
<td>AC2 overflow flag</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST0</td>
<td>AC0V3</td>
<td>AC3 overflow flag</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST0</td>
<td>TC1</td>
<td>Test/control flag 1</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST0</td>
<td>TC2</td>
<td>Test/control flag 2</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST0</td>
<td>CARRY</td>
<td>Carry Bit</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>BRAF</td>
<td>Block-repeat active flag</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>CPL</td>
<td>Compiler mode</td>
<td>B-1</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>XF</td>
<td>External flag</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST1</td>
<td>HM</td>
<td>Hold mode</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST1</td>
<td>INTM</td>
<td>Interrupt Mask</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>M40</td>
<td>Computation mode for the D unit</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>SATD</td>
<td>Saturation mode for the D unit</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>SXMD</td>
<td>Sign-extension mode for the D unit</td>
<td>B-1</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>C16</td>
<td>Dual 16-bit arithmetic mode</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>FRCT</td>
<td>Fractional mode</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST1</td>
<td>C54CM</td>
<td>C54x-compatible mode</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>Register</td>
<td>Status Bit</td>
<td>Status Bit Name</td>
<td>Type</td>
<td>Notes</td>
</tr>
<tr>
<td>----------</td>
<td>------------</td>
<td>-----------------------------------------</td>
<td>------</td>
<td>----------------------------</td>
</tr>
<tr>
<td>ST2</td>
<td>ARMS</td>
<td>AR mode switch</td>
<td>B-1</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST2</td>
<td>DBGM</td>
<td>Debug mode</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST2</td>
<td>EALLOW</td>
<td>Emulation access enable</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST2</td>
<td>RDM</td>
<td>Rounding mode</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST2</td>
<td>CDPLC</td>
<td>CDP linear/circular configuration</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST2</td>
<td>AR0-7LC</td>
<td>ARn linear/circular configuration</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST3</td>
<td>CAFRZ</td>
<td>Cache freeze</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST3</td>
<td>CAEN</td>
<td>Cache enable</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST3</td>
<td>CACLR</td>
<td>Cache clear</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST3</td>
<td>HINT</td>
<td>Host interrupt</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST3</td>
<td>CBERR</td>
<td>CPU bus error</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST3</td>
<td>MPNMC</td>
<td>Microprocessor/Microcomputer mode</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST3</td>
<td>SATA</td>
<td>Saturation mode for A unit</td>
<td>B-0</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST3</td>
<td>CLKOFF</td>
<td>CLKOUT disable</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>ST3</td>
<td>SMUL</td>
<td>Saturation-on-multiplication mode</td>
<td>B-1</td>
<td>Restored after int</td>
</tr>
<tr>
<td>ST3</td>
<td>SST</td>
<td>Saturate-on-store mode</td>
<td>X</td>
<td>Restored after int</td>
</tr>
</tbody>
</table>
This appendix describes things you need to know about DSP/BIOS in order to use it with the OMAP 2320 platform.

### C.1 Overview
DSP/BIOS has been enhanced to provide seamless support for the core timers and Level 2 Interrupt Controller (L2IC) present within the OMAP 2320. The CLK module functionality is now driven by the core timers. The HWI module APIs can define and manipulate level 2 interrupts in addition to level 1 interrupts.

The OMAP 2320 is part of a series of next generation "OMAP 4" devices. This series encompasses the 23xx and 24xx devices.

### C.2 OMAP 2320 and the CLK Module
Changes and enhancements have been made to the DSP/BIOS CLK module to enable the use of OMAP 2320 core timers. The OMAP 2320 has 2 core timers, which can be use to drive the low- and high-resolution DSP/BIOS clock functionality.

#### C.2.1 Static Configuration
By default, the low-resolution CLK function (see CLK_gettime) is enabled and assigned to core Timer 0. Alternately, you can configure Timer 1 for this function. To change the configuration, add the following line to your Tconf configuration file:

```
bios.CLK.TIMERSSELECT = "Timer 1"; // "Timer 0" or "Timer 1"
```
You can disable the low-resolution CLK function using the following Tconf script commands:

```c
bios.CLK.ENABLECLK = 0;
bios.PRD.USECLK = 0;
```

By default, the high-resolution CLK function (see CLK_gethtime) is enabled and derived from the low-resolution timer. You can disable this function with the following configuration script command:

```c
bios.CLK.ENABLEHTIME = 0;    // 0 (disabled) or 1 (enabled)
```

In the Gconf configuration tool, the CLK properties for the OMAP 2320 are as follows:

![CLK - Clock Manager Properties](image)

C.3 OMAP 2320 and the HWI Module

With the introduction of the OMAP family of dual-core ARM + 'C55x devices, many more interrupt sources have been defined than can be terminated on the legacy 'C55x level 1 interrupt controller, which has a limit of 32 interrupts. To accommodate additional interrupt sources, a new interrupt mechanism has been provided in hardware: the "Level 2 Interrupt Controller" (L2IC).

The additional interrupts are prioritized and multiplexed by the Level 2 Interrupt Controller onto two dedicated level 1 interrupts. DSP/BIOS internally configures all 32 level 2 interrupts to terminate on the single level 1 FIQ interrupt. In the 23xx/24xx OMAP family, many peripherals that formerly interrupted the DSP at level 1 have been moved to level 2.

The DSP/BIOS interface to this interrupt controller is called the Level 2 Interrupt Manager (L2IM). The complexities of the L2IM are concealed by reusing and enhancing existing HWI module APIs. As a result, very few new API elements are needed.
The following sections describe extensions made to the HWI module to support the OMAP 2320.

C.3.1 Level 2 Interrupt Controller Base Address

By default, the Level 2 Interrupt Controller (L2IC) resides at data memory address 0x7c4800. This coincides with the reset IOMA value of 0x3e. The IO MAP (IOMA) base address is the page index used to access DSP I/O space addresses from DSP memory space.

If you modify IOMA for any reason, you need to tell DSP/BIOS the new base address for the L2IC. The following Tconf configuration property is provided for this purpose:

```
bios.HWI.INTC_BASE = 0x7c4800; // 0x7c4800 is default
```

C.3.2 Level 2 Interrupt Objects and Properties

There are 64 new HWI interrupt objects defined to correspond to level 2 interrupts 0 through 63. These objects are named HWI_L2_INT0 through HWI_L2_INT63.

The following parameters have been added to HWI interrupt objects to allow for static configuration of the level 2 interrupt priorities, mirmask, and mir1mask:

- **iMirMask**. This property is valid for both level 1 and 2 interrupts. It specifies which level 2 interrupts the dispatcher should disable before calling this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptMask0 and interruptMask1, which deal with level 1 interrupts.)
  - The "self" option causes the dispatcher to disable only the current interrupt and causes the appropriate interruptBitMask0, interruptBitMask1, mirmask, and mir1mask values to be generated for the interrupt being configured.
  - The "all" option disables all level 2 interrupts.
  - The "none" option disables no level 2 interrupts.
  - The "bitmask" option causes the mirmask and mir1mask properties to be used to specify the level 2 interrupts to disable.

- **mirmask**. This property is valid for both level 1 and 2 interrupts. It defines a bitmask of level 2 interrupts 0-31 to be disabled by the DSP/BIOS HWI dispatcher when executing this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptBitMask0, which masks level 1 interrupts.)

- **mir1mask**. This property is valid for both level 1 and 2 interrupts. It defines a bitmask of level 2 interrupts 32-63 to be disabled by the DSP/BIOS HWI dispatcher when executing this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptBitMask1, which masks level 1 interrupts.)

- **priority**. Sets the priority from 0 to 63 of a level 2 interrupt. Zero is the highest priority. The default priority for a level 2 interrupt matches its interrupt number. Although this field exists for all HWI interrupt objects, it cannot be configured for level 1 interrupts. You can change the priority at run-time using the C55_l2SetIntPriority API.
The following Tconf statements configure the level 2 interrupt 0 to have a priority of 63 (lowest priority) and a mirmask of 0xffffffff (no other level 2 interrupts enabled while servicing this interrupt):

```c
// valid priority values: 0-63
bios.HWI_L2_INT0.priority = 63;

// use dispatcher and enable setting iMirMask, mirmask
bios.HWI_L2_INT0.useDispatcher = true;

// "bitmask" enables writing to mirmask and mir1mask
bios.HWI_L2_INT0.iMirMask = "bitmask";

// no other L2 interrupts while servicing HWI_L2_INT0
bios.HWI_L2_INT0.mirmask = 0xffffffff;

// no other L2 interrupts while servicing HWI_L2_INT0
bios.HWI_L2_INT0.mir1mask = 0xffffffff;
```

### C.3.3 HWI_dispatchPlug API

The range of vector IDs allowed is extended from 0-31 to 0-95. The IDs 32-95 correspond to level 2 interrupts 0-63 respectively. The c55.h file now includes definitions for C55_L2_INT0 through C55_L2_INT63, which map to vector IDs 32-95.

The HWI_Attrs structure used by HWI_dispatchPlug has been expanded to include two additional fields: mirmask and mir1mask. Each of these fields contains a 32-bit mask to specify which of the additional level 2 interrupts to mask during the interrupt. The mirmask field controls L2 interrupts 0-31. The mir1mask field controls L2 interrupts 32-63.

```c
typedef struct HWI_Attrs {
    Uns ier0mask;  // Level 1 interrupt masks
    Uns ier1mask;
    Arg arg;       // fxn arg (default = 0)
    LgUns mirmask; // Level 2 interrupt mask 0-31
    LgUns mir1mask; // Level 2 interrupt mask 32-63
} HWI_Attrs;
```

The default values of mirmask and mir1mask (provided by HWI_ATTRS) for all interrupts is consistent with the “self” setting.

### C.3.4 HWI_enter and HWI_exit APIs

The HWI_enter and HWI_exit assembly language macros have been enhanced to support selective interrupt nesting control of level 2 interrupts. This matches the way level 1 interrupts are controlled.

The argument lists for these macros have two additional interrupt mask arguments. In HWI_enter, these 32-bit bitmasks define which level 2 interrupts are to be masked while executing the HWI body. In HWI_exit, these masks define which level 2 interrupts are to be restored to their prior state before returning from the interrupt.
The OMAP 2320 macro invocation syntax is shown below:

```
HWI_enter C55_AR_DR_X_MASK, C55_ACC_X_MASK, C55_MISC1_X_MASK, C55_MISC2_X_MASK,
C55_MISC3_X_MASK, IER0DISABLEMASK, IER1DISABLEMASK, MIRDISABLEMASK, MIR1DISABLEMASK
```

```
HWI_exit C55_AR_DR_X_MASK, C55_ACC_X_MASK, C55_MISC1_X_MASK, C55_MISC2_X_MASK,
C55_MISC3_X_MASK, IER0RESTOREMASK, IER1RESTOREMASK, MIRRESTOREMASK, MIR1RESTOREMASK
```

C.4 OMAP 2320 and the C55 Module

In addition to extensions to the HWI module, the following extensions have been made to the C55 module to support the OMAP 2320 level 2 interrupts.

C.4.1 C55_plug API

For C55_plug, the range of vector IDs is extended from 0-31 to 0-95. The IDs 32-95 correspond to level 2 interrupts 0-63 respectively. The c55.h file now includes definitions C55_L2_INT0 through C55_L2_INT63 which map to vector IDs 32-95.

C.4.2 New APIs

The following APIs have been added to the C55 module for use with OMAP 2320. For details, see the topics for these APIs in the alphabetic reference in Chapter 2.

- C55_disableInt. Disable an individual interrupt.
- C55_enableInt. Enable an individual interrupt.
- C55_l2AckInt. Explicitly acknowledge an L2 interrupt
- C55_l2DisableMIR. Disable a mask of L2 interrupts
- C55_l2EnableMIR. Enable a mask of L2 interrupts
- C55_l2SetIntPriority. Set the priority of a L2 interrupt

C.5 Building DSP/BIOS Applications for OMAP 2320

In order for the proper DSP/BIOS header files to be used during the build process, you must define the symbol "_2320_" at assembly time.

If you are building from the command line, add the following option to your assembler command line:

```
d_2320_
```

If you are building with CCS, follow these steps:

1. Open the application's CCS project.
2. Choose Project->Build Options to open the Build Options dialog.
3. Go to the Compiler tab and choose the Assembly category
4. Add _2320_ to the “Pre-Define NAME (-ad)” field.
5. Click OK.
C.6 Usage Examples

The following examples provide examples that use the HWI and C55 APIs related to the OMAP 2320.

C.6.1 Installing and Enabling a Single Level 2 Interrupt

This C code example plugs and enables the 23xx Level 2 interrupt #1.

```c
/*
 * ======== l2_example1.c ========
 * DSP/BIOS Level 2 interrupt example
 * /

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void myIsr (Arg id)
{
    LOG_printf(&trace, "My l2 ISR %d", ArgToInt(id));
}

void main ()
{
    HWI_Attrs attrs = HWI_ATTRS;

    // pass vector ID to myIsr
    attrs.arg = (Arg)C55_L2_INT1;

    // Plug Level 2 Interrupt #1 Vector
    HWI_dispatchPlug(C55_L2_INT1, (Fxn)myIsr, &attrs);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}
```
This C code example plugs and enables level 2 interrupts numbers 10, 11, 12, and 13 and sets their priority levels to 0, 1, 2, 3 respectively (0 = highest priority). The default interrupt nesting behavior (all other interrupts enabled while l2FiqFunc is called) is configured.

```c
#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void l2FiqFunc(Arg id)
{
    LOG_printf(&trace, "l2_fiq %d\n", ArgToInt(id)&32);
}

void main()
{
    HWI_Attrs attrs;
    attrs.arg = (Arg)C55_L2_INT10;
    HWI_dispatchPlug( C55_L2_INT10, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT10, 0);

    attrs.arg = (Arg)C55_L2_INT11;
    HWI_dispatchPlug( C55_L2_INT11, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT11, 1);

    attrs.arg = (Arg)C55_L2_INT12;
    HWI_dispatchPlug( C55_L2_INT12, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT12, 2);

    attrs.arg = (Arg)C55_L2_INT13;
    HWI_dispatchPlug( C55_L2_INT13, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT13, 3);

    C55_l2EnableMIR(0x00003c00);
}
```
C.6.3 Enabling an L2 Interrupt Using "interrupt" Keyword

This C code example plugs and enables OMAP 23xx level 2 interrupt number 1.

```
/*
 * ======== l2_example3.c ========
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

interrupt void myIsr ()
{
    // Acknowledge this level 2 interrupt to the L2IC
    C55_l2AckInt();

    // ...
    // Your code here
    // ...
}

Void main ()
{
    // Plug Level 2 Interrupt #1 Vector
    C55_plug(C55_L2_INT1, (Fxn)myIsr);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}
```
C.6.4  Assembly Language ISR Using HWI_enter, HWI_exit

This assembly code example uses the MIR mask arguments.

;#
;# DSP/BIOS Level 2 interrupt example
;#

; Include files
.include log.h55
.include hwi.h55
.include c55.h55

.global _l2FiqFunc
.global _intCount
.ref _trace
.ref _reportInfo

_myIsr:
HWI_enter C55_ALL_AR_DR_REGS, C55_ALL_ACC_REGS, C55_ALL_MISC1_REGS,
C55_ALL_MISC2_REGS, C55_ALL_MISC3_REGS,
0x0000,       ; ier0 interrupt mask unchanged
0x0000,       ; ier1 interrupt mask unchanged
0xffffffff    ; all level 2 ints 0-31 masked
0xffffffff    ; all level 2 ints 32-63 masked

; Your code here
;

HWI_exit C55_ALL_AR_DR_REGS, C55_ALL_ACC_REGS, C55_ALL_MISC1_REGS,
C55_ALL_MISC2_REGS, C55_ALL_MISC3_REGS,
0x0000,       ; ier0 interrupt mask unchanged
0x0000,       ; ier1 interrupt mask unchanged
0xffffffff    ; all level 2 ints 0-31 restored
0xffffffff    ; all level 2 ints 32-63 restored
C.6.5 Statically Configuring a Level 2 Interrupt

This example plugs and enables Level 2 interrupt number 43. All other level 1 and level 2 interrupts are disabled by the DSP/BIOS dispatcher during the execution of "myIsr".

```
/*--------------------------------------------------------
| TCONF script                                           |
/*--------------------------------------------------------

/* ======== l2_example4.c ========
* DSP/BIOS Level 2 interrupt example
*
#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void myIsr (Arg id)
{
    LOG_printf(&trace, "My L2 ISR \d", ArgToInt(id));
}

void main ()
{
    // Enable Level 2 interrupt number 43
    C55_enableInt(C55_L2_INT43);
}

bios.HWI_L2_INT43.useDispatcher = 1;
    // use HWI dispatcher
bios.HWI_L2_INT43.fxn = prog.extern("myIsr");
    // attach to "myIsr" C function
bios.HWI_L2_INT43.arg = 43;
    // pass interrupt ID as argument
bios.HWI_L2_INT43.iMirMask = "all";
    // mask all other L2 ints
bios.HWI_L2_INT43.interruptMask0 = "all";
    // mask L1 ints 0-15
bios.HWI_L2_INT43.interruptMask1 = "all";
    // mask L1 ints 16-31
bios.HWI_L2_INT43.priority = 15;
```
This appendix describes things you need to know about DSP/BIOS in order to use it with the OMAP 2420 platform.

<table>
<thead>
<tr>
<th>Topic</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>D.1 Overview</td>
<td>507</td>
</tr>
<tr>
<td>D.2 OMAP 2420 and the CLK Module</td>
<td>507</td>
</tr>
<tr>
<td>D.3 OMAP 2420 and the HWI Module</td>
<td>510</td>
</tr>
<tr>
<td>D.4 OMAP 2420 and the C55 Module</td>
<td>512</td>
</tr>
<tr>
<td>D.5 Building DSP/BIOS Applications for OMAP 2420</td>
<td>513</td>
</tr>
<tr>
<td>D.6 Usage Examples</td>
<td>514</td>
</tr>
</tbody>
</table>

### D.1 Overview

DSP/BIOS has been enhanced to provide seamless support for the General Purpose Timers (GP Timers) and Level 2 Interrupt Controller (L2IC) present within the OMAP 2420. The CLK module functionality is now driven by GP Timers. The HWI module APIs can define and manipulate level 2 interrupts in addition to level 1 interrupts.

The OMAP 2420 is the first in a series of next generation "OMAP 4" devices. This series may also be referred to as OMAP24xx devices.

Documentation for the OMAP 2420 is provided in the *OMAP 2410/2420 Technical Reference Manual* (SWPU064).

### D.2 OMAP 2420 and the CLK Module

A number of changes and enhancements have been made to the DSP/BIOS CLK module to enable the use of OMAP 2420 General Purpose (GP) timers. The OMAP 2420 has 12 General Purpose (GP) timers. Four timers (5, 6, 7, and 8) are designed to be used by the DSP.

#### D.2.1 Static Configuration

For OMAP 2420, the high- and low-resolution DSP/BIOS clocks are completely independent of each other. It is possible to disable the low-resolution CLK while still supporting the high-resolution CLK features, and vice versa.
The following CLK module properties have differences for OMAP 2420:

- **TIMERSELECT.** This property may be set to “Timer 5” or “Timer 6” to set the GP timer used for the low-resolution time. The GP Timer 7 is used for the high-resolution time. Timer 5 (the default) runs at 32 kHz. Timers 6 and 7 run at 12 MHz. For example:

  bios.CLK.TIMERSELECT = “Timer 5”;

- **TIMERS_BASE.** This property points to the address of GP timer 5 within the DSP address space. This location is set by the DSP MMU configuration shown in Section D.2.2, *GEL Configuration*. The locations of timers 6 and 7 are determined by adding 0x0400 and 0x0800 respectively to the base address. For example, the following statement informs DSP/BIOS that the GP Timer 5 is mapped to IO address 0x7000, the GP Timer 6 is mapped to IO address 0x7400, and the GP Timer 7 is mapped to IO address 0x7800.

  bios.CLK.TIMERS_BASE = 0x7000;

- **ENABLECLK.** For OMAP 2420, this property enables/disables only the low-resolution timer. For example, these statements disable the low-resolution clock:

  bios.PRD.USECLK = false;
  bios.CLK.ENABLECLK = false;

- **ENABLEHTIME.** For OMAP 2420, this property enables/disables the high-resolution clock independent of the low-resolution clock. For example:

  bios.CLK.ENABLEHTIME = false;
OMAP 2420 and the CLK Module

D.2.2 GEL Configuration

In order for the DSP to access the GP timers, you must configure the DSP MMU to map the GP timers into the DSP address space. This can be done using the following ARM-side GEL commands (which are also provided with CCS) or dedicated ARM code.

hotmenu ProgramMMU()
{
    /* DSP MMU_SYSCONFIG - Set bit 1 to perform a SOFTRESET */
    *(int *)0x5A000010 |= 0x2;

    /* TLB 0 - GPTIMER5 = 0x7000, Big Endian */
    *(int *)0x5A000050 = 0x00000000;  /* DSP MMU_LOCK */
    *(int *)0x5A000058 = 0x00fdd00e;  /* DSP MMU_CAM */
    *(int *)0x5A00005c = 0x4807c340;  /* DSP MMU_RAM */
    *(int *)0x5A000054 = 0x00000001;  /* DSP MMU_LD_TLB */

    /* TLB 1 - GPTIMER6 = 0x7400, Big Endian */
    *(int *)0x5a000050 = 0x00000010;  /* DSP MMU_LOCK */
    *(int *)0x5a000058 = 0x00fdd00e;  /* DSP MMU_CAM */
    *(int *)0x5a00005c = 0x4807e340;  /* DSP MMU_RAM */
    *(int *)0x5a000054 = 0x00000001;  /* DSP MMU_LD_TLB */

    /* TLB 2 - GPTIMER7 = 0x7c00, Big Endian */
    *(int *)0x5a000050 = 0x00000020;  /* DSP MMU_LOCK */
    *(int *)0x5a000058 = 0x00fde00e;  /* DSP MMU_CAM */
    *(int *)0x5a00005c = 0x48080340;  /* DSP MMU_RAM */
    *(int *)0x5a000054 = 0x00000001;  /* DSP MMU_LD_TLB */

    /* disable TLB updates, disable TWL, enable MMU */
    *(int*)0x5a000044 = 0x02;
}
In addition, you must route the appropriate clock sources to each GP timer (32KHz to the low-resolution timer, SYSCLK to the high-resolution timer). This can also be done using the following ARM-side GEL commands or dedicated ARM code.

```c
hotmenu RouteGPTClocks() {
    /* CM_FCKLEN1_CORE */
    /* Enable functional clock to GPT 5,6,7 */
    (*(int*)0x48008200) = 0x380;

    /* CM_ICKLEN1_CORE */
    /* Enable interface clock to GPT 5,6,7 */
    (*(int*)0x48008210) = 0x380;

    /* CM_CLKSEL2_CORE */
    /* route 32kHz clock to gpt5,6 and sys_clk to gpt7 */
    (*(int*)0x48008244) = 0x1000;

    /* PRCM_CLKCFG_CTRL */
    /* Validate CLK config in previous step */
    (*(int*)0x48008080) = 1;
}
```

### D.3 OMAP 2420 and the HWI Module

With the introduction of the OMAP family of dual-core ARM + 'C55x devices, many more interrupt sources have been defined than can be terminated on the legacy ‘C55x level 1 interrupt controller, which has a limit of 32 interrupts. To accommodate additional interrupt sources, a new interrupt mechanism has been provided in hardware: the "Level 2 Interrupt Controller" (L2IC).

The additional interrupts are prioritized and multiplexed by the Level 2 Interrupt Controller onto two dedicated level 1 interrupts. DSP/BIOS internally configures all 32 level 2 interrupts to terminate on the single level 1 FIQ interrupt. In the 24xx OMAP family, many peripherals that formerly interrupted the DSP at level 1 have been moved out to level 2.

The L2IC contains a 32-bit Interrupt Mask Register (MIR), which defines which level 2 interrupts are enabled or disabled.

The DSP/BIOS interface to the L2IC is implemented as part of the HWI module. The following sections describe extensions made to the HWI module to support the OMAP 2420.

#### D.3.1 Level 2 Interrupt Controller Base Address

By default, the Level 2 Interrupt Controller (L2IC) resides at data memory address 0x7e4800. This coincides with the reset IOMA value of 0x3f. The IO MAP (IOMA) base address is the page index used to access DSP I/O space addresses from DSP memory space.

If you modify IOMA for any reason, you need to tell DSP/BIOS the new base address for the L2IC. The following Tconf configuration property is provided for this purpose:

```c
bios.HWI.INTC_BASE = 0x7e4800; // 0x7e4800 is default
```

See the OMAP 2410/2420 Technical Reference Manual (SWPU064) for details about programming IOMA.
D.3.2 Level 2 Interrupt Objects and Properties

There are 32 new HWI interrupt objects defined to correspond to level 2 interrupts 0 through 31. These objects are named HWI_L2_INT0 through HWI_L2_INT31.

The following parameters have been added to HWI interrupt objects to allow for static configuration of the level 2 interrupt priorities and mirmask:

- **iMirMask.** This property is valid for both level 1 and 2 interrupts. It specifies which level 2 interrupts the dispatcher should disable before calling this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptMask0 and interruptMask1, which deal with level 1 interrupts.)
  - The "self" option causes the dispatcher to disable only the current interrupt and causes the appropriate interruptBitMask0, interruptBitMask1, and mirmask values to be generated for the interrupt being configured.
  - The "all" option disables all level 2 interrupts.
  - The "none" option disables no level 2 interrupts.
  - The "bitmask" option causes the mirmask property to be used to specify which level 2 interrupts to disable.

- **mirmask.** This property is valid for both level 1 and 2 interrupts. It defines a bitmask of the level 2 interrupts to be disabled by the DSP/BIOS HWI dispatcher when executing this HWI function. This property is writable only when the useDispatcher property is set to true. (This property is similar to interruptBitMask0 and interruptBitMask1, which mask level 1 interrupts.)

- **priority.** Sets the priority from 0 to 31 of a level 2 interrupt. Zero is the highest priority. The default priority for a level 2 interrupt matches its interrupt number. Although this field exists for all HWI interrupt objects, it cannot be configured for level 1 interrupts. You can change the priority at run-time using the C55_l2SetIntPriority API.

The following Tconf statements configure the level 2 interrupt 0 to have a priority of 31 (lowest priority) and a mirmask of 0xffffffff (no other level 2 interrupts enabled while servicing this interrupt):

```plaintext
// valid priority values: 0-31
bios.HWI_L2_INT0.priority = 31;

// use dispatcher and enable setting iMirMask, mirmask
bios.HWI_L2_INT0.useDispatcher = true;

// setting to "bitmask" enables writing to mirmask
bios.HWI_L2_INT0.iMirMask = "bitmask";

// no other L2 interrupts while servicing HWI_L2_INT0
bios.HWI_L2_INT0.mirmask = 0xffffffff;
```
D.3.3 **HWI_dispatchPlug API**

The range of vector IDs allowed is extended from 0-31 to 0-63. The IDs 32-63 correspond to level 2
interrupts 0-31 respectively. The c55.h file now includes definitions for C55_L2_INT0 through
C55_L2_INT31, which map to vector IDs 32-63.

The HWI_Attrs structure used by HWI_dispatchPlug has been expanded to include a mirmask field. This
field contains a 32-bit mask to specify which additional level 2 interrupts to mask during the interrupt.
Each bit in this mask corresponds to a level 2 interrupt. The default value of mirmask for all interrupts is
to mask only the current level 2 interrupt.

```c
typedef struct HWI_Attrs {
    Uns     ier0mask;    // Level 1 interrupt masks
    Uns     ier1mask;
    Arg     arg;         // fxn arg (default = 0)
    LgUns   mirmask;     // Level 2 interrupt mask
} HWI_Attrs;
```

D.3.4 **HWI_enter and HWI_exit APIs**

The HWI_enter and HWI_exit assembly language macros have been enhanced to support selective
interrupt nesting control of level 2 interrupts. This matches the way level 1 interrupts are controlled.

The argument lists for these macros have an additional interrupt mask argument. In HWI_enter, this 32-
bit bitmask defines which level 2 interrupts are to be masked while executing the HWI body. In HWI_exit,
the mask defines which level 2 interrupts are to be restored to their prior state before returning from the
interrupt.

The OMAP 2420 macro invocation syntax is shown below:

```c
HWI_enter C55_AR_DR_X_MASK, C55_ACC_X_MASK, C55_MISC1_X_MASK, C55_MISC2_X_MASK,
          C55_MISC3_X_MASK, IER0DISABLEMASK, IER1DISABLEMASK, MIRDISABLEMASK

HWI_exit C55_AR_DR_X_MASK, C55_ACC_X_MASK, C55_MISC1_X_MASK, C55_MISC2_X_MASK,
          C55_MISC3_X_MASK, IER0RESTOREMASK,  IER1RESTOREMASK, MIRRESTOREMASK
```

D.4 **OMAP 2420 and the C55 Module**

In addition to extensions to the HWI module, the following extensions have been made to the C55 module
to support the OMAP 2420 level 2 interrupts.

D.4.1 **C55_plug API**

For C55_plug, the range of vector IDs is extended from 0-31 to 0-63. The IDs 32-63 correspond to level
2 interrupts 0-31 respectively. The c55.h file now includes definitions C55_L2_INT0 through
C55_L2_INT31 which map to vector IDs 32-63.

D.4.2 **New APIs**

The following APIs have been added to the C55 module for use with OMAP 2420. For details, see the
topics for these APIs in the alphabetic reference in Chapter 2.

- C55_disableInt. Disable an individual interrupt.
• C55_enableInt. Enable an individual interrupt.
• C55_l2AckInt. Explicitly acknowledge an L2 interrupt
• C55_l2DisableMIR. Disable a mask of L2 interrupts
• C55_l2EnableMIR. Enable a mask of L2 interrupts
• C55_l2SetIntPriority. Set the priority of a L2 interrupt

D.5 Building DSP/BIOS Applications for OMAP 2420

In order for the proper DSP/BIOS header files to be used during the build process, you must define the symbol "_2420_" at assembly time.

If you are building from the command line, add the following option to your assembler command line:

```
-d_2420_
```

If you are building with CCS, follow these steps:
1. Open the application's CCS project.
2. Choose Project->Build Options to open the Build Options dialog.
3. Go to the Compiler tab and choose the Assembly category
4. Add _2420_ to the “Pre-Define NAME (-ad)” field.
5. Click OK.
D.6 Usage Examples

The following examples provide examples that use the HWI and C55 APIs related to the OMAP 2420.

D.6.1 Installing and Enabling a Single Level 2 Interrupt

This C code example plugs and enables the 24xx Level 2 interrupt #1.

```c
/*
 * ======= l2_example1.c ========
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void myIsr (Arg id)
{
    LOG_printf(&trace, "My l2 ISR \%d", ArgToInt(id));
}

Void main ()
{
    HWI_Attrs attrs = HWI_ATTRS;

    // pass vector ID to myIsr
    attrs.arg = (Arg)C55_L2_INT1;

    // Plug Level 2 Interrupt #1 Vector
    HWI_dispatchPlug(C55_L2_INT1, (Fxn)myIsr, &attrs);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}
```
D.6.2 Installing and Enabling Multiple Level 2 Interrupts

This C code example plugs and enables level 2 interrupts numbers 10, 11, 12, and 13 and sets their priority levels to 0, 1, 2, 3 respectively (0 = highest priority). The default interrupt nesting behavior (all other interrupts enabled while l2FiqFunc is called) is configured.

```c
/*
 * ========= l2_example2.c =========
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void l2FiqFunc(Arg id)
{
    LOG_printf(&trace, "l2_fiq %d\n", ArgToInt(id));
}

void main()
{
    HWI_Attrs attrs;
    attrs = HWI_ATTRS;

    attrs.arg = (Arg)C55_L2_INT10;
    HWI_dispatchPlug( C55_L2_INT10, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT10, 0);

    attrs.arg = (Arg)C55_L2_INT11;
    HWI_dispatchPlug( C55_L2_INT11, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT11, 1);

    attrs.arg = (Arg)C55_L2_INT12;
    HWI_dispatchPlug( C55_L2_INT12, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT12, 2);

    attrs.arg = (Arg)C55_L2_INT13;
    HWI_dispatchPlug( C55_L2_INT13, (Fxn)l2FiqFunc, &attrs);
    C55_l2SetIntPriority( C55_L2_INT13, 3);

    C55_l2EnableMIR(0x00003c00);
}
```
D.6.3 Enabling an L2 Interrupt Using "interrupt" Keyword

This C code example plugs and enables OMAP 24xx level 2 interrupt number 1.

```c
/*
 * ======== l2_example3.c ========
 * DSP/BIOS Level 2 interrupt example
 */
#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

interrupt void myIsr ()
{
    // Acknowledge this level 2 interrupt to the L2IC
    C55_l2AckInt();

    // ...
    // Your code here
    // ...
}

Void main ()
{
    // Plug Level 2 Interrupt #1 Vector
    C55_plug(C55_L2_INT1, (Fxn)myIsr);

    // Enable Level 2 interrupt
    C55_enableInt(C55_L2_INT1);
}
```
D.6.4 Assembly Language ISR Using HWI_enter, HWI_exit

This assembly code example uses the MIR mask arguments.

;# DSP/BIOS Level 2 interrupt example
;#

; Include files
.include log.h55
.include hwi.h55
.include c55.h55

.global _l2FiqFunc
.global _intCount
.ref _trace
.ref _reportInfo

_myIsr:
HWI_enter C55_ALL_AR_DR_REGS, C55_ALL_ACC_REGS, C55_ALL_MISC1_REGS,
C55_ALL_MISC2_REGS, C55_ALL_MISC3_REGS,
0x0000, ; ier0 interrupt mask unchanged
0x0000, ; ier1 interrupt mask unchanged
0xffffffff ; all level 2 interrupts masked

; Your code here
;

HWI_exit C55_ALL_AR_DR_REGS, C55_ALL_ACC_REGS, C55_ALL_MISC1_REGS,
C55_ALL_MISC2_REGS, C55_ALL_MISC3_REGS,
0x0000, ; ier0 interrupt mask unchanged
0x0000, ; ier1 interrupt mask unchanged
0xffffffff ; all level 2 interrupts restored
D.6.5 **Statically Configuring a Level 2 Interrupt**

This example plugs and enables Level 2 interrupt number 7. All other level 1 and level 2 interrupts are disabled by the DSP/BIOS dispatcher during the execution of "myIsr".

```c
/*
 * ======== l2_example4.c ========
 * DSP/BIOS Level 2 interrupt example
 */

#include <std.h>
#include <hwi.h>
#include <log.h>
#include <c55.h>

extern LOG_Obj trace;

void myIsr (Arg id)
{
  LOG_printf(&trace, "My L2 ISR %d", ArgToInt(id));
}

Void main ()
{
  // Enable Level 2 interrupt number 7
  C55_enableInt(C55_L2_INT7);
}
```

---

**TCONF script**

---

`/* == 12_example4.tcf == */`

```
bios.HWI_L2_INT7.useDispatcher = 1;
  // use HWI dispatcher
bios.HWI_L2_INT7.fxn = prog.extern("myIsr");
  // attach to "myIsr" C function
bios.HWI_L2_INT7.arg = 7;
  // pass interrupt ID as argument
bios.HWI_L2_INT7.iMirMask = "all";
  // mask all other L2 ints
bios.HWI_L2_INT7.interruptMask0 = "all";
  // mask L1 ints 0-15
bios.HWI_L2_INT7.interruptMask1 = "all";
  // mask L1 ints 16-31
```
This appendix describes special DSP/BIOS features provided for use with the C55x devices that provide three 32-bit general-purpose timers.

### E.1 Overview

Certain C55x devices include three 32-bit general-purpose timers. Currently, the devices that provide such timers are the C5505, C5515, C5517, and C5535. Future devices may also provide these timers.

The CLK module supports these devices' timers, which share a common interrupt (HWI_INT4), by allowing separate functions to be configured for each of the three timers.

In order for DSP/BIOS to use one of these timers to drive the CLK module and to allow applications to use the other two timers, several new CLK module configuration parameters and a new runtime API—CLK_setTimerFunc()—have been added to DSP/BIOS.

---

**Important:** DSP/BIOS configures only the timer selected for use by the CLK manager. You must fully configure any other timers you use. Additionally, timer functions you configure must acknowledge the timer's interrupt and clear the timer's interrupt pending status in the timer's "interrupt" register as well as its corresponding status in the "Timer Interrupt Aggregation Flag Register" at IO address 0x1c14.

---

### E.2 CLK Module Support for Three Timers

A rudimentary interrupt dispatcher is invoked whenever any of the three timers generates an interrupt. The CLK interrupt dispatcher then determines which timers have interrupts pending and calls the function configured for each.

Timer interrupt functions configured for any of the three timers must have the following signature:

```c
Void timerfunc(Arg arg);
```

These interrupt functions can be set either statically or dynamically.
E.2.1 Static Configuration

The following CLK module properties are provided specifically for multiple timer support:

- **TIMER0FUNC.** This property specifies the function to be executed when the timer 0 interrupt occurs. By default, timer 0 is used to drive the DSP/BIOS CLK, and so this timer cannot be configured to run a user function unless you change the CLK module’s Timer Selection property to a different timer or disable the CLK manager. To configure this property in a configuration script, follow this example:

  ```
  bios.CLK.TIMER0FUNC = prog.extern("timer0Fxn");
  ```

- **TIMER0ARG.** This property specifies the argument to be passed to the corresponding timer function. For example:

  ```
  bios.CLK.TIMER0ARG = 1;
  ```

- **TIMER1FUNC.** This property specifies the function to be executed when the timer 1 interrupt occurs. To configure this property in a configuration script, follow this example:

  ```
  bios.CLK.TIMER1FUNC = prog.extern("timer1Fxn");
  ```

- **TIMER1ARG.** This property specifies the argument to be passed to the corresponding timer function. For example:

  ```
  bios.CLK.TIMER1ARG = 2;
  ```

- **TIMER2FUNC.** This property specifies the function to be executed when the timer 2 interrupt occurs. To configure this property in a configuration script, follow this example:

  ```
  bios.CLK.TIMER2FUNC = prog.extern("timer2Fxn");
  ```

- **TIMER2ARG.** This property specifies the argument to be passed to the corresponding timer function. For example:

  ```
  bios.CLK.TIMER2ARG = 4;
  ```

The DSP/BIOS Configuration Tool lets you choose one of the three timers in the Timer Selection field. This timer is used to drive the DSP/BIOS clock. You can configure user functions and arguments for the other two timers only.

DSP/BIOS automatically plugs the CLK interrupt dispatcher into HWI_INT4 if any of the 3 timer functions are statically set to something other than FXN_F_nop. By default, the CLK manager's timer handler makes this happen without the user having to manually set any of the timer interrupt functions.

E.2.2 Dynamic Configuration

To dynamically set a timer interrupt function, use the following new CLK API:

```
CLK_setTimerFunc( Uns   timerId,
                 Void  (*func)(Arg),
                 Arg   arg);
```

The timerId is 0, 1, or 2 corresponding to the timer being used. By default, the DSP/BIOS CLK manager uses timer 0.

For example, the following statement dynamically sets timer 1’s interrupt handler:

```
CLK_setTimerFunc(1, myTimer1Func, 4);
```

When timer 1’s interrupt occurs, the CLK interrupt dispatcher calls the configured handler as follows:

```
myTimerFunc(4);
```

See page 2–74 for details.
Index

A

abort function 427

aborting program 429
AC registers, conventions for 494
allocators
  for messages sent by MSGQ module 227
  interface for 277
AND operation
  signed integers 24
  unsigned integers 25
AR registers, conventions for 494
Arg data type 10
ArgToInt macro 482
ArgToPtr macro 482
arguments for functions 10
assembly language
  callable functions (DSP/BIOS) 484
calling C functions from 9
atexit function 482
ATM module 23
  function callability 484
  functions in, list of 11, 23
ATM_andi function 24
ATM_andu function 25
ATM_cleari function 26
ATM_clearu function 27
ATM_deci function 28
ATM_decu function 29
ATM_inci function 30
ATM_incu function 31
ATM_iri function 32
ATM_iro function 33
ATM_seti function 34
ATM_setu function 35
atomic queue manager 323
average statistics for data series 391

B

BIOS clock (see timer)
BIOS library
  instrumented or non-instrumented 121
BK registers, conventions for 494
board clock frequency 120
board input clock 122
board name 120

Bool data type 10
Boolean values 10
BR registers, conventions for 494
BSA registers, conventions for 494
BUF module 36
  configuration properties 36
  function callability 484
  functions in, list of 11, 36
  global properties 37
  object properties 38
BUF_alloc function 39
BUF_create function 40
BUF_delete function 42
BUF_free function 43
BUF_maxbuff function 44
BUF_stat function 45
buffer pool
  allocating fixed-size buffer 39
  creating 40
  deleting 42
  fixed-size buffers 36
  freeing fixed-size buffer 43
  maximum number of buffers 44
  status of 45
buffered pipe manager 259
buffers, splitting 115

C

C functions
  calling from assembly language 9
C_library_stdlib 482
C5000 boards
  memory segments 210
C55 module
  function callability 485
  functions in, list of 11
  OMAP 2320 and 501
  OMAP 2420 and 512
C55_disableIER0 function 47
C55_disableIER1 function 47
C55_disableInt function 48, 501, 512
C55_enableIER0 function 49
C55_enableIER1 function 49
C55_enableInt function 51, 501, 513
C55_i2AckInt function 52, 501, 513
C55_i2DisableMIR function 53, 501, 513
C55_i2DisableMIR1 function 54
C55_i2EnableMIR function 55, 501, 513
C55_i2EnableMIR1 function 56
C55_i2SetIntPriority function 57, 501, 513
C55_plugin function 58, 501, 512
C5505 timers 74
callability of functions 484
calling context (see context)
calloc function 482
    not callable from SWI or HWI 491
CDP register, conventions for 494
CFCT register, conventions for 494
channels (see communication channels; data channels; host
    channels)
character, outputting 441
class driver 80
CLK module 59
    checking calling context 171
    configuration properties 59
    function callability 155, 485
functions in, list of 12, 59
global properties 62
object properties 65
OMAP 2320 and 497
OMAP 2420 and 507, 519
property differences for OMAP 2320 497
property differences for OMAP 2420 507, 520
timer for, driving PRD ticks 281, 282
trace types for 442
CLK_countsPms function 66
CLK_cpuCyclesPerHTime function 67
CLK_cpuCyclesPerLTime function 68
CLK_getHTime function 69
CLK_getPTime function 70
CLK_getPRD function 71
CLK_reconfig function 72
CLK_setTimerFunc function 74
CLK_start function 75
CLK_stop function 76
CLKMD - (PLL) Clock Mode Register 120
CLKMD register 120
clock domains
    idling 290, 292, 300, 311
    idling during deep sleep 295
clock function
    not callable from SWI or HWI 491
Clock Mode Register 120
clocks (see clock domains; real-time clock; system clock;
timer)
communication channels
    closing 136
    control call on 133
    opening 134, 138
consumer, of data pipe 260
context
    CLK, checking for 171
    HWI, checking for 171
    SWI, checking for 417
switching, functions allowing 484
switching, register usage and 9
count statistics for data series 390
counts per millisecond, timer 66
CPU clock domains (see clock domains)
CPU cycles
    converting high-resolution time to 67
    converting low-resolution time to 68
CPU frequency 123, 126
CSR register, conventions for 494
data channels
    busy status, checking 341
    initializing 342
    initializing for output 343
    input, disabling 344
    input, enabling 346
    input, number of MADUs read from 352
    input, reading from 350, 351
    input, status of 348
    output, disabling 345
    output, enabling 347
    output, status of 349
    output, writing to 353
data pipes 259
    allocating empty frame from 263
    getting frame from 266
    number of frames available to read 268
    number of frames available to write 271
    number of words written, setting 276
    putting frame in 274
    recycling frame that has been read to 265
    writerAddr point of, getting 270
data types 10
    Arg 10
    Bool 10
    EnumInt 10
    EnumString 10
    Extern 10
    Int16 10
    Int32 10
    Int32 10
    Numeric 10
    Reference 10
    String 10
    DBIER0 register, conventions for 494
    DBIER1 register, conventions for 494
deep sleep, enabling 295
default values
    for properties 10
dependencies
    declaring 319
    number of, determining 305
    releasing 318
DEV module 77
    configuration properties 79
    function callability 485
    functions in, list of 12, 77
    object properties 80
    properties 79
    DEV_createDevice function 82
| DEV_deleteDevice function | 85 |
| DEV_match function | 86 |
| device |  
| closing | 87 |
| control operation of | 88 |
| creating | 82 |
| deleting | 85 |
| idling | 89 |
| initializing | 90 |
| matching with driver | 86 |
| opening | 92 |
| readiness of, checking | 93 |
| retrieving buffer from | 94 |
| sending buffer to | 91 |
| device drivers | 77 |
| DGN driver | 96 |
| DGS driver | 100 |
| DHL driver | 103 |
| DIO adapter | 106 |
| DNL driver | 109 |
| DOV driver | 110 |
| DPI driver | 112 |
| DST driver | 115 |
| DTR driver | 117 |
| list of | 79 |
| matching device with | 86 |
| device table | 86 |
| device-dependent control operations, performing | 373 |
| DGN driver | 80, 96 |
| object properties | 97 |
| DGS driver | 80, 100 |
| DGS_Params structure | 100 |
| dgs.h file | 100 |
| DHL driver | 80, 103 |
| global properties | 104 |
| object properties | 105 |
| DIO adapter | 80, 106 |
| configuration properties for | 106 |
| global properties | 107 |
| object properties | 108 |
| DNL driver | 80, 109 |
| DOV driver | 80, 110 |
| DP register, conventions for | 494 |
| DPI driver | 80, 112 |
| object properties | 114 |
| D-port write operation | 121 |
| drivers (see device drivers) |  
| DSP speed | 120 |
| DSP/BIOS clock (see timer) |  
| DSP/BIOS functions, list of | 11 |
| DSP/BIOS modules, list of | 8 |
| DSP/BIOS version | 125 |
| DST driver | 80, 115 |
| DTR driver | 80, 117 |
| DTR_multiply function | 117 |
| DTR_multiplyInt16 function | 117 |
| DTR_Params structure | 118 |
| dtr.h file | 118 |
| Dxx_close function | 87 |
| Dxx_ctrl function | 88 |
| Dxx_idle function | 89 |
| Dxx_init function | 90 |
| Dxx_issue function | 91 |
| Dxx_open function | 92 |
| Dxx_ready function | 93 |
| Dxx_reclaim function | 94 |

**E**

- empty devices | 109 |
- enumerated integers | 10 |
- enumerated strings | 10 |
- EnumInt data type | 10 |
- EnumString data type | 10 |
- environment for HOOK and TSK objects | 147 |
- environment pointer for HOOK and TSK objects | 148 |
- error condition flagging | 431 |
- error function | 427 |
- error handling error codes | 491 |
| MSGQ module | 254 |
- error message, writing to system log | 188 |
- error number for tasks | 465 |
- events power, function to be called on | 313, 316 |
| scheduling functions based on | 282 |
| tracing | 442 |
| unregistering notification function for | 322 |
| exit function | 427, 482 |
| exit handler |  
| stacking | 430 |
| Extern data type | 10 |

**F**

- f32toi16 function | 101 |
- false/true values | 10 |
- fixed-size buffers allocating | 39 |
| freeing | 43 |
| maximum number of | 44 |
| pools of | 36 |
- formatted data, outputting | 433, 435, 437, 439 |
| fprintf function not callable from SWI or HWI | 491 |
- frame available to read, getting number of | 268 |
| available to write, getting number of | 271 |
| getting from pipe | 266 |
| number of words in, getting | 269 |
| number of words that can be written to | 272 |
| putting in pipe | 274 |
| recycling | 265 |
| size and address of, determining | 273 |
- free function | 482 |
| not callable from SWI or HWI | 491 |
- frequency changing | 297 |
| for setpoint, determining | 307 |
- frequency scaling | 294 |
| reprogramming clock after | 292 |
- functions arguments for | 10 |
callability of 484
calling conventions for 9
external 10
list of 11
naming conventions for 9

gather/scatter driver 100
GBL module 119
configuration properties 119
functions in, list of 13, 119
global properties 120
GBL_getCkin function 122
GBL_getFrequency function 123
GBL_getProcId function 124
GBL_getVersion function 125
GBL_setFrequency function 126
GBL_setProcId function 127
Gconf
underscore preceding C function names 9, 65, 175, 402
GEL configuration 509
General Purpose (GP) Timers 497, 507, 519
generators 96
getenv function 482
    not callable from SWI or HWI 491
GIO module 128
configuration properties 129
functions in, list of 13, 128
global properties 130
object properties 131
GIO_abort function 132
GIO_control function 133
GIO_create function 134
GIO_delete function 136
GIO_flush function 137
GIO_new function 138
GIO_read function 140
GIO_submit function 141
GIO_write function 143
global settings 119
GP (General Purpose) Timers 497, 507, 519
target-specific, enabling and disabling 46
target-specific, setting priority of 57
hardware registers
MEM module and 203
hardware timer counter register ticks 59
heap, address 218
high-resolution time 59, 60, 62
    converting to CPU cycles 67
    getting 69
hook functions 144
HOOK module 144
configuration properties 144
functions in, list of 13, 144
object properties 145
properties 145
HOOK_getenv function 147
HOOK_setenv function 148
host channel manager 149
host link driver 80, 103
HST module 149
configuration properties 149
functions in, list of 13, 149
global properties 150
object properties 150
HST object 103
HST_getpipe function 152
HWI module 153
configuration properties 153
functions in, list of 14, 153
global properties 156
object properties 157
OMAP 2320 and 498
OMAP 2420 and 510
statistics units for 391
HWI_disable function 161
HWI_dispatchPlug function 500, 512
HWI_dispatchplug function 162
HWI_enable function 164
HWI_enter function 155, 165, 500, 512
HWI_exit function 155, 168, 500, 512
HWI_isHWI function 171
HWIRestore function 172
I/O availability, scheduling functions based on 282
i16tof32 function 101
i16toi32 function 101
i16toiu8 function 101
i32to16 function 101
IDL module 173
configuration properties 173
functions in, list of 14, 173
global properties 174
object properties 174
IDL_run function 176
idle functions, running 176
idle thread manager 173
IER (Interrupt Enable Register)
  disable interrupts using 47
  enable interrupts using 49
IER0 register, conventions for 494
IER1 register, conventions for 494
IFR0 register, conventions for 494
IFR1 register, conventions for 494
initialization 144
input channels
  declaring 342
  disabling 344
  enabling 346
  number of MADUs read from 352
  reading from 350, 351
  status of, determining 348
input streams 365
Input/Output
  aborting 132
  closing communication channel 136
  control call on communication channel 133
  flushing input and output channels 137
  opening communication channel 134, 138
  submitting GIO packet 141
  synchronous read 140
  synchronous write 143
Int16 data type 10
Int32 data type 10
integers
  enumerated 10
  unsigned 10
interface for allocators 277
Interrupt Enable Register
  disable interrupts using 47
  enable interrupts using 49
Interrupt Mask Register 53, 54, 55, 56
interrupt service routines (see hardware interrupts)
interrupt threads 401
interrupt vector, plugging 46, 58
interrupts (see hardware interrupts; software interrupts)
IOM model for device drivers 77
ISR epilog 168
ISR prolog 165
IVPD register, conventions for 494
IVPH register, conventions for 494

L
L2IC (Level 2 Interrupt Controller) 497, 507, 519
  base address 499, 510
  objects and properties 499, 511
  latency to scale between setpoints 309
LCM module 177
  configuration properties 177
  function callability 486
  functions in, list of 14, 177
  global properties 177
  object properties 178
LCM_create function 179
LCM_delete function 180
LCM_pend function 181
  thread restrictions for 483
LCM_post function 182

M
MADUs 203
mailbox
  clear bits from 403, 405
  creating 197
  decrementing 408
  deleting 198
  get value of 414
  incrementing 416
  OR mask with value in 418, 419
  posting message to 200
  waiting for message from 199
mailbox manager 195
main function
  calling context 171
malloc function 482
  not callable from SWI or HWI 491
maximum statistics for data series 391
MBX module 195
  configuration properties 195
  function callability 486
  functions in, list of 14, 195
  global properties 196
  object properties 196
  MBX_create function 197
MBX_delete function 198
MBX_pend function 199
MBX_post function 200
MEM module 201
  configuration properties 201
  function callability 486
  functions in, list of 15, 201
  global properties 203
  object properties 209
  MEM_alloc function 211
MEM_define function 216  
MEM_free function 217  
MEM_getBaseAddress function 218  
MEM_increaseTableSize function 219  
MEM_redefine function 220  
MEM_stat function 221  
MEM_undefine function 222  
MEM_valloc function 223

memory block  
freeing 217  
increasing 219  
memory model 121

memory segment manager 201

memory segments  
allocating and initializing 223  
allocating from 211  
C5000 boards 210  
defining 216  
extisting, redefining 220  
status of, returning 221  
undefining 222

message log 183  
appending formatted message to 191  
disabling 186  
enabling 187  
resetting 194  
writing unformatted message to 189

message queues 226  
closing 234  
determining destination queue for message 239  
finding 246  
number of messages in 235  
open, finding 244  
opening 248  
placing message in 251  
receiving message from 237  
releasing 253

messages  
allocating 233  
determining destination message queue of 239  
freeing 236  
ID for, setting 256  
ID of, determining 240  
number of, in message queue 235  
placing in message queue 251  
receiving from message queue 237  
reply destination of, determining 242  
reply destination of, setting 258  
size of, determining 241  
mesaing, multi-processor 224  
mini-drivers 106  
deleting 136  
mint function  
non callabe from SWI or HWI 491

MIR (Interrupt Mask Register) 53, 54, 55, 56

modules  
ATM module 23  
BUF module 36  
CLK module 59  
DEV module 77  
functions for, list of 11  
GBL module 119  
GIO module 128

HOOK module 144  
HST module 149  
HWI module 153  
IDL module 173  
LCK module 177  
list of 8  
LOG module 183  
MBX module 195  
MEM module 201  
MSGQ module 224  
PIP module 259  
POOL module 277  
PRD module 281  
PWRM module 288  
QUE module 323  
SEM module 354  
SIO module 365  
STS module 390  
SWI module 399  
SYS module 426  
trace types for 442  
TRC module 442  
TSK module 446  
MSGQ API 227, 228  
MSGQ module 224  
configuration properties 226  
function callability 486  
functions in, list of 15, 224  
global properties 232  
internal errors, handling 254  
static configuration 228  
MSGQ_alloc function 233  
MSGQ_close function 234  
MSGQ_count function 235  
MSGQ_free function 236  
MSGQ_get function 237  
MSGQ_getAttrs function 238  
MSGQ_getDstQueue function 239  
MSGQ_getMsgId function 240  
MSGQ_getMsgSize function 241  
MSGQ_getSrcQueue function 242  
MSGQ_isLocalQueue function 243  
MSGQ_locate function 244  
MSGQ_locateAsync function 246  
MSGQ_open function 248  
MSGQ_put function 251  
MSGQ_release function 253  
MSGQ_setErrorHandler function 254  
MSGQ_setMsgrd function 256  
MSGQ_setSrcQueue function 258  
multiple processors 127  
multiprocessor application  
converting single-processor application to 113  
multi-processor applications 127  
multi-processor messaging 224

N

naming conventions  
functions 9  
properties 10  
NMI functions
calling HWI functions 155
notification function signatures 316
notification functions 322
notifyReader function 260
PIP API calls and 156
notifyWriter function 260
null driver 109
Numeric data type 10

O
object references
properties holding 10
OMAP 2320 497
C55 module and 501
CLK module and 497
HWI module and 498
OMAP 2420 507, 519
C55 module and 512
CLK module and 507, 519
HWI module and 510
on-chip timer (see timer)
operations (see functions)
OR operation
signed integers 32
unsigned integers 33
output channels
declaring 343
disabling 345
enabling 347
status of, determining 349
writing to 353
output streams 365
outputting formatted data 433, 435, 437, 439
outputting single character 441
overlap driver 110

P
packing/unpacking ratio, DGS driver 100
PC register, conventions for 494
period register
value of 71
periodic function
starting 285
stopping 286
periodic function manager 281
periodic rate 60
PIP module 259
configuration properties 259
function callability 487
functions in, list of 16, 259
global properties 261
object properties 261
statistics units for 391
trace types for 442
PIP_alloc function 263
PIP_free function 260, 265
PIP_get function 266
PIP_getReaderAddr function 267
PIP_getReaderNumFrames function 268
PIP_getReaderSize function 269
PIP_getWriterAddr function 270
PIP_getWriterNumFrames function 271
PIP_getWriterSize function 272
PIP_peek function 273
PIP_put function 260, 274
PIP_setWriterSize function 276
pipe driver 80, 112
pipe manager, buffered 259
pipe object 152
pipes
allocating empty frame from 263
get readerAddr pointer of 267
getting frame from 266
number of frames available to read 268
number of frames available to write 271
number of words written, setting 276
putting frame in 274
recycling frame that has been read to 265
writerAddr point of, getting 270
POOL module 277
configuration properties 277
functions in, list of 277
global properties 280
posted mode 121
power event
function to be called on 313
registered, function to be called on 316
power management 288
PRD module 281
configuration properties 281
function callability 487
functions in, list of 16, 281
global properties 282
object properties 283
statistics units for 391
ticks driven by CLK timer 281, 282
ticks, getting current count 284
ticks, incrementing 287
ticks, setting increments for 282
trace types for 442
PRD_getticks function 284
PRD_start function 285
PRD_stop function 286
PRD_tick function 287
prescalar register
resetting 72
printf function
not callable from SWI or HWI 491
processor ID 120, 124, 127
processors
multiple 127
PROCID 127
producer, of data pipe 260
program
aborting 429
terminating 432
properties
data types for 10
default values for 10
GIO object 131
HOOK module 145
HOOK object 145
MEM object 209
naming conventions 10
putc function 428
PWRM module 288
capabilities of, determining 302
clock domains, idling 290, 292, 300, 311
clock domains, idling during deep sleep 295
configuration properties 290, 300
function callability 487
functions in, list of 16, 288
global properties 291
PWRM_changeSetpoint function 297
PWRM_configure function 300
PWRM_getCapabilities function 302
PWRM_getDependSetpoint function 304
PWRM_getDependencyCount function 305
PWRM_getCurrentSetpoint function 304
PWRM_getSetpoints function 306
PWRM_getSetpointInfo function 307
PWRM_idleClocks function 311
PWRM_registerNotify function 313
PWRM_releaseDependency function 318
PWRM_setDependency function 319
PWRM_sleepDSP function 320
PWRM_unregisterNotify function 322
pwrmNotifyFxn function 316

QUE module 323
configuration properties 323
function callability 488
functions in, list of 17, 323
global properties 324
object properties 324
QUE_create function 325
QUE_delete function 326
QUE_enqueue function 327
QUE_empty function 328
QUEUE function 329
QUE_get function 330
QUE_head function 331
QUE_insert function 332
QUE_new function 333
QUE_next function 334
QUE_prev function 335
QUE_put function 336
QUE_remove function 337
queue manager 323
queues
creating 325
deleting 326
emptying 333
getting element from front of 330
inserting element at end of 329
inserting element in middle of 332
putting element at end of 336
removing element from front of 327
removing element from middle of 337
returning pointer to element at front of 331
returning pointer to next element of 334
returning pointer to previous element of 335
testing if empty 328

RAND
rand function
not callable from SWI or HWI 491
REA0 register, conventions for 494
REA1 register, conventions for 494
reader, of data pipe 260
readers, MSGQ module 226, 228
read-time data exchange settings 338
realloc function 482
not callable from SWI or HWI 491
real-time clock (see CLK module)
Reference data type 10
register conventions 493
registers
modification in multi-threaded application 493
preserving across task context switches or
interrupts 493
resource lock
acquiring ownership of 181
creating 179
deleting 180
relinquishing ownership of 182
resource lock manager 177
resources
declaring dependency on 319
number of dependencies on 305
releasing dependency on 318
RETA register, conventions for 494
RPTC register, conventions for 494
RSA0 register, conventions for 494
RSA1 register, conventions for 494
RTDX module 338
configuration properties 338
function callability 488
functions in, list of 17
object properties 340
target configuration properties 339
RTDX_channelBusy function 341
RTDX_CreateInputChan function 342
RTDX_CreateOutputChannel function 343
RTDX_disableInput function 344
RTDX_disableOutput function 345
RTDX_enableInput function 346
RTDX_enableOutput function 347
RTDX_isInputEnabled function 348
RTDX_isOutputEnabled function 349
RTDX_read function 350
RTDX_readNB function 351
RTDX_sizeofInput function 352
RTDX_write function 353
RTS functions
not calling in HWI or SWI threads 155, 483
RTS library 120

S
scaling operation 117
SEM module 354
configuration properties 354
function callability 488
functions in, list of 18, 354
global properties 355
object properties 355
SEM_count function 356
SEM_create function 357
SEM_delete function 358
SEM_new function 359
SEM_pend function 360
SEM_pendBinary function 361
SEM_post function 362
SEM_postBinary function 363
SEM_reset 364
semaphore manager 354
semaphores
  binary, signaling 363
  binary, waiting for 361
count of, determining 356
count of, resetting 364
  creating 357
deleting 358
initializing 359
signaling 362
waiting for 360
setpoints (see V/F setpoints)
signal generators 96
signed integers
  AND operation 24
clearing 26
decrementing 28
incrementing 30
OR operation 32
setting 34
single-processor application
  converting to multiprocessor application 113
SIO module 365
configuration properties 366
function callability 489
functions in, list of 18
functions in, list of 365
global properties 367
object properties 367
SIO_bufsize function 370
SIO_create function 371
SIO_ctrl function 373
SIO_delete function 374
SIO_flush function 375
SIO_get function 376
SIO_idle function 378
SIO_issue function 379
SIO_ISSUERECLAIM streaming model
  DPI and 113
SIO_put function 381
SIO_ready function 383
SIO_reclaim function 384
SIO_reclaimx function 386
SIO_segid function 387
SIO_select function 388
SIO_staticbuf function 389
SIO/DEV model for device drivers 77
sleep
  changing sleep states 320
depth sleep, enabling 295
  for tasks 477
software generator driver 80
software interrupt manager 399
software interrupts
  address of currently executing interrupt 423
  attributes of, returning 412
  attributes of, setting 424
  callable functions 484
  checking to see if in context of 417
  clearing 406
  context of, determining if in 417
deleting 409
  disabled, manipulating variables while 23
  enabling 411
  mailbox for, clearing bits 403, 405
  mailbox for, decrementing 408
  mailbox for, incrementing 416
  mailbox for, OR mask with value in 418, 419
  mailbox for, returning value of 414
  posting 418, 419, 420
  priority mask, returning 415
  raising priority of 421
  restoring priority of 422
SP register, conventions for 494
split driver 115
sprintf function
  not callable from SWI or HWI 491
srand function
  not callable from SWI or HWI 491
SSP register, conventions for 494
ST registers, conventions for 495
stack
  allocating for tasks 452
  checking for overflow 454
  stack size for tasks 450, 452
stackable gather/scatter driver 100
stackable overlap driver 110
stackable split driver 115
stackable streaming transformer driver 117
STATICPOOL allocator 279
statistics
  resetting values of 396
  saving values for delta 397
  tracing 442
  updating 394
  updating with delta 395
statistics object manager 390
status register conventions 495
std.h library
  functions in 482
  macros in, list of 21
stdlib.h library
  functions in 482
  functions in, list of 21
stream I/O manager 365
streams
  acquiring static buffer from 389
  closing 374
device for, determining if ready 383
device for, selecting ready device 388
device-dependent control operation, issuing 373
  flushing 375
getting buffer from 376
idling 378
memory segment used by, returning 387
opening 371
putting buffer to 381
requesting buffer from 384, 386
sending buffer to 379
size of buffers used by, determining 370
strftime function
not callable from SWI or HWI 491
String data type 10
strings 10
enumerated 10
STS module 390
configuration properties 390
function callability 489
functions in, list of 19, 390
global properties 392
object properties 393
STS_add function 394
STS_delta function 395
STS_reset function 396
STS_set function 397
sum statistics for data series 391
SWI module 399
configuration properties 400
function callability 489
functions in, list of 19, 399
global properties 402
object properties 402
statistics units for 391
trace types for 442
SWI_andn function 403
SWI_andnHook function 405
SWI_create function 406
SWI_dec function 408
SWI_delete function 409
SWI_enable function 411
SWI_getattr function 412
SWI_getmbox function 414
SWI_getpri function 415
SWI_inc function 416
SWI_isSWI function 417
SWI_or function 418
SWI_orHook function 419
SWI_post function 420
SWI_raisepri function 421
SWI_restorepri function 422
SWI_self function 423
SWI_setattr function 424
synchronous read 140
synchronous write 143
SYS module 426
configuration properties 426
function callability 489
functions in, list of 20, 426
global properties 427
object properties 428
SYS_abort function 427, 429
SYS_atexit function 430
SYS_EALLOC status 491
SYS_EBADIO status 491
SYS_EBADOBJ status 492
SYS_EBUSY status 491
SYS_EDead status 492
SYS_EDOMAIN status 492
SYS_EEOF status 492
SYS_EFREE status 491
SYS EINVAL status 491
SYS EMODE status 491
SYS ENODEV status 491
SYS ENOTFOUND status 492
SYS ENOTIMPL status 492
SYS_error function 427, 431
SYSETIMEOUT status 492
SYS EUSER status 492
SYS_exit function 427, 432
SYS_OK status 491
SYS_printf function 428, 433
SYS_putchar function 428, 441
SYS_sprintf function 428, 437
SYS_vsprintf 439
system clock 60
incrementing in TSK module 470, 479
PRD module driving 451
returning current value of 480
system clock manager 59
writing error message to 188
writing program-supplied message to 190
system settings, managing 426

T
T0 register, conventions for 494
T1 register, conventions for 494
T2 register, conventions for 494
T3 register, conventions for 494
target board name 120
task context switches, preserving registers across 493
task environment setting 472
task manager 446
task scheduler disabling 461
enabling 462
tasks
callable functions 484
checking if in context of 469
creating 455
currently executing, handle of 471
default priority of 451
delaying execution of (sleeping) 477
deleting 458
evironment pointer for, getting 464
error number for, getting 465
error number for, setting 473
execution priority of, setting 474
handle of STS object, getting 468
incrementing system clock for 470, 479
name of, getting 466
not shutting down system during 453
priority of 453, 467
<table>
<thead>
<tr>
<th>Term</th>
<th>Page(s)</th>
</tr>
</thead>
<tbody>
<tr>
<td>resetting time statistics for</td>
<td>475</td>
</tr>
<tr>
<td>status of, retrieving</td>
<td>478</td>
</tr>
<tr>
<td>terminating</td>
<td>463</td>
</tr>
<tr>
<td>updating time statistics for</td>
<td>459</td>
</tr>
<tr>
<td>yielding to task of equal priority</td>
<td>481</td>
</tr>
<tr>
<td>Tconf</td>
<td></td>
</tr>
<tr>
<td>underscore preceding C function names</td>
<td>9, 65, 175, 402</td>
</tr>
<tr>
<td>TDDR</td>
<td>59</td>
</tr>
<tr>
<td>terminating program</td>
<td>432</td>
</tr>
<tr>
<td>threads</td>
<td></td>
</tr>
<tr>
<td>idle thread manager</td>
<td>173</td>
</tr>
<tr>
<td>interrupt threads</td>
<td>401</td>
</tr>
<tr>
<td>register modification and</td>
<td>493</td>
</tr>
<tr>
<td>RTS functions callable from</td>
<td>483</td>
</tr>
<tr>
<td>tick count, determining</td>
<td>284</td>
</tr>
<tr>
<td>tick counter (see PRD module, ticks)</td>
<td></td>
</tr>
<tr>
<td>timer</td>
<td>59, 60</td>
</tr>
<tr>
<td>counts per millisecond</td>
<td>66</td>
</tr>
<tr>
<td>reprogramming after frequency scaling</td>
<td>292</td>
</tr>
<tr>
<td>resetting</td>
<td>72</td>
</tr>
<tr>
<td>timer counter</td>
<td>60</td>
</tr>
<tr>
<td>timer divide-down register</td>
<td>59</td>
</tr>
<tr>
<td>timer period register</td>
<td>72</td>
</tr>
<tr>
<td>timers</td>
<td>74</td>
</tr>
<tr>
<td>trace buffer</td>
<td></td>
</tr>
<tr>
<td>memory segment for</td>
<td>427</td>
</tr>
<tr>
<td>size of</td>
<td>427</td>
</tr>
<tr>
<td>trace manager</td>
<td>442</td>
</tr>
<tr>
<td>tracing</td>
<td></td>
</tr>
<tr>
<td>disabling</td>
<td>443</td>
</tr>
<tr>
<td>enabling</td>
<td>444</td>
</tr>
<tr>
<td>querying enabled trace types</td>
<td>445</td>
</tr>
<tr>
<td>transform function, DGS driver</td>
<td>100</td>
</tr>
<tr>
<td>transformer driver</td>
<td>117</td>
</tr>
<tr>
<td>transformers</td>
<td>117</td>
</tr>
<tr>
<td>transports array</td>
<td>127, 231</td>
</tr>
<tr>
<td>transports, MSGQ module</td>
<td>227</td>
</tr>
<tr>
<td>TRC module</td>
<td>442</td>
</tr>
<tr>
<td>function callability</td>
<td>490</td>
</tr>
<tr>
<td>functions in, list of</td>
<td>20, 442</td>
</tr>
<tr>
<td>TRC_disable function</td>
<td>443</td>
</tr>
<tr>
<td>TRC_enable function</td>
<td>444</td>
</tr>
<tr>
<td>TRC_query function</td>
<td>445</td>
</tr>
<tr>
<td>TRN0 register, conventions for</td>
<td>494</td>
</tr>
<tr>
<td>TRN1 register, conventions for</td>
<td>494</td>
</tr>
<tr>
<td>true/false values</td>
<td>10</td>
</tr>
<tr>
<td>TSK module</td>
<td>446</td>
</tr>
<tr>
<td>configuration properties</td>
<td>447</td>
</tr>
<tr>
<td>function callability</td>
<td>490</td>
</tr>
<tr>
<td>functions in, list of</td>
<td>20, 446</td>
</tr>
<tr>
<td>global properties</td>
<td>450</td>
</tr>
<tr>
<td>object properties</td>
<td>452</td>
</tr>
<tr>
<td>statistics units for</td>
<td>391</td>
</tr>
<tr>
<td>system clock driven by</td>
<td>451, 470, 479</td>
</tr>
<tr>
<td>trace types for</td>
<td>442</td>
</tr>
<tr>
<td>TSK_checkstacks function</td>
<td>454</td>
</tr>
<tr>
<td>TSK_create function</td>
<td>455</td>
</tr>
<tr>
<td>TSK_delete function</td>
<td>458</td>
</tr>
<tr>
<td>TSK_deltatime function</td>
<td>459</td>
</tr>
<tr>
<td>TSK_disable function</td>
<td>461</td>
</tr>
<tr>
<td>TSK_enable function</td>
<td>462</td>
</tr>
<tr>
<td>TSK_exit function</td>
<td>463</td>
</tr>
<tr>
<td>TSK_getenv function</td>
<td>464</td>
</tr>
<tr>
<td>TSK_geterr function</td>
<td>465</td>
</tr>
<tr>
<td>TSK_getname function</td>
<td>466</td>
</tr>
<tr>
<td>TSK_getpri function</td>
<td>467</td>
</tr>
<tr>
<td>TSK_getsts function</td>
<td>468</td>
</tr>
<tr>
<td>TSK_isTSK function</td>
<td>469</td>
</tr>
<tr>
<td>TSK_itick function</td>
<td>470</td>
</tr>
<tr>
<td>TSK_self function</td>
<td>471</td>
</tr>
<tr>
<td>TSK_setenv function</td>
<td>472</td>
</tr>
<tr>
<td>TSK_seterr function</td>
<td>473</td>
</tr>
<tr>
<td>TSK_setpri function</td>
<td>474</td>
</tr>
<tr>
<td>TSK_settime function</td>
<td>475</td>
</tr>
<tr>
<td>TSK_sleep function</td>
<td>477</td>
</tr>
<tr>
<td>TSK_stat function</td>
<td>478</td>
</tr>
<tr>
<td>TSK_tick function</td>
<td>479</td>
</tr>
<tr>
<td>TSK_time function</td>
<td>480</td>
</tr>
<tr>
<td>TSK_yield function</td>
<td>481</td>
</tr>
<tr>
<td>u16tou32 function</td>
<td>101</td>
</tr>
<tr>
<td>u32tou16 function</td>
<td>101</td>
</tr>
<tr>
<td>u32tou8 function</td>
<td>101</td>
</tr>
<tr>
<td>u8toi16 function</td>
<td>101</td>
</tr>
<tr>
<td>u8tou32 function</td>
<td>101</td>
</tr>
<tr>
<td>underscore</td>
<td></td>
</tr>
<tr>
<td>preceding C function names</td>
<td>9, 65, 175, 402</td>
</tr>
<tr>
<td>unsigned integers</td>
<td>10</td>
</tr>
<tr>
<td>AND operation</td>
<td>25</td>
</tr>
<tr>
<td>clearing</td>
<td>27</td>
</tr>
<tr>
<td>decrementing</td>
<td>29</td>
</tr>
<tr>
<td>incrementing</td>
<td>31</td>
</tr>
<tr>
<td>OR operation</td>
<td>33</td>
</tr>
<tr>
<td>setting</td>
<td>35</td>
</tr>
<tr>
<td>user hook function</td>
<td>292</td>
</tr>
<tr>
<td>V/F setpoints</td>
<td></td>
</tr>
<tr>
<td>changing</td>
<td>297</td>
</tr>
<tr>
<td>determining</td>
<td>304</td>
</tr>
<tr>
<td>frequency and voltage of, determining</td>
<td>307</td>
</tr>
<tr>
<td>latency to scale between</td>
<td>309</td>
</tr>
<tr>
<td>number of determining</td>
<td>306</td>
</tr>
<tr>
<td>variables</td>
<td></td>
</tr>
<tr>
<td>manipulating with interrupts disabled</td>
<td>23</td>
</tr>
<tr>
<td>vfprintf function</td>
<td></td>
</tr>
<tr>
<td>not callable from SWI or HWI</td>
<td>491</td>
</tr>
<tr>
<td>voltage</td>
<td></td>
</tr>
<tr>
<td>changing</td>
<td>297</td>
</tr>
<tr>
<td>for setpoint, determining</td>
<td>307</td>
</tr>
<tr>
<td>voltage scaling</td>
<td>294</td>
</tr>
<tr>
<td>vsprintf function</td>
<td></td>
</tr>
<tr>
<td>not callable from SWI or HWI</td>
<td>491</td>
</tr>
<tr>
<td>W</td>
<td></td>
</tr>
<tr>
<td>writer, of data pipe</td>
<td>260</td>
</tr>
<tr>
<td>Module/Section</td>
<td>Page</td>
</tr>
<tr>
<td>-------------------------------------------------------------------------------</td>
<td>------</td>
</tr>
<tr>
<td>writers, MSGQ module</td>
<td>226, 228</td>
</tr>
<tr>
<td>XCDP register, conventions</td>
<td>494</td>
</tr>
<tr>
<td>XDP register, conventions</td>
<td>494</td>
</tr>
<tr>
<td>XSP register, conventions</td>
<td>494</td>
</tr>
<tr>
<td>XSSP register, conventions</td>
<td>494</td>
</tr>
<tr>
<td>XAR registers, conventions</td>
<td>494</td>
</tr>
</tbody>
</table>
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