TMS320C55x DSP/BIOS 5.32
Application Programming Interface (API) Reference Guide

Literature Number: SPRU404N
September 2007
Preface

Read This First

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:

```c
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


**Trademarks**


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

**Trademarks**

MS-DOS, Windows, and Windows NT are trademarks of Microsoft Corporation.

The Texas Instruments logo and Texas Instruments are registered trademarks of Texas Instruments. Trademarks of Texas Instruments include: TI, XDS, Code Composer, Code Composer Studio, Probe Point, Code Explorer, DSP/BIOS, RTDX, Online DSP Lab, BIOSuite, SPOX, TMS320, TMS320C28x, TMS320C54x, TMS320C55x, TMS320C62x, TMS320C64x, TMS320C67x, TMS320C5000, and TMS320C6000.

All other brand or product names are trademarks or registered trademarks of their respective companies or organizations.
Contents

1 API Functional Overview ................................................................. 1-1
   This chapter provides an overview to the TMS320C55x DSP/BIOS API functions.
   1.1 DSP/BIOS Modules .................................................................. 1-2
   1.2 Naming Conventions ............................................................... 1-3
   1.3 Assembly Language Interface Overview .................................... 1-3
   1.4 DSP/BIOS Tconf Overview ....................................................... 1-3
   1.5 List of Operations ................................................................. 1-5

2 Application Program Interface ......................................................... 2-1
   This chapter describes the DSP/BIOS API modules and functions.
   2.1 ATM Module ........................................................................... 2-2
   2.2 BUF Module ............................................................................. 2-15
   2.3 C55 Module .............................................................................. 2-26
   2.4 CLK Module ............................................................................. 2-39
   2.5 DEV Module .............................................................................. 2-58
   2.6 GBL Module .............................................................................. 2-108
   2.7 GIO Module .............................................................................. 2-118
   2.8 HOOK Module .......................................................................... 2-137
   2.9 HST Module .............................................................................. 2-143
   2.10 HWI Module ............................................................................ 2-148
   2.11 IDL Module ............................................................................. 2-172
   2.12 LCK Module ............................................................................ 2-176
   2.13 LOG Module ............................................................................. 2-183
   2.14 MBX Module ............................................................................ 2-195
   2.15 MEM Module ............................................................................ 2-201
   2.16 MSGQ Module ......................................................................... 2-229
   2.17 PIP Module .............................................................................. 2-265
   2.18 POOL Module .......................................................................... 2-285
   2.19 PRD Module ............................................................................. 2-290
   2.20 PWRM Module ......................................................................... 2-298
   2.21 QUE Module ............................................................................. 2-336
   2.22 RTDX Module ......................................................................... 2-353
   2.23 SEM Module ............................................................................. 2-369
   2.24 SIO Module .............................................................................. 2-382
   2.25 STS Module .............................................................................. 2-412
   2.26 SWI Module .............................................................................. 2-422
## Contents

**2.27 SYS Module** ................................................................. 2-451
**2.28 TRC Module** ................................................................. 2-467
**2.29 TSK Module** ................................................................. 2-472
**2.30 std.h and stdlib.h functions** ........................................ 2-511

**A Function Callability and Error Tables** ................................. A-1
*This appendix provides tables describing TMS320C55x errors and function callability.*
**A.1 Function Callability Table** .............................................. A-2
**A.2 DSP/BIOS Error Codes** .................................................. A-11

**B C55x DSP/BIOS Register Usage** .......................................... B-1
*This appendix provides tables describing the TMS320C55x register conventions in terms of preservation across multi-threaded context switching and preconditions.*
**B.1 Overview** ................................................................. B-2
**B.2 Register Conventions** .................................................. B-2
**B.3 Status Register Conventions** ........................................ B-4

**C DSP/BIOS for OMAP 2320** .................................................. C-1
*This appendix describes things you need to know about DSP/BIOS in order to use it with the OMAP 2320 platform.*
**C.1 Overview** ................................................................. C-2
**C.2 OMAP 2320 and the CLK Module** ..................................... C-2
**C.3 OMAP 2320 and the HWI Module** ..................................... C-4
**C.4 OMAP 2320 and the C55 Module** ..................................... C-8
**C.5 Building DSP/BIOS Applications for OMAP 2320** .................. C-8
**C.6 Usage Examples** ........................................................ C-9

**D DSP/BIOS for OMAP 2420** .................................................. D-1
*This appendix describes things you need to know about DSP/BIOS in order to use it with the OMAP 2420 platform.*
**D.1 Overview** ................................................................. D-2
**D.2 OMAP 2420 and the CLK Module** ..................................... D-2
**D.3 OMAP 2420 and the HWI Module** ..................................... D-5
**D.4 OMAP 2420 and the C55 Module** ..................................... D-9
**D.5 Building DSP/BIOS Applications for OMAP 2420** ................. D-9
**D.6 Usage Examples** ........................................................ D-10
Figures

2-1 MYSEG Heap Initial Memory Map ................................................................. 2-215
2-2 MYSEG Memory Map After Allocation ......................................................... 2-216
2-3 MYSEG Memory Map After Modified Allocation ......................................... 2-217
2-4 Writers and Reader of a Message Queue ..................................................... 2-232
2-5 Components of the MSGQ Architecture ..................................................... 2-233
2-6 MSGQ Function Calling Sequence .............................................................. 2-233
2-7 Pipe Schematic ............................................................................................ 2-267
2-8 Allocators and Message Pools ..................................................................... 2-286
2-9 Buffer Layout as Defined by STATICPOOL_Params .................................... 2-288
2-10 PRD Tick Cycles ......................................................................................... 2-295
2-11 Statistics Accumulation on the Host ........................................................ 2-415
## Tables

<table>
<thead>
<tr>
<th>Table No.</th>
<th>Description</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>1-1</td>
<td>DSP/BIOS Modules</td>
<td>1-2</td>
</tr>
<tr>
<td>1-2</td>
<td>DSP/BIOS Operations</td>
<td>1-5</td>
</tr>
<tr>
<td>2-1</td>
<td>Timer Counter Rates, Targets, and Resets</td>
<td>2-41</td>
</tr>
<tr>
<td>2-2</td>
<td>High-Resolution Time Determination</td>
<td>2-42</td>
</tr>
<tr>
<td>2-3</td>
<td>HWI interrupts for the 'C55x'</td>
<td>2-158</td>
</tr>
<tr>
<td>2-4</td>
<td>Conversion Characters for LOG_printf</td>
<td>2-191</td>
</tr>
<tr>
<td>2-5</td>
<td>Typical Memory Segments for C5000 Boards</td>
<td>2-213</td>
</tr>
<tr>
<td>2-6</td>
<td>Statistics Units for HWI, PIP, PRD, and SWI Modules</td>
<td>2-413</td>
</tr>
<tr>
<td>2-7</td>
<td>Conversion Characters Recognized by SYS_printf</td>
<td>2-458</td>
</tr>
<tr>
<td>2-8</td>
<td>Conversion Characters Recognized by SYS_sprintf</td>
<td>2-460</td>
</tr>
<tr>
<td>2-9</td>
<td>Conversion Characters Recognized by SYS_vlog</td>
<td>2-462</td>
</tr>
<tr>
<td>2-10</td>
<td>Conversion Characters Recognized by SYS_vsprintf</td>
<td>2-464</td>
</tr>
<tr>
<td>2-11</td>
<td>Events and Statistics Traced by TRC</td>
<td>2-467</td>
</tr>
<tr>
<td>A-1</td>
<td>Function Callability</td>
<td>A-2</td>
</tr>
<tr>
<td>A-2</td>
<td>RTS Function Calls</td>
<td>A-9</td>
</tr>
<tr>
<td>A-3</td>
<td>Error Codes</td>
<td>A-11</td>
</tr>
</tbody>
</table>
This chapter provides an overview to the TMS320C55x DSP/BIOS API functions.

<table>
<thead>
<tr>
<th>Topic</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.1  DSP/BIOS Modules</td>
<td>1–2</td>
</tr>
<tr>
<td>1.2  Naming Conventions</td>
<td>1–3</td>
</tr>
<tr>
<td>1.3  Assembly Language Interface Overview</td>
<td>1–3</td>
</tr>
<tr>
<td>1.4  DSP/BIOS Tconf Overview</td>
<td>1–3</td>
</tr>
<tr>
<td>1.5  List of Operations</td>
<td>1–5</td>
</tr>
</tbody>
</table>
## 1.1 DSP/BIOS Modules

### 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>
<tr>
<td>PIP Module</td>
<td>Buffered pipe manager</td>
</tr>
<tr>
<td>POOL Module</td>
<td>Allocator interface module</td>
</tr>
<tr>
<td>PRD Module</td>
<td>Periodic function manager</td>
</tr>
<tr>
<td>PWRM Module</td>
<td>Reduce application’s power consumption</td>
</tr>
<tr>
<td>QUE Module</td>
<td>Queue manager</td>
</tr>
<tr>
<td>RTDX Module</td>
<td>Real-time data exchange manager</td>
</tr>
<tr>
<td>SEM Module</td>
<td>Semaphores manager</td>
</tr>
<tr>
<td>SIO Module</td>
<td>Stream I/O manager</td>
</tr>
<tr>
<td>STS Module</td>
<td>Statistics object manager</td>
</tr>
<tr>
<td>SWI Module</td>
<td>Software interrupt manager</td>
</tr>
<tr>
<td>SYS Module</td>
<td>System services manager</td>
</tr>
<tr>
<td>TSK Module</td>
<td>Multitasking manager</td>
</tr>
<tr>
<td>std.h and stdlib.h functions</td>
<td>Standard C library I/O functions</td>
</tr>
</tbody>
</table>
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 modules 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>
</tbody>
</table>
List of Operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<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_gethtime</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_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>
</tbody>
</table>
## List of Operations

### 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>

### Functional Overview

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<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>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>
### List of Operations

#### 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>

#### 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_dispatchPlug</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>
</tbody>
</table>
### List of Operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<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>
## List of Operations

### 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>
<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>

### MEM module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>MEM_alloc, MEM_valloc,</td>
<td>Allocate from a memory heap</td>
</tr>
<tr>
<td>MEM_calloc</td>
<td></td>
</tr>
<tr>
<td>MEM_define</td>
<td>Define a new memory heap</td>
</tr>
<tr>
<td>MEM_free</td>
<td>Free a block of memory</td>
</tr>
<tr>
<td>MEM_getBaseAddress</td>
<td>Get base address of a memory heap</td>
</tr>
<tr>
<td>MEM_increaseTableSize</td>
<td>Increase the internal MEM table size</td>
</tr>
<tr>
<td>MEM_redefine</td>
<td>Redefine an existing memory heap</td>
</tr>
<tr>
<td>MEM_stat</td>
<td>Return the status of a memory heap</td>
</tr>
<tr>
<td>MEM_undefined</td>
<td>Undefine an existing memory segment</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>
</tbody>
</table>
### List of Operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<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>
<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>
## List of Operations

### 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

<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>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>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>
<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>
</tbody>
</table>
### List of Operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<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>

#### SEM module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>SEM_count</td>
<td>Get current semaphore count</td>
</tr>
<tr>
<td>SEM_create</td>
<td>Create a semaphore</td>
</tr>
<tr>
<td>SEM_delete</td>
<td>Delete a semaphore</td>
</tr>
<tr>
<td>SEM_new</td>
<td>Initialize a semaphore</td>
</tr>
<tr>
<td>SEM_pend</td>
<td>Wait for a counting semaphore</td>
</tr>
<tr>
<td>SEM_pendBinary</td>
<td>Wait for a binary semaphore</td>
</tr>
<tr>
<td>SEM_post</td>
<td>Signal a counting semaphore</td>
</tr>
<tr>
<td>SEM_postBinary</td>
<td>Signal a binary semaphore</td>
</tr>
<tr>
<td>SEM_reset</td>
<td>Reset semaphore</td>
</tr>
</tbody>
</table>

#### SIO module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>SIO_bufsize</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_ctrl</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>
<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>
</tbody>
</table>
### List of Operations

#### 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>
</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>

#### SIO_ready
Determine if device for stream 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 section used by a stream

#### SIO_select
Select a ready device

#### SIO_staticbuf
Acquire static buffer from stream
## List of Operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<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>
<tr>
<td>SWI_post</td>
<td>Post a software interrupt</td>
</tr>
<tr>
<td>SWI_raisepri</td>
<td>Raise an SWI’s priority</td>
</tr>
<tr>
<td>SWI_restorepri</td>
<td>Restore an SWI’s priority</td>
</tr>
<tr>
<td>SWI_self</td>
<td>Return address of currently executing SWI object</td>
</tr>
<tr>
<td>SWI_setattrs</td>
<td>Set attributes of a software interrupt</td>
</tr>
</tbody>
</table>

### SYS module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>SYS_abort</td>
<td>Abort program execution</td>
</tr>
<tr>
<td>SYS_atexit</td>
<td>Stack an exit handler</td>
</tr>
<tr>
<td>SYS_error</td>
<td>Flag error condition</td>
</tr>
<tr>
<td>SYS_exit</td>
<td>Terminate program execution</td>
</tr>
<tr>
<td>SYS_putchar</td>
<td>Output a single character</td>
</tr>
<tr>
<td>SYS_printf, SYS_sprintf, SYS_vprintf, SYS_vsprintf</td>
<td>Formatted output</td>
</tr>
</tbody>
</table>

### TRC module operations

<table>
<thead>
<tr>
<th>Function</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>TRC_disable</td>
<td>Disable a set of trace controls</td>
</tr>
<tr>
<td>TRC_enable</td>
<td>Enable a set of trace controls</td>
</tr>
<tr>
<td>TRC_query</td>
<td>Test whether a set of trace controls is enabled</td>
</tr>
</tbody>
</table>

### TSK module operations

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

**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>2–2</td>
</tr>
<tr>
<td>2.2 BUF Module</td>
<td>2–15</td>
</tr>
<tr>
<td>2.3 C55 Module</td>
<td>2–26</td>
</tr>
<tr>
<td>2.4 CLK Module</td>
<td>2–39</td>
</tr>
<tr>
<td>2.5 DEV Module</td>
<td>2–58</td>
</tr>
<tr>
<td>2.6 GBL Module</td>
<td>2–108</td>
</tr>
<tr>
<td>2.7 GIO Module</td>
<td>2–118</td>
</tr>
<tr>
<td>2.8 HOOK Module</td>
<td>2–137</td>
</tr>
<tr>
<td>2.9 HST Module</td>
<td>2–143</td>
</tr>
<tr>
<td>2.10 HWI Module</td>
<td>2–148</td>
</tr>
<tr>
<td>2.11 IDL Module</td>
<td>2–172</td>
</tr>
<tr>
<td>2.12 LCK Module</td>
<td>2–176</td>
</tr>
<tr>
<td>2.13 LOG Module</td>
<td>2–183</td>
</tr>
<tr>
<td>2.14 MBX Module</td>
<td>2–195</td>
</tr>
<tr>
<td>2.15 MEM Module</td>
<td>2–201</td>
</tr>
<tr>
<td>2.16 MSGQ Module</td>
<td>2–229</td>
</tr>
<tr>
<td>2.17 PIP Module</td>
<td>2–265</td>
</tr>
<tr>
<td>2.18 POOL Module</td>
<td>2–285</td>
</tr>
<tr>
<td>2.19 PRD Module</td>
<td>2–290</td>
</tr>
<tr>
<td>2.20 PWRM Module</td>
<td>2–298</td>
</tr>
<tr>
<td>2.21 QUE Module</td>
<td>2–336</td>
</tr>
<tr>
<td>2.22 RTDX Module</td>
<td>2–353</td>
</tr>
<tr>
<td>2.23 SEM Module</td>
<td>2–369</td>
</tr>
<tr>
<td>2.24 SIO Module</td>
<td>2–382</td>
</tr>
<tr>
<td>2.25 STS Module</td>
<td>2–412</td>
</tr>
<tr>
<td>2.26 SWI Module</td>
<td>2–422</td>
</tr>
<tr>
<td>2.27 SYS Module</td>
<td>2–451</td>
</tr>
<tr>
<td>2.28 TRC Module</td>
<td>2–467</td>
</tr>
<tr>
<td>2.29 TSK Module</td>
<td>2–472</td>
</tr>
<tr>
<td>2.30 std.h and stdlib.h functions</td>
<td>2–511</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**

**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:

```
`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:

```
`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**

```
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:

```
`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

\[ \text{uval} = \text{ATM\_decu(udst)}; \]

Parameters

\[
\begin{align*}
\text{volatile Uns} & \quad \text{*udst;} & \text{/* pointer to unsigned */} \\
\end{align*}
\]

Return Value

\[
\begin{align*}
\text{Uns} & \quad \text{uval;} & \text{/* new value after decrement */} \\
\end{align*}
\]

Description

ATM\_decu atomically decrements a Uns memory location and returns its new value as follows:

\`
\text{\textbackslash interrupt disable}\text{\textbackslash}
\text{uval} = *\text{udst} - 1;
*\text{udst} = \text{uval};
\text{\textbackslash interrupt enable}\text{\textbackslash}
\text{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

Atomically increment Int memory and return new value

**C Interface**

**Syntax**

\[
\text{ival} = \text{ATM\_inci}(\text{idst});
\]

**Parameters**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Int</td>
<td>pointer to integer</td>
</tr>
</tbody>
</table>

**Return Value**

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Int</td>
<td>new value after increment</td>
</tr>
</tbody>
</table>

**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**

```
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:

```
`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**

```c
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

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

**C Interface**

**Syntax**

```c
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:

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

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:

```c
`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
Atomically set Uns memory and return previous value

C Interface

Syntax

\[
uold = \text{ATM\_setu} \text{(udst, } \text{unew)};\]

Parameters

\[
\text{volatile Uns } \ast \text{udst}; \quad \text{/* pointer to unsigned */} \\
\text{Uns } \text{unew}; \quad \text{/* new unsigned value */}
\]

Return Value

\[
\text{Uns } \text{uold}; \quad \text{/* previous value of } \ast \text{udst */}
\]

Description

ATM\_setu atomically sets an Uns memory location to a new value and returns its previous value as follows:

```
`interrupt disable`
uval = \ast \text{udst};
\ast \text{udst} = \text{unew};
`interrupt enable`
return (\text{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

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 1-3.
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;
 BUF Module

- **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**

**Syntax**
```c
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**

```c
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 (`0xcafe`). 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_maxbuff` Check the maximum number of buffers from the buffer pool
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

```c
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.h file also contain assembly language macros for saving and restoring registers in HWIs.
C Interface

Syntax

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

Parameters

Uns mask; /* disable mask */

Return Value

Uns oldmask; /* actual bits cleared by disable mask */

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**

```c
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`
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;

TSK_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
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
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**

```c
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**

```c
// 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

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 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. (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

// 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**

<table>
<thead>
<tr>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Uns</td>
<td><code>vecid</code>; /* vector ID of interrupt */</td>
</tr>
<tr>
<td>Uns</td>
<td><code>priority</code>; /* new priority of interrupt */</td>
</tr>
</tbody>
</table>

**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**

```c
C55_plug(vecid, fxn);
```

**Parameters**

- **Int vecid;** /* interrupt id */
- **Fxnx 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_getlttime. Get low-resolution time
- CLK_getprd. Get period register value
- CLK_reconfig. Reset timer period and registers using CPU frequency
- 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 1-3.

**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>TCRRTDDR</td>
<td>EnumInt</td>
<td>0 (0 to 15) (not for OMAP 2320/2420)</td>
</tr>
</tbody>
</table>
## CLK Module

### Instance Configuration Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<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>
<tr>
<td>INPUTCLK</td>
<td>Numeric</td>
<td>0.032 MHz (OMAP 2420 only)</td>
</tr>
<tr>
<td>HTIMECLK</td>
<td>Numeric</td>
<td>12.0 MHz (OMAP 2420 only)</td>
</tr>
</tbody>
</table>

### Description

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 2-1. Timer Counter Rates, Targets, and Resets

<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.
CLK Module

- 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_gettime 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 OMAP 2320/2420.)

<table>
<thead>
<tr>
<th>Platform</th>
<th>Options</th>
<th>Size</th>
<th>Registers</th>
</tr>
</thead>
<tbody>
<tr>
<td>'C5503, 'C5507, 'C5509, 'C5510, 'C5561</td>
<td>00h to 0fh</td>
<td>4 bits</td>
<td>part of TCR</td>
</tr>
<tr>
<td>'C5501, 'C5502</td>
<td>00h to 0fffffffh</td>
<td>32 bits</td>
<td>PRD3:PRD4</td>
</tr>
</tbody>
</table>

Example: bios.CLK.TCRTDDR = 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. The default value for 'C5501/5502 is 74999, for 'C5503/5507/5509/5510 is 46666, for 5561 is 59999, for OMAP2320 is 12000, and for OMAP 2420 is 32. (Not available for 1x10 and 59xx.)

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

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 timeFxn";

- **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("timeFxn");

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**  
`ncounts = CLK_countspms();`

**Parameters**  
Void

**Return Value**  
`Lg Uns ncounts;`

**Reentrant**  
yes

**Description**  
CLK_countspms returns the number of high-resolution timer counts per millisecond.

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.

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

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

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

**See Also**  
CLK_gethtime  
CLK_getprd  
CLK_cpuCyclesPerHtime  
CLK_cpuCyclesPerLtime  
GBL_getCkin  
STS_delta
CLK_cpuCyclesPerHtime

Return multiplier for converting high-res time to CPU cycles

C Interface

Syntax

\[
\text{ncycles} = \text{CLK_cpuCyclesPerHtime}() \; \text{Void};
\]

Parameters

Void

Return Value

Float \text{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.

\[
\begin{align*}
\text{time1} &= \text{CLK_gethtime}(); \\
\text{... processing ...} \\
\text{time2} &= \text{CLK_gethtime}(); \\
\text{CPUcycles} &= (\text{time2} - \text{time1}) \times \text{CLK_cpuCyclesPerHtime}(); \\
&\quad \text{/* calculate absolute time in milliseconds */} \\
\text{TimeAbsolute} &= \frac{\text{CPUcycles}}{\text{GBL_getFrequency}()};
\end{align*}
\]

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
CLK_gethtime

Get high-resolution time

C Interface

Syntax

currtime = CLK_gethtime();

Parameters

Void

Return Value

LgUns currtime /* 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 2-42 for information about how this rate is set.

CLK_gethtime provides a value with greater accuracy than CLK_getltime, 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

/* ======== 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

curtime = 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 2-41 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_getltime, 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

/* ======== showTicks ======== */

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

See Also

CLK_getltime
PRD_getticks
STS_delta
CLK_getprd  Get period register value

C Interface

Syntax       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.

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.

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

See Also
CLK_countspms
CLK_gethtime
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_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

**Important Note:** The DEV module is being deprecated and 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). The DEV module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

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.
DEV Module

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*/
#endif
    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 1-3.

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>fxnTable</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>fxnTableType</td>
<td>EnumString</td>
<td>&quot;DEV_Fxns&quot; (&quot;IOM_Fxns&quot;)</td>
</tr>
<tr>
<td>devcId</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>params</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
<tr>
<td>devcGlobalDataPtr</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.
  
  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.
  
  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.
  
  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.

- **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

Important Note: 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

C Interface

Syntax

```c
status = DEV_createDevice(name, fxns, initFxn, attrs);
```

Parameters

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>String</td>
<td>name; /* name of device to be created */</td>
</tr>
<tr>
<td>Void</td>
<td><em>fxns; /</em> pointer to device function table */</td>
</tr>
<tr>
<td>Fxn</td>
<td>initFxn; /* device init function */</td>
</tr>
<tr>
<td>DEV_Attrs</td>
<td><em>attrs; /</em> pointer to device attributes */</td>
</tr>
</tbody>
</table>

Return Value

Int status; /* 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 initFxn 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:

```c
typedef struct DEV_Attrs {
#if (defined(_54_) && defined(_FAR_MODE)) || defined(_55_)
    LgInt     devid;  /* device id */
#else
    Int       devid;  /* device id */
#endif
    #else
    Int       devid;  /* device id */
    #endif
    #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

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

```c
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*

**Important Note:** 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### C Interface

**Syntax**

```c
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.
DEV_deleteDevice

- 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

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

See Also

SIO_delete
**DEV_match**

*Match a device name with a driver*

**Important Note:** 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### C Interface

**Syntax**

\[
\text{substr} = \text{DEV\_match(name, device)};
\]

**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 Note:** 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### C Interface

**Syntax**

```c
int 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 Note:** 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### 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
**Dxx_idle**

**Important Note:** 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### C Interface

#### Syntax

```c
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
**Important Note:** 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

<table>
<thead>
<tr>
<th>C Interface</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Syntax</strong></td>
<td>Dxx_init();</td>
</tr>
<tr>
<td><strong>Parameters</strong></td>
<td>Void</td>
</tr>
<tr>
<td><strong>Return Value</strong></td>
<td>Void</td>
</tr>
<tr>
<td><strong>Description</strong></td>
<td>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.</td>
</tr>
</tbody>
</table>
Dxx_issue

Send a buffer to the device

**Important Note:** 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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 Note: 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

C Interface

Syntax

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 Note: 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

C Interface

Syntax

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

**Important Note:** 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). This API is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### C Interface

**Syntax**

```c
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 SYS_ETIMEOUT. 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 Note:** 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). This driver is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### 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 1-3.

#### 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>deviceld</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>
</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 a custom function to produce or 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.

---

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<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 prog.extern(&quot;FXN_F_nop&quot;)</td>
<td></td>
</tr>
<tr>
<td>arg</td>
<td>Arg</td>
<td>0x00000000</td>
</tr>
</tbody>
</table>
DGN Driver

- **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 approximated to the nearest power of two.
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:
  \[ \text{step} = \left( \frac{256 \times \text{Frequency}}{\text{Rate}} \right) \]

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:

\[ \text{fxn}(\text{Arg arg, Ptr buf, Uns nmadus}) \]

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 Note:** 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). This driver is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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
typedef struct DGS_Params {      /* device parameters */
    Fxn   createFxn;          /* device parameters */
    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:

  ```c
dstsize = myTrans(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 that 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:

```
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
Important Note: 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). This driver is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

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 1-3.
DHL Driver

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.

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:

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...
DHL Driver

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).

**Configure Mini-driver**
To create a DIO device object in a configuration script, first use the following syntax:

```javascript
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:

```javascript
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 1-3.

**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>STATICCREATE</td>
<td>Bool</td>
<td>false</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>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:

```
Application
  TSK or SWI threads

SIO Module API

DIO adapter

DEV module
  (DEV_match, DEV_Fxns, DEV_Handle, DEV_Callback)

IOM mini-driver
  (IOM_Fxns function table)
```

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_alloc 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:

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;
**Important Note:** 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). This driver is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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 Note:** 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). This driver is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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.

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 that 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
**Important Note:** 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). This driver is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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 1-3.

**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>allowVirtual</td>
<td>Bool</td>
<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);
```

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

and from the writer task call:

```c
eextern 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.

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 C:\ti\c5000\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
The 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.

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.

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

There are no global properties for the DPI driver manager.

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.

  ```javascript
  Tconf Name: comment
  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 Note:** 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). This driver is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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 Note:** 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). This driver is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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:

```javascript
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.fxn */
};
```

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.fxn 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.fxn is NULL, no transformation is performed at all.
if (user.fxn != NULL) {
    (*user.fxn)(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_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 1-3.

### 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</td>
</tr>
<tr>
<td></td>
<td></td>
<td>'C5510, etc: 140</td>
</tr>
<tr>
<td></td>
<td></td>
<td>'C5561: 60</td>
</tr>
<tr>
<td></td>
<td></td>
<td>'C59xx: 12</td>
</tr>
<tr>
<td></td>
<td></td>
<td>1x10 (1510, 1610, and 1710): 12</td>
</tr>
<tr>
<td></td>
<td></td>
<td>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.
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: CLKOUT  
  Type: Int16  
  Example: `bios.GBL.CLKOUT = 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 2-511. 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 `<BIOS_INSTALL_DIR>/xdcTools/packages/ti/targets` tree. 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 addressing range. The difference is that 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
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
    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 `<BIOS_INSTALL_DIR>\packages\ti\bios\lib`. By default, the instrumented version of the library for your platform is used.

    Tconf Name: INSTRUMENTED
    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
    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
    Example: bios.GBL.DCRPOSTEDERITE = true;
**GBL_getClkin**  
*Get configured value of board input clock in KHz*

**C Interface**

**Syntax**

```c
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  
version = GBL_getVersion(Void);

Parameters  
Void

Return Value  
Uint16 version; /* version data */

Reentrant  
yes

Description  
Returns DSP/BIOS version information as a 4-digit hex number. For example: 0x5100.

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>

Also, 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. (The last item uses two digits 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**

- `Uint32 frequency; /* 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**

```c
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**

```c
/* 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_EBADIO      -1    /* generic failure */
#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_EABORT      -6    /* I/O aborted uncompleted*/
#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 IOMETIMEOUTUNREC -11   /* unrecoverable timeout occurred */
#define IOM_EINUSE      -12   /* device already in use */
```
/* 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 syncrh. 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 1-3.

**Module Configuration Parameters**

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>ENABLEGIO</td>
<td>Bool</td>
<td>false</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>PENDFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
<tr>
<td>POSTFXN</td>
<td>Extern</td>
<td>prog.extern(&quot;FXN_F_nop&quot;)</td>
</tr>
</tbody>
</table>

**Description**

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:

![Diagram of module relationships]

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

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 2-118.

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

/* abort all I/O requests given to the device*/

gioStatus = GIO_abort(gioChan);
GIO_control

Device specific control call

C Interface

Syntax

\[
\text{status} = \text{GIO\_control(gioChan, cmd, args);}
\]

Parameters

GIO\_HandlegioChan; /* handle to an instance of the device */
Intcmd; /* control functionality to perform */
Ptrargs; /* data structure to pass control information */

Return Value

Intstatus; /* 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 2-118. 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 2-118.

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

\[
/* Carry out control/configuration on the device*/
gioStatus = GIO\_control(gioChan, XXX\_RESET, &args);
\]
**GIO_create**

*Allocate and initialize a GIO object*

**C Interface**

**Syntax**

```c
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**

```c
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.

```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.

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

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

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 2-118.

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

/* close the device instance */
GIO_delete(gioChan);
GIO_flush

**C Interface**

**Syntax**

```c
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 2-118.

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**

```c
/* Flush all I/O given to the device*/
GIO_flush(gioChan);
```
**GIO_new**  
*Initialize a GIO object with pre-allocated memory*

**C Interface**

**Syntax**

```c
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.

```c
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 the nPackets 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
```
GIO_read

Synchronous read command

**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 2-118.

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

```c
/* Read from the device */
size = sizeof(readStruct);
status = GIO_read(gioChan, &readStruct, &size);
```
### GIO_submit

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 2-118. 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 2-118.

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);
```
**C Interface**

**Syntax**

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**

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 2-118.

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, &writeStruct, &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

typedef Int HOOK_Id; /* HOOK instance id */

typedef Void (*HOOK_InitFxn)(HOOK_Id id);
typedef Void (*HOOK_CreateFxn)(TSK_Handle task);
typedef Void (*HOOK_DeleteFxn)(TSK_Handle task);
typedef Void (*HOOK_ExitFxn)(Void);
typedef Void (*HOOK_ReadyFxn)(TSK_Handle task);
typedef 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 1-3.

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:

```
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

HOOK_setenv(task, id, environ);

Parameters

TSK_Handle task; /* task object handle */
HOOK_Id id; /* HOOK instance id */
Ptr environ; /* environment pointer */

Return Value

Void

Reentrant

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 Note:** This module is being deprecated and will no longer be supported in the next major release of DSP/BIOS. The HST module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

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 1-3.

#### 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>notifyFxnn</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:

```javascript
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;
**Important Note:** This API is being deprecated and will no longer be supported in the next major release of DSP/BIOS. The HST module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### C Interface

**Syntax**

```c
pipe = HST_getpipe(hst);
```

**Parameters**

- `HST_Handle hst /* host object handle */`

**Return Value**

- `PIP_Handle pip /* pipe object handle*/`

**Reentrant**

yes

**Description**

HST_getpipe gets the address of the pipe object for the specified host channel object.

**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 == 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
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

```c
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 */
};
```

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 1-3.

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;ac0l&quot;, &quot;ac1g&quot;, &quot;ac1h&quot;, &quot;ac1l&quot;, &quot;ac2g&quot;, &quot;ac2h&quot;, &quot;ac2l&quot;, &quot;ac3g&quot;, &quot;ac3h&quot;, &quot;ac3l&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;xssp&quot;, &quot;tim&quot;, &quot;st0_55&quot;, &quot;st1_55&quot;, &quot;st2_55&quot;, &quot;st3_55&quot;, &quot;tm0&quot;, &quot;bk03&quot;, &quot;br0&quot;, &quot;xdp&quot;, &quot;xdc&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;tm1&quot;, &quot;br1&quot;, &quot;csr&quot;, &quot;rplc&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;)</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>mimask</td>
<td>Numeric</td>
<td>0x00000000 * (OMAP 2320/2420 only)</td>
</tr>
<tr>
<td>mir1mask</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 of RTS functions that should not be called from a SWI or an HWI function, see “LCK_pend” on page 2-180.

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. HWI_enter/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 SWIDisable or SWIEnable 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
  - SEM_post
  - MBX_post
  - TSK_yield
  - TSK_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.

\[ Tconf \text{ Name: } \text{fxn} \quad \text{Type: Extern} \]

\[ \text{Example: } \text{bios.HWI_INT2.fxn} = \text{prog.extern("myHWI", "asm");} \]

- **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", "trn0", "bk03", "brc0", "xdp", "xcdp", "dph", "mdp05", "mdp67", "pdp", "bk47", "bkc", "bsa01", "bsa23", "bsa45", "bsa67", "bsac", "tm1", "brc1", "csr", "rptc"

\[ \text{Example: } \text{bios.HWI_INT2.monitor} = \text{"Nothing"}; \]

- **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.

\[ Tconf \text{ Name: } \text{addr} \quad \text{Type: Arg} \]

\[ \text{Example: } \text{bios.HWI_INT2.addr} = \text{0x00000000}; \]

- **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.

\[ Tconf \text{ Name: } \text{dataType} \quad \text{Type: EnumString} \]

Options: "signed", "unsigned"

\[ \text{Example: } \text{bios.HWI_INT2.dataType} = \text{"signed"}; \]
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.)

- Tconf Name: interruptMask0
- Type: EnumString
- Tconf Name: interruptMask1
- Type: EnumString

- Options: "self", "all", "none", "bitmask"

Example: bios.HWI_INT2.interruptMask0 = "self";
**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.

<table>
<thead>
<tr>
<th>Tconf Name</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>interruptBitMask0</td>
<td>Numeric</td>
</tr>
<tr>
<td>interruptBitMask1</td>
<td>Numeric</td>
</tr>
</tbody>
</table>

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)

<table>
<thead>
<tr>
<th>Tconf Name</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>iMirMask</td>
<td>EnumString</td>
</tr>
</tbody>
</table>

Options: "self", "all", "none", "bitmask"

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)

<table>
<thead>
<tr>
<th>Tconf Name</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>mirmask</td>
<td>Numeric</td>
</tr>
</tbody>
</table>

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_l2SetIntPriority 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 2–152)</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>

2-158
## HWI_disable

**Disable hardware interrupts**

### C Interface

#### Syntax

```c
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

```c
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.

```c
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:

```c
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
HWI_enter  

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,  
MIR1DISABLEMASK

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, MIRDISABLEMASK

Preconditions  
intm = 1

Postconditions  
intm=0, braf=0, cpl=1, m40=0, satd=0, sxmd=0, c16=0, frct=0, c54cm=0,  
arms=1, rdm=0, cdplc=0, ar[0...7]lc=0, 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

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, ifr0, dbier0, ier1, ifr, dbier1, st0, st1, st2, st3, trn0, bk03, brc0
- **C55_MISC2_X_MASK**: Mask of registers dp, cdp, mdp, mdp05, mdp67, pdp, bk47, bkc, bof01, bof23, bof45, bof67, bofc, lvpd, ivph, trn1
- **C55_MISC3_X_MASK**: Mask of registers brc1, csr, rsa0_h_addr, rsa0, rsa0_h_addr, rea0, rsa1_h_addr, rsa1, rea1_h_addr, rea1, rptc
- **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.

```c
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:

```c
call _myCfunction;
```

When exiting the hardware interrupt, you need to call HWI_exit with the following macro:

```c
HWI_exit C55_AR_DR_SAVE_BY_CALLER_MASK, \n    C55_ACC_SAVE_BY_CALLER_MASK, \n    C55_MISC1_SAVE_BY_CALLER_MASK, \n    C55_MISC2_SAVE_BY_CALLER_MASK, \n    C55_MISC3_SAVE_BY_CALLER_MASK, \n    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

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_enter and HWI_exit must surround all statements in any DSP/BIOS assembly language HWIs that call C functions only for HWIs that are not dispatched by the HWI dispatcher.

HWI_exit calls the DSP/BIOS SWI manager if DSP/BIOS itself is not in the middle of updating critical data structures, or if no currently interrupted HWI is also in a HWI_enter/HWI_exit region. The DSP/BIOS SWI manager services all pending SWI handlers (functions).

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_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

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_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. It also returns TRUE when called from main(). 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**

```c
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**

```c
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 1-3.

### 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>AUTOCALCULATE</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>LOOPINSTCOUNT</td>
<td>Int32</td>
<td>1000</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>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 2–111), 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;`
IDL Module

- **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.

```plaintext
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: comment 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 1-3.

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:
LCK Module

- **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_ATTRS`, 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 2–205.

**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**

```
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

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 thread.

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>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.

**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 1-3.

### 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&quot;)</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 2–467, 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.

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");`

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.

```javascript
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  
  **Type:** EnumInt  
  **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  
  **Type:** EnumString  
  **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. See LOG_printf, page 2–191, and LOG_event, page 2–189, for information about the structure of a log record.
  
  **Tconf Name:** format  
  **Type:** String  
  **Example:**  
  ```
  myLog.format = "0x%x, 0x%x, 0x%x";
  ```
**LOG_disable**

*Disable a message log*

**C Interface**

**Syntax**

```
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**

```
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

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:

<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 2-184).

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

LOG_event(&trace, (Arg)value1, (Arg)value2, (Arg)CLK gethtime());

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 */`
- `Arg 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 2-4.

<table>
<thead>
<tr>
<th>Conversion Character</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>%d</code></td>
<td>Signed integer</td>
</tr>
<tr>
<td><code>%u</code></td>
<td>Unsigned integer</td>
</tr>
<tr>
<td><code>%x</code></td>
<td>Unsigned hexadecimal integer</td>
</tr>
<tr>
<td><code>%o</code></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.

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.

---

**Conversion Character | Description**

<table>
<thead>
<tr>
<th>%s</th>
<th>Character string</th>
</tr>
</thead>
<tbody>
<tr>
<td>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:</td>
<td></td>
</tr>
<tr>
<td>char *msg = &quot;Hello world!&quot;;</td>
<td></td>
</tr>
<tr>
<td>LOG_printf(&amp;trace, &quot;%s&quot;, msg);</td>
<td></td>
</tr>
<tr>
<td>However, the following example is not supported:</td>
<td></td>
</tr>
<tr>
<td>char msg[100];</td>
<td></td>
</tr>
<tr>
<td>strcpy(msg, &quot;Hello world!&quot;);</td>
<td></td>
</tr>
<tr>
<td>LOG_printf(&amp;trace, &quot;%s&quot;, msg);</td>
<td></td>
</tr>
<tr>
<td>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.</td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>%r</th>
<th>Symbol from symbol table</th>
</tr>
</thead>
<tbody>
<tr>
<td>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:</td>
<td></td>
</tr>
<tr>
<td>Int testval = 17;</td>
<td></td>
</tr>
<tr>
<td>LOG_printf(&quot;%r = %d&quot;, &amp;testval, testval);</td>
<td></td>
</tr>
<tr>
<td>displays:</td>
<td></td>
</tr>
<tr>
<td>testval = 17</td>
<td></td>
</tr>
<tr>
<td>If no symbol is found for the value passed to %r, the Event Log uses the string &lt;unknown symbol&gt;.</td>
<td></td>
</tr>
</tbody>
</table>

| %p | data pointer |
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
- 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**

```c
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**

```c
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

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 1-3.

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 Module

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.

```javascript
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");`
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 2–205.

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**

```c
status = MBX_post(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**

`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.
- MEM_calloc. 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_redefine. 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 1-3.
## Module Configuration Parameters

<table>
<thead>
<tr>
<th>C55x Name</th>
<th>Type</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>REUSECODESPACE</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>ARGSSIZE</td>
<td>Numeric</td>
<td>x0008</td>
</tr>
<tr>
<td>STACKSIZE</td>
<td>Numeric</td>
<td>0x0400</td>
</tr>
<tr>
<td>SYSSSTACKSIZE</td>
<td>Numeric</td>
<td>0x0100</td>
</tr>
<tr>
<td>NOMEMORYHEAPS</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>BIOSOBJSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>MALLOCSSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>ARGSSSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>STACKSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>SYSSSTACKSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>GBLINITSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>TRCDATASEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>SYSDATASEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>OBJSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>BIOSSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>SYSSINITSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>HWISEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>HWIVECSEG</td>
<td>Reference</td>
<td>prog.get(&quot;VECT&quot;)</td>
</tr>
<tr>
<td>RTDXTTEXTSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>USERCOMMANDFILE</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>TEXTSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>SWITCHSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>BSSSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>CINITSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>PINITSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>CONSTSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>DATASEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>CIOSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
<tr>
<td>ENABLELOADADDR</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>LOADBIOSSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>LOADSYSINITSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>LOADGBLINITSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>LOADTRCDATASEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>LOADTEXTSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>LOADSWITCHSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>LOADCINITSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>LOADPINITSEG</td>
<td>Reference</td>
<td>prog.get(&quot;SARAM&quot;)</td>
</tr>
<tr>
<td>LOADCONSTSEG</td>
<td>Reference</td>
<td>prog.get(&quot;DARAM&quot;)</td>
</tr>
</tbody>
</table>
MEM Module

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.

<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>base</td>
<td>Numeric</td>
<td>0x000000</td>
</tr>
<tr>
<td>len</td>
<td>Numeric</td>
<td>0x000000</td>
</tr>
<tr>
<td>createHeap</td>
<td>Bool</td>
<td>true</td>
</tr>
<tr>
<td>heapSize</td>
<td>Numeric</td>
<td>0x03f80</td>
</tr>
<tr>
<td>enableHeapLabel</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<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>
</tbody>
</table>

Instance Configuration Parameters

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 malloc, free, and calloc functions. 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.

Note that settings you specify in the Visual Linker normally override settings you specify in the configuration. See the Visual Linker help for details on using the Visual Linker with DSP/BIOS.

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 run-time 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 run-time via the XXX_create functions is disabled.

Tconf Name: BIOSOBJSEG Type: Reference
Example: bios.MEM.BIOSOBJSEG = prog.get("myMEM");
MEM Module

- **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: ARGSEG Type: Reference
  Example: `bios.MEM.ARGSEG = 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: OBJSEGG Type: Reference
Example: `bios.MEM.OBJSEGG = prog.get("myMEM");`

BIOS Code tab

BIOS Code Section (.bios). The memory segment containing the DSP/BIOS code.

Tconf Name: BIOSSEGG Type: Reference
Example: `bios.MEM.BIOSSEGG = prog.get("myMEM");`

Startup Code Section (.sysinit). The memory segment containing DSP/BIOS startup initialization code; this memory can be reused after main starts executing.

Tconf Name: SYSINITSEGG Type: Reference
Example: `bios.MEM.SYSINITSEGG = 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: HWIVECSEGG Type: Reference
Example: `bios.MEM.HWIVECSEGG = prog.get("myMEM");`

RTDX Text Segment (.rtdx_text). The memory segment containing the code sections for the RTDX module.

Tconf Name: RTDXTEXTSEGG Type: Reference
Example: `bios.MEM.RTDXTEXTSEGG = 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");
MEM Module

- **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: LOADTRCDATASEG  
  Type: Reference  
  Example:  
  ```
  bios.MEM.LOADTRCDATASEG = 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");
  ```
MEM Module

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  
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  
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  
Example: bios.MEM.LOADHWISEG = prog.get("myMEM");

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  
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: LOADRDTDTEXTSEG  
Example: bios.MEM.LOADRDTDTEXTSEG = 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.

Note that settings you specify in the Visual Linker normally override settings you specify in the configuration. See the Visual Linker help for details on using the Visual Linker with DSP/BIOS.
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>
<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>

Table 2-5. Typical Memory Segments for C5000 Boards
### MEM_alloc

#### Allocate from a memory segment

**C Interface**

**Syntax**

```c
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 A-2 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.

*Figure 2-2. MYSEG Memory Map After Allocation*

- 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 for 0x6000. 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.

- \( P2 = \text{MEM\_alloc}(\text{MYSEG}, 0x1800, 0); \)
  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.

- \( P4 = \text{MEM\_alloc}(\text{MYSEG}, 0x800, 0); \)
  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 MEMAlloc calls were made in the following sequence:

- \( P1 = \text{MEM\_alloc}(\text{MYSEG}, 0x6000, 0); \)
- \( P2 = \text{MEM\_alloc}(\text{MYSEG}, 0x1800, 0); \)
- \( P3 = \text{MEM\_alloc}(\text{MYSEG}, 0xFF80, 0); \)
- \( P4 = \text{MEM\_alloc}(\text{MYSEG}, 0x800, 0); \)

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.
MEM_alloc

- 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 MEM_alloc 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

```c
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.
MEM_define

- 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**

```c
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**

```c
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**

```c
addr = MEM_valloc(segid, size, align, value);
```

**Parameters**

- `Int segid; /* memory segment identifier */`
- `size_t size; /* block size in MADUs */`
- `size_t align; /* block alignment */`
- `Char value; /* character value */`

**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_alloc.** Allocate a message. Performed by writer.
- **MSGQ_close.** Closes a message queue. Performed by reader.
- **MSGQ_count.** Return the number of messages in a message queue.
- **MSGQ_free.** Free a message. Performed by reader.
- **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_open.** Opens a message queue. Performed by reader.
- **MSGQ_put.** Place a message on a message queue. Performed by writer.
- **MSGQ_release.** Release a located 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 Module

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;
MSGQ Module

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 1-3.

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.

![Figure 2-4. Writers and Reader of a Message Queue](image)

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 2-233. 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).

Figure 2-5. Components of the MSGQ Architecture

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).

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:

Figure 2-6. MSGQ Function Calling Sequence

The reader calls the following APIs:
MSGQ Module

- 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 2-238)
- MSGQ_config variable in application code (see below)
- PROCID property of the GBL module using Tconf (see “GBL Module Properties” on page 2-109)
- ENABLEPOOL property of the POOL module using Tconf (see “POOL Manager Properties” on page 2-289)
- POOL_config variable in application code (see “Static Configuration” on page 2-286)

An application must provide a filled in MSGQ_config variable in order to use the MSGQ module.

MSGQ_Config MSGQ_config;

The MSGQ_Config type has the following structure:
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:

typedef struct MSGQ_TransportObj {
    MSGQ_MqtInit initFxn;    /* Transport init func */
    MSGQ_TransportFxns *fxns; /* Interface funcns */
    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>proclid</td>
<td>Uint16</td>
<td>Numeric ID of the processor that this transport communicates with. The current processor must have a proclid 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:

```c
#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:

  ```c
  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:

  ```c
  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.
transports[0].initFxn = ...  
transports[0].fxns = ...  
transports[0].object = ...  
transports[0].params = ...  
transports[0].procId = 0;  
transports[1] = MSGQ_NOTTRANSPORT; // 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 2-234.

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 2-234) is initialized.

  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 2-286.)

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

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**

- `MSGQ_Queue msgqQueue; /* Message queue to count */`
- ` Uns *count; /* Pointer to returned count */`

**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

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

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, SYS_ETIMEOUT 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(msgQueue);
```

**Parameters**  
- **MSGQ_Queue** `msgQueue;` /* 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**

```c
status = MSGQ_locate(queueName, msgqQueue, locateAttrs);
```

**Syntax**

- `status` 
- `queueName` /* Name of message queue to locate */
- `msgqQueue` /* Return located message queue here */
- `locateAttrs` /* Locate attributes */

**Parameters**

- String `queueName`;
- MSGQ_Queue `msgqQueue`;
- MSGQ_LocateAttrs `locateAttrs`;

**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:
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:

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

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**

```c
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:

```c
/* Asynchronous locate message ID */
#define MSGQ_ASYNCLOCATEMSGID   0xFF00
```

The MSGQ_LocateAsyncAttrs structure has the following fields:

```c
typedef struct MSGQ_LocateAsyncAttrs {
    Uint16      poolId;
    Arg         arg;
} MSGQ_LocateAttrs;
```

The default attributes are as follows:

```c
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 indicate 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
define 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>
</tbody>
</table>
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`.

---

**MSGQ_open**

<table>
<thead>
<tr>
<th>Pend</th>
<th>MSGQ_Pend</th>
<th>Function pointer to a user-specified pend function.</th>
</tr>
</thead>
<tbody>
<tr>
<td>Post</td>
<td>MSGQ_Post</td>
<td>Function pointer to a user-specified post function.</td>
</tr>
</tbody>
</table>

---

Application Program Interface  2-255
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_Post)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

```c
/* 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

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**

```c
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

Syntax

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:

/* Asynchronous error message ID */
#define MSGQ_ASYNCERRORMSGID   0xFF01

The following is the structure for an asynchronous error message:

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>
<tr>
<td>mqtId</td>
<td>Uint16</td>
<td>ID of the transport that sent the error message</td>
</tr>
<tr>
<td>parameter</td>
<td>Uint16</td>
<td>Error-specific field</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_MQTERREOREXIT</td>
<td></td>
<td>ID of the transport that is exiting. Not used.</td>
</tr>
<tr>
<td>MSGQ_MQTFAILEDPUT</td>
<td></td>
<td>ID of the transport that failed to send a message.</td>
</tr>
<tr>
<td>MSGQ_MQTERRORENTAL</td>
<td></td>
<td>ID of destination queue. The parameter is 16 bits, so only the lower 16 bits of the msgqQueue 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 msgqQueue.</td>
</tr>
<tr>
<td>MSGQ_MQTERRORINTERNAL</td>
<td></td>
<td>Generic internal error. Transport defined.</td>
</tr>
<tr>
<td>MSGQ_MQTERRORPHYSICAL</td>
<td></td>
<td>Problem with the physical link. Transport defined.</td>
</tr>
<tr>
<td>MSGQ_MQTERRORALLOC</td>
<td></td>
<td>Transport could not allocate memory. 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**

`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 - 0xFFFE`
- 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`. |
### MSGQ_setMsgId

**Example**

```c
/* 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

**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 Note:** 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 still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

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.
PIP Module

- **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 1-3.

#### 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>notifyWriterFxn</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>notifyReaderFxn</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 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.PIPE.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: myPip.bufAlign = 1;

- **framesize.** The length of each frame (in words)
  Tconf Name: frameSize Type: Int16
  Example: myPip.frameSize = 8;

- **numframes.** The number of frames
  Tconf Name: numFrames Type: Int16
  Example: 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: "reader", "writer", "none"
  Example: 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: notifyWriterFxnxn Type: Extern
Example: myPip.notifyWriterFxnxn =
           prog.extern("writerFxnxn");

- nwarg0, nwarg1. Two Arg type arguments for the notifyWriter function.
  Tconf Name: notifyWriterArg0 Type: Arg
  Tconf Name: notifyWriterArg1 Type: Arg
  Example: 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: notifyReaderFxnxn Type: Extern
  Example: myPip.notifyReaderFxnxn =
            prog.extern("readerFxnxn");

- nrarg0, nrarg1. Two Arg type arguments for the notifyReader function.
  Tconf Name: notifyReaderArg0 Type: Arg
  Tconf Name: notifyReaderArg1 Type: Arg
  Example: myPip.notifyReaderArg0 = 0;
Important Note: 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

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 2–147, also uses a pipe with host channel objects.

See Also
PIP_free
PIP_get
PIP_put
HST_getpipe
Important Note: 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

C Interface

Syntax

```c
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 2–271. The example for `HST_getpipe`, page 2–147, also uses a pipe with host channel objects.

See Also

- `PIP_alloc`
- `PIP_get`
- `PIP_put`
- `HST_getpipe`
Important Note: 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

C Interface

Syntax

```c
PIP_get(pipe);
```

Parameters

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>PIP_Handle pipe; /* pipe object handle */</td>
<td></td>
</tr>
</tbody>
</table>

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 2–271. The example for HST_getpipe, page 2–147, also uses a pipe with host channel objects.

See Also

PIP_alloc
PIP_free
PIP_put
HST_getpipe
Important Note: 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

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);
}
**Important Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**C Interface**

**Syntax**

```c
num = PIP_getReaderNumFrames(pipe);
```

**Parameters**

- `PIP_Handle pipe;` /* pip object handle */

**Return Value**

- `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 2–275.
**PIP_getReaderSize**

*Get the number of words of data in a pipe frame*

**Important Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### 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 2–275.
**Important Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### 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 2–275.
**PIP_getWriterNumFrames**  
*Get number of pipe frames available to be written to*

**Important Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**C Interface**

**Syntax**

```c
num = PIP_getWriterNumFrames(pipe);
```

**Parameters**

- `PIP_Handle pipe;` /* pipe object handle*/

**Return Value**

- `Uns num;` /* number of empty frames to be written */

**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 2–275.
**Important Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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);
}
```
**Important Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**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 Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### 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 2–271. The example for `HST_getpipe`, page 2–147, also uses a pipe with host channel objects.

**See Also**

- `PIP_alloc`
- `PIP_free`
- `PIP_get`
- `HST_getpipe`
**Important Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

**C Interface**

**Syntax**

```c
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
**Important Note:** 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. The PIP module is still supported in DSP/BIOS 5.32 and will be supported in any patch releases or minor enhancements to DSP/BIOS 5.32.

### 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 2–275.
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 1-3.

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.

![Allocators and Message Pools](image)

**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 2-289)
- 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 \texttt{POOL\_Obj} structure:

\begin{verbatim}
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;
\end{verbatim}

The fields in the \texttt{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 (\texttt{STATICPOOL}) is shipped with DSP/BIOS. Additional allocator implementations can be created by application writers.

\textbf{STATICPOOL \underline{Allocator}}

The \texttt{STATICPOOL} allocator takes a user-specified buffer and allocates fixed-size messages from the buffer. The following are its configuration parameters:

\begin{verbatim}
typedef struct STATICPOOL\_Params {
    Ptr addr;
    size_t length;
    size_t bufferSize;
} STATICPOOL\_Params;
\end{verbatim}
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:

![Figure 2-9. Buffer Layout as Defined by STATICPOOL_Params](image)

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
};
```

2-288
To configure the POOL manager, the POOL_Config structure must be defined in the application code. See “Static Configuration” on page 2-286.

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 2-286) 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 1-3.

### 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* 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**

```c
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 2–39, 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**

```c
/* ======== showTicks ======== */
Void showTicks
{
    LOG_printf(&trace, "ticks = \%d", PRD_getticks());
}
```

**See Also**

PRD_start
PRD_tick
CLK_gethtime
CLK_getltime
STS_delta

---

2-294
**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 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*

![Tick Tick Tick]

Time to first tick after PRD_start is called.

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 stops 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 'C55x 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.
- 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.
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

```c
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.</td>
</tr>
</tbody>
</table>
|                           | For example, a client has registered with PWRM indicat-
|                           | ing that it cannot support the requested V/F setpoint. |
| PWRM_EOUTOF RANGE         | The operation could not be completed                    |
|                           | because a parameter was out of the range supported by   |
|                           | PWRM.                                                   |
| PWRM_ETIMEOUT             | A timeout occurred while trying to complete the opera-
|                           | tion.                                                  |
| PWRM_ETOOMANYCALLS        | Indicates PWRM_releaseDependency has been called more  |
|                           | times for a resource than PWRM_setDependency was called.|
| PWRM_EBUSY                | The requested operation cannot be performed at this    |
|                           | time; PWRM is busy processing a previous request.      |
| PWRM_EINITFAILURE         | A failure occurred while initializing V/F scaling       |
|                           | support; V/F scaling is unavailable.                   |

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>
</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 1-3.

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_IDLEIPORT</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>PWRM_IDLEHWA</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>PWRM_IDLEMPORT</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>PWRM_IDLEXPORT</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>NAME</td>
<td>Usage</td>
<td></td>
</tr>
<tr>
<td>PWRM_IDLEIPORT</td>
<td>Idle the IPORT clock domain (OMAP 2420 only)</td>
<td></td>
</tr>
<tr>
<td>PWRM_IDLEHWA</td>
<td>Idle the HWA clock domain (OMAP 2420 only)</td>
<td></td>
</tr>
<tr>
<td>PWRM_IDLEMPORT</td>
<td>Idle the MPORT clock domain (OMAP 2420 only)</td>
<td></td>
</tr>
<tr>
<td>PWRM_IDLEXPORT</td>
<td>Idle the XPORT clock domain (OMAP 2420 only)</td>
<td></td>
</tr>
<tr>
<td>NAME</td>
<td>Type</td>
<td>Default (Enum Options)</td>
</tr>
<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>DEVICEDBMEMSEG</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>
<tr>
<td>INITIALFREQ</td>
<td>Numeric</td>
<td>15</td>
</tr>
<tr>
<td>INITVOLTS</td>
<td>Numeric</td>
<td>1.6</td>
</tr>
<tr>
<td>SCALEVOLT</td>
<td>Bool</td>
<td>false</td>
</tr>
<tr>
<td>WAITVOLT</td>
<td>Bool</td>
<td>true</td>
</tr>
</tbody>
</table>
Examples

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:

- **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: DEVICESDBMEMSEG Type: Reference
Example: bios.PWRM.DEVICESDBMEMSEG = 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;

PERIPHERALS. Checking this box causes the PERIPHERALS 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 PCRs, timers via the IDLE_EN bit in the TCRs, the ADC module via the IdleEn bit in the ADCCR, the I2C module via the IDLEEN bit in the ICMRDR, USB via the IDLEEN bit in the 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 2-310.

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.PWRM.SCALEVOLT = 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 over-clocking 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 PERIPHS 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;

Wake up interrupt mask, IER0. Specifies the wake up 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;

Wake up interrupt mask, IER1. Specifies the wake up 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**

```c
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 PWRMETIMEOUT.

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_ENOTIMPLEMENTED</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**

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;
Int i;

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 */

Reentrant

yes

Description

PWRM_configure specifies new configuration properties for the PWRM module. It overrides those specified in the static configuration.

The PWRM_Attrs parameter you pass to PWRM_configure has the following structure:

```c
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" property in the V/F Scaling tab of the configuration. If scaleVoltage is TRUE, the voltage is scaled down if possible when going to a lower frequency. If scaleVoltage is FALSE, the voltage is not scaled lower. The voltage is always scaled up if the new 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" property in the V/F Scaling tab of the configuration. 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 over-clocking 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>
<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_IDLEIIMPORT</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>

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_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 attrs parameter was NULL.</td>
</tr>
<tr>
<td>PWRM_EINVALIDVALUE</td>
<td>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.</td>
</tr>
</tbody>
</table>
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 EINVALSOURCE</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_EINVALIDPOINTER</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 resource

C Interface

Syntax

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

/* 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 the 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_EINVALIDPOINTER</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);
LOG_printf(TRACE, "NumSetpoints: %d", numSetpoints);
if (status != PWRM_SOK) { /* exit on error */
    LOG_printf(TRACE, "Error: status = %x", status);
    return;
}
```
**PWRM_getSetpointInfo**

*Get frequency and CPU core voltage for a setpoint*

**C Interface**

**Syntax**

```c
status = PWRM_getSetpointInfo(setpoint, frequency, voltage);
```

**Parameters**

- `Uns setpoint; /* the setpoint to query */`
- `float *frequency; /* DSP core frequency */`
- `float *voltage; /* DSP voltage */`

**Return Value**

- `PWRM_Status 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_EINVALIDVALUE</td>
<td>The operation failed because the setpoint parameter was invalid.</td>
</tr>
<tr>
<td>PWRM_EINVALIDPOINTER</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>
</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**

```
PWRM_Status status;
Uns numSetpoints = 16;
Uns frequencyLatency;
Uns voltageLatency;

status = PWRM_getTransitionLatency((numSetpoints - 1), 0, &frequencyLatency, &voltageLatency);
LOG_printf(TRACE, "Frequency latency: %d, Voltage latency: %d", frequencyLatency, voltageLatency);
if (status != PWRM_SOK) { /* exit on error */
    LOG_printf(TRACE, "Error: status=%x", status);
    return;
}
```
PWRM_idleClocks

**PWRM_idleClocks** *Immediately idle clock domains*

**C Interface**

Syntax

```c
status = PWRM_idleClocks(domainMask, idleStatus);
```

Parameters

<table>
<thead>
<tr>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Uns domainMask</td>
<td>/* bitmask of clock domains to be idled */</td>
</tr>
<tr>
<td>Uns <em>idleStatus</em></td>
<td>/* contents of ISTR after idling */</td>
</tr>
</tbody>
</table>

Return Value

<table>
<thead>
<tr>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>PWRM_Status</td>
<td>/* returned status */</td>
</tr>
</tbody>
</table>

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_IDLEXPORT</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_EINVALIDPOINTER</td>
<td>Operation failed because the idleStatus parameter was NULL.</td>
</tr>
<tr>
<td>PWRM_EINVALIDVALUE</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

status = PWRM_registerNotify(eventType, eventMask, notifyFxn,
clientArg, notifyHandle, delayedCompletionFxn);

Parameters

PWRM_Event eventType; /* type of power event */
LgUns eventMask; /* event-specific mask */
Fxn notifyFxn; /* function to call on event */
Arg clientArg; /* argument to pass to notifyFxn */
PWRM_NotifyHandle *notifyHandle; /* handle for unregistering */
Fxn *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. This parameter has an enumerated type of PWRM_Event. 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 deep sleep.</td>
</tr>
<tr>
<td>PWRM_AWAKEFROMDEEPSLEEP</td>
<td>The DSP has awoken from deep sleep.</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.

The notifyFxn parameter specifies the function to call when the specified power event occurs. The notifyFunction must behave as described in the pwrmNotifyFxn 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 delayedCompletionFxn 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 delayedCompletionFxn to signal PWRM that it has finished. The delayedCompletionFxn 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 delayedCompletionFxn.

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 delayedCompletionFxn 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 EINVALPOINTER</td>
<td>The operation failed because the notifyFxn, notifyHandle or delayedCompletionFxn parameter was NULL.</td>
</tr>
<tr>
<td>PWRM EINVALEVENT</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

```c
/* client allows all setpoints */
#define ALLSETPOINTSALLOWED 0xFFFF
/* client doesn't allow lowest 4 setpoints */
#define SOMESETPOINTSALLOWED 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,
                    ALLSETPOINTSALLOWED, (Fxn)myNotifyFxn1,
                    (Arg)0x1111, &notifyHandle1, (Fxn *) &delayFxn1);

/* Client 2 registers post-setpoint notification */
PWRM_registerNotify(PWRM_DONESETPOINTCHANGE,
                    SOMESETPOINTSALLOWED, (Fxn)myNotifyFxn2,
                    (Arg)0x2222, &notifyHandle2, &delayFxn2);
```
Function to be called on a registered power event

C Interface

Syntax

```c
status = notifyFxn(eventType, eventArg1, eventArg2, clientArg);
```

Parameters

- `eventType`: /* type of power event */
- `eventArg1`: /* event-specific argument */
- `eventArg2`: /* event-specific argument */
- `clientArg`: /* arbitrary argument */

Return Value

- `PWRM_NotifyResponse status`: /* returned status */

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:

- **PWRM_PENDINGSETPOINTCHANGE.** The `eventArg1` holds the current setpoint, and `eventArg2` holds the pending setpoint.
- **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>
<tr>
<td>PWRM_NOTIFYERROR</td>
<td>Notification cannot be processed. Either an internal client error occurred or the client was notified of an event it could not process. (For V/F setpoint changes, the client registers setpoints it can accommodate to avoid this error.) When a client returns this error, the caller of the PWRM function that triggered the notification receives a PWRM_EFAIL return status.</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, "\nclient #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 */  
}
```

2-330
**PWRM_releaseDependency**

*Release a dependency that was previously declared*

**C Interface**

**Syntax**

```c
status = PWRM_releaseDependency(resourceID);
```

**Parameters**

- `Uns resourceID; /* resource ID */`

**Return Value**

- `PWRM_Status 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**

```c
/* Release default dependency on CLKOUT to save power*/
PWRM_releaseDependency(PWRM_5509A_CLKOUT);
```
**PWRM_setDependency**

Declare a dependency upon a resource

**C Interface**

**Syntax**

```c
status = PWRM_setDependency(resourceID);
```

**Parameters**

- `Uns resourceID; /* resource ID */`
- `PWRM_Status status; /* returned status */`

**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);
```
**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 following constants may be used:

<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 <code>sleepArg</code>.</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 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 EINVALHANDLE</td>
<td>Operation failed because <code>notifyHandle</code> is invalid.</td>
</tr>
</tbody>
</table>

**Constraints and Calling Context**

- This API cannot be called from a program’s main() function.

**Example**

```c
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

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 1-3.

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>
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.

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");`
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.

```javascript
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.
  - **Tconfig Name:** comment  
  - **Type:** String
  - **Example:** `myQue.comment = "my QUE";`
**QUE_create**  
Create an empty queue

### C Interface

**Syntax**
```
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 2–205.

### 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

---

*Application Program Interface*  
2-339
# QUE_delete

Delete an empty queue

## C Interface

### Syntax

```c
QUE_delete(queue);
```

### Parameters

- `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 `QUE`. `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

- **queue**: /* queue object handle */

Return Value

- **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 ((QUE_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**

```
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**

```c
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

Ptr qelem; /* element in queue */

Return Value

Ptr elem; /* next element in queue */

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**

Ptr qelem; /* element in queue */

**Return Value**

Ptr elem; /* previous element in queue */

**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 preemted by another thread that operates on the same queue.

See Also
QUE_get
QUE_head
**C Interface**

**Syntax**

`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`).

---

*Application Program Interface* 2-351
| **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

- 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 1-3.

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, rtx.i, is a macro interface file that can be used to interface to RTDX at the assembly level.

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.

```
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:**  
    ```
    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:**  
    ```
    myRtdx.channelMode = "output";
    ```

---

### Examples

The `rtdx.xls` example is in the `TI_DIR\examples\hostapps\rtdx` folder. The examples are described below.

- **Ta_write.asm**. Target to Host transmission example. This example sends 100 consecutive integers starting from 0. In the `rtdx.xls` file, use the `h_read` VB macro to view data on the host.

- **Ta_read.asm**. Host to target transmission example. This example reads 100 integers. Use the `h_write` VB macro of the `rtdx.xls` file to send data to the target.

- **Ta_readNB.asm**. Host to target transmission example. This example reads 100 integers. Use the `h_write` VB macro of the `rtdx.xls` file to send data to the target. This example demonstrates how to use the non-blocking read, RTDX_readNB, function.

---

**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

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

口 RTDX_CreateInputChannel cannot be called by an HWI function.

See Also

RTDX_CreateOutputChannel
### RTDX_CreateOutputChannel

*Declare output channel structure*

#### C Interface

<table>
<thead>
<tr>
<th>Syntax</th>
<th>RTDX_CreateOutputChannel( ochan );</th>
</tr>
</thead>
<tbody>
<tr>
<td>Parameters</td>
<td>ochan /* Label for the output channel */</td>
</tr>
<tr>
<td>Return Value</td>
<td>none</td>
</tr>
<tr>
<td>Reentrant</td>
<td>no</td>
</tr>
<tr>
<td>Description</td>
<td>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.</td>
</tr>
</tbody>
</table>

#### 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**

```c
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**

`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

RTDX_isInputEnabled( ichan );

Parameter

ichan /* Identifier for an input channel. */

Return Value

0 /* Not enabled. */
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

RTDX_isOutputEnabled(ohan);

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

```c
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 1-3.

**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 makes available 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**

```
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

sem = SEM_create(count, attrs);

Parameters

Int count; /* initial semaphore count */
SEM_Attr 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.

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.

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

Application Program Interface 2-373
**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**

- `SEM_Handle 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**

- `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_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 SYS_FOREVER, 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 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_pend if the semaphore count is 0 and timeout is not zero.

**Constraints and Calling Context**

- SEM_pend cannot 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

2-376
**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**

```c
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

Signal a binary semaphore

C Interface

Syntax

SEM_postBinary(sem);

Parameters

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

```c
SEM_reset(sem, count);
```

Parameters

- `SEMHANDLE 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 1-3.

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>**</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>Bool</td>
<td>false</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>
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 if the timeout parameter is 0. TSK threads can be used with either model.

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:  
  ```c
  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:  
  ```c
  bios.SIO.USEISSUERECLAIM = false;
  ```

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.
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_ETIMOUT) and no buffer is returned.

Tconf Name: timeout Type: Int16
Example: 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

\[
\text{size} = \text{SIO_bufsize} (\text{stream});
\]

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 { /* 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;
    /* 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.

Existing 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

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

<table>
<thead>
<tr>
<th>Syntax</th>
<th>status = SIO_flush(stream);</th>
</tr>
</thead>
<tbody>
<tr>
<td>Parameters</td>
<td>SIO_Handle stream; /* stream handle */</td>
</tr>
<tr>
<td>Return Value</td>
<td>Int status; /* result of operation */</td>
</tr>
</tbody>
</table>

#### 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**

```c
SIO_handle stream /* stream handle */
Ptr *bufp; /* pointer to a buffer */

Int nmadus; /* number of MADUs read or error if negative */
```

**Parameters**
- **stream**: SIO_Handle
- **bufp**: Ptr

**Return Value**
- **nmadus**: Int

**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_ETIMEOUT) 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

- `SIO_Handler stream; /* stream handle */`
- `Ptr pbuf; /* pointer to a buffer */`
- `size_t nmadus; /* number of MADUs in the buffer */`
- `Arg arg; /* user argument */`

Return Value

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

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, 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

```c
int nmadus = SIO_put(stream, bufp, nmadus);
```

Parameters

- `SIO_Handle stream; /* stream handle */`
- `Ptr *bufp; /* pointer to a buffer */`
- `size_t nmadus; /* number of MADUs in the buffer */`

Return Value

- `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 * SYS_ETIMEOUT` 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**

```
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 dereference 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 \texttt{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 \texttt{attrs.model} set to \texttt{SIO\_ISSUERECLAIM}.
- There must be at least one outstanding \texttt{SIO\_issue} when an \texttt{SIO\_reclaim} call is made.
- \texttt{SIO\_reclaim} returns an error if it is called from a SWI when no buffer is available. \texttt{SIO\_reclaim} does not block if called from a SWI.
- All frames issued to a stream must be reclaimed before closing the stream.
- \texttt{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

- \texttt{Dxx\_reclaim}
- \texttt{SIO\_issue}
- \texttt{SIO\_create}
- \texttt{SIO\_reclaimx}
SIO_reclaimx

Request a buffer back from a stream, including frame status

C Interface

Syntax

\[ \text{nmmadus} = \text{SIO_reclaimx}(\text{stream}, \text{pbufp}, \text{parg}, \text{pfstatus}); \]

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 nmmadus; /* 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 `nmmadus` 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

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

nmmadus = SIO_staticbuf(stream, bufp);

Parameters

SIO_Handle stream; /* stream handle */
Ptr *bufp; /* pointer to a buffer */

Return Value

Int nmmadus; /* 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 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 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 1-3.

**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>
</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 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.

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 2-11 shows the effects of the $(A \times X + B) / C$ operation.

**Figure 2-11. Statistics Accumulation on the Host**

### 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");`

### STS Object Properties

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.
  Tconf Name: comment Type: String
  Example: `mySts.comment = "my STS";`
• prev. The initial 32-bit history value to use in this object.
  Tconf Name: previousVal Type: Int32
  Example: mySts.previousVal = 0;

• 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.
  Tconf Name: unitType Type: EnumString
  Options: "Not time based", "High resolution time based", "Low resolution time based"
  Example: mySts.unitType = "Not time based";

• 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 x X
  ■ A x X + B
  ■ (A x X + B) / C
  Tconf Name: operation Type: EnumString
  Example: mySts.operation = "Nothing";

• A, B, C. The integer parameters used by the expression specified by the Host Operation property above.
  Tconf Name: numA Type: Int32
  Tconf Name: numB Type: Int32
  Tconf Name: numC Type: Int32
  Example: mySts.numA = 1;
            mySts.numB = 0;
            mySts.numC = 1;
**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**

- `STS_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_getltm`
- `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**

`STS_set(sts, value);`

**Parameters**

- `STS_Handle sts;` /* statistics object handle */
- `LgInt value;` /* new value to update statistics object */

**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.
STS_set

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 */
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 1-3.

### 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 2-180.

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.)
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 processing 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_swi 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.

<table>
<thead>
<tr>
<th>Always post</th>
<th>Treat mailbox as bitmask</th>
<th>Treat mailbox as counter</th>
<th>Does not modify mailbox</th>
</tr>
</thead>
<tbody>
<tr>
<td>SWI_or</td>
<td>SWI_inc</td>
<td>SWI_post</td>
<td></td>
</tr>
<tr>
<td>Post if becomes 0</td>
<td>SWI_andn</td>
<td>SWI_dec</td>
<td></td>
</tr>
</tbody>
</table>
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:**  
  ```java
  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:**  
  ```javascript
  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:**  
  ```javascript
  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:**  
  ```javascript
  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**

- `SWI_Handle swi; /* SWI object handle*/`
- `Uns mask /* inverse value to be ANDed */`

**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.

![Mailbox value transition diagram]

**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**

```
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**

```
/* ======== 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 2–205.

**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**

```c
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

```c
/* ======== 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**
  
  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
void 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
Get attributes of a software interrupt

C Interface

Syntax

```
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:

```
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**

Void

**Return Value**

Uns `num` /* mailbox value */

**Reentrant**

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 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**

```c
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

```c
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**

```c
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**

`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

```c
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**

```
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**

<table>
<thead>
<tr>
<th><strong>C Interface</strong></th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Syntax</strong></td>
</tr>
<tr>
<td><strong>Parameters</strong></td>
</tr>
<tr>
<td><strong>Return Value</strong></td>
</tr>
<tr>
<td><strong>Reentrant</strong></td>
</tr>
</tbody>
</table>

**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**  
```c
SWI_restorepri(key);
```

**Parameters**  
```c
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` 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**
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:

```
SWI_post(SWI_self());
```

**See Also**
SWI_andn
SWI_getmbox
SWI_post
SWI_setattrs

Set attributes of a software interrupt

C Interface

Syntax

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
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_getattrs(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_ETIMEOUT   9  /* call timed out */
#define SYS_EEOF       10 /* end-of-file */
#define SYS_EDEAD      11 /* deleted obj */
#define SYS_EBADOBJ    12 /* invalid object */
#define SYS_ENOTIMPL   13 /* action not implemented */
#define SYS_ENOTFOUND  14 /* resource not found */
#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 1-3.
**SYS Module**

**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>
<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>

**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 Code Composer Studio 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:
  
  ```c
  Void myAbort(String fmt, va_list ap);
  ```

  **Tconf Name:** ABORTFXN  **Type:** Extern

  **Example:**
  ```c
  bios.SYS.ABORTFXN =
                       prog.extern("myAbort");
  ```

- **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:

  ```c
  Void myError(String s, Int errno, va_list ap);
  ```

  **Tconf Name:** ERRORFXN  **Type:** Extern

  **Example:**
  ```c
  bios.SYS.ERRORFXN =
                       prog.extern("myError");
  ```

- **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:

  ```c
  Void myExit(Int status);
  ```

  **Tconf Name:** EXITFXN  **Type:** Extern

  **Example:**
  ```c
  bios.SYS.EXITFXN =
                       prog.extern("myExit");
  ```

- **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 Code Composer Studio memory view. The prototype for this function should be:

  ```c
  Void myPutc(Char c);
  ```

  **Tconf Name:** PUTCFXN  **Type:** Extern

  **Example:**
  ```c
  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**
```
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.

```
(*(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
SYS_atexit Stack an exit handler

C Interface

Syntax

success = SYS_atexit(handler);

Parameters

Fxnn handler /* exit handler function */

Return Value

Bool success /* handler successfully stacked */

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:

(*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.

Application Program Interface 2-455
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)

(*Exit_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>

Note that the %f conversion character is supported only on devices that have a native floating point type (for example, the 'C67x).

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_vprintf 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 Code Composer Studio 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_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 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>

Note that the %f conversion character is supported only on devices that have a native floating point type (for example, the 'C67x).
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 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>

Note that the %f conversion character is supported only on devices that have a native floating point type (for example, the 'C67x).
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 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 Code Composer Studio 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

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 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>

Note that the %f conversion character is supported only on devices that have a native floating point type (for example, the 'C67x).
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_vprintf 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**
```
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.

```
((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 Code Composer Studio 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
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 2-11 lists events and statistics that can be traced. The constants defined in trc.h and 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</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 and TRC_USER1</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.</td>
<td>off</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</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>off</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**

```c
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:

```c
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**

```
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:

```
result = TRC_query(TRC_STSPRD);
```

The following C code returns 0 if both logging and statistics tracing for the SWI class are enabled:

```
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:

```
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:

```
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**

```c
Void TSK_createFxn(TSK_Handle task);
Void TSK_deleteFxn(TSK_Handle task);
Void TSK_exitFxn(Void);
Void TSK_readyFxn(TSK_Handle newtask);
Void TSK_switchFxn(TSK_Handle oldtask,
                   TSK_Handle newtask);
```
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 */
    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 */
    TSK->STACKSEG,      /* stack segment */
    NULL,               /* stack */
    #ifdef _55_
        TSK->SYSSTACKSIZE,  /* system stacksize in MADUs */
    #endif
    TSK->STACKSIZE,     /* stack size */
    #ifdef _55_
    TSK->SYSSTACKSIZE,  /* system stack size in MADUs */
    #endif
    "",                 /* name */
    TRUE,              /* exit flag */
    TRUE,              /* initialize stack flag */
};

enum 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 */
    #ifdef _55_
        TSKMode   mode;   /* task execution mode */
    #endif
    size_t      sp;    /* stack pointer */
    #ifdef _55_
        size_t      sp;    /* stack pointer */
    #endif
    size_t      used;  /* stack used */
    #ifdef _55_
        size_t      sysused; /* system stack used */
    #endif
    #endif

    };

Application Program Interface  2-473
### 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>0x0000000000</td>
</tr>
</tbody>
</table>
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.

<table>
<thead>
<tr>
<th>Name</th>
<th>Type</th>
<th>Default (Enum Options)</th>
</tr>
</thead>
<tbody>
<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>
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 myReadyFxn(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: 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.

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: 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: 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.

- **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:** manualStack  
  - **Type:** Extern
  - **Example:**
    ```
    myTsk.manualStack = prog.extern("myStack");
    ```

- **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:**
    ```
    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**  
`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

<table>
<thead>
<tr>
<th>Syntax</th>
<th>task = TSK_create(fxn, attrs, [arg,] ...);</th>
</tr>
</thead>
<tbody>
<tr>
<td>Parameters</td>
<td><code>Fx</code>n: /* pointer to task function */</td>
</tr>
<tr>
<td></td>
<td>TSK_Attrs: /* pointer to task attributes */</td>
</tr>
<tr>
<td></td>
<td>Arg: /* task arguments */</td>
</tr>
<tr>
<td>Return Value</td>
<td>TSK_Handle: task; /* task object handle */</td>
</tr>
<tr>
<td>Description</td>
<td>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).</td>
</tr>
</tbody>
</table>

The `fxn` parameter uses the `Fx`n 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((Fx)n)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 __C55_
        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 (preset to 1024). 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.

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.
TSK_create

- 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**

`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 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. For a complete list, see Section A.1, *Function Callability Table*, page A-2.

- `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 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. For a complete list, see Section A.1, *Function Callability Table*, page A-2.
- 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
TSK_exit

**Terminate execution of the current task**

**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

```c
TSK_Handle task; /* task object handle */
```

Return Value

```c
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

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

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**

```c
curtask = TSK_self();
```

**Parameters**

Void

**Return Value**

```c
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**

```c
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

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**

```c
TSK_settime(task);
```

**Parameters**

```c
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:

```c
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
## TSK_sleep

*Delay execution of the current task*

### C Interface

**Syntax**

```c
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**

```
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:

```
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**

```
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
<table>
<thead>
<tr>
<th><strong>TSK_time</strong></th>
<th>Return current value of system clock</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>C Interface</strong></td>
<td></td>
</tr>
<tr>
<td><strong>Syntax</strong></td>
<td>curtime = TSK_time();</td>
</tr>
<tr>
<td><strong>Parameters</strong></td>
<td>Void</td>
</tr>
<tr>
<td><strong>Return Value</strong></td>
<td>Uns curtime; /* current time */</td>
</tr>
<tr>
<td><strong>Description</strong></td>
<td>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.</td>
</tr>
</tbody>
</table>
**TSK_yield**

*Yield processor to equal priority task*

**C Interface**

**Syntax**

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 2-180.

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>fprintf</th>
<th>printf</th>
<th>vfprintf</th>
<th>sprintf</th>
</tr>
</thead>
<tbody>
<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.

<table>
<thead>
<tr>
<th>Topic</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>A.1 Function Callability Table</td>
<td>A–2</td>
</tr>
<tr>
<td>A.2 DSP/BIOS Error Codes</td>
<td>A–11</td>
</tr>
</tbody>
</table>
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

<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>
<th>Callable from main()?</th>
</tr>
</thead>
<tbody>
<tr>
<td>ATM_andi</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_andu</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_cleari</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_clearu</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_deci</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_decu</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_inci</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_incu</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_ori</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_oru</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_seti</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>ATM_setu</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>BUF_alloc</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>BUF_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>BUF_delete</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>BUF_free</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>BUF_maxbuff</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>BUF_stat</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>C55_disableIER0, C55_disableIER1</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>C55_disableInt</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>C55_enableIER0, C55_enableIER1</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>C55_enableInt</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>C55_l2AckInt</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>Function</td>
<td>Callable by TSKs?</td>
<td>Callable by SWIs?</td>
<td>Callable by HWIs?</td>
<td>Possible Context Switch?</td>
<td>Callable from main()?</td>
</tr>
<tr>
<td>------------------------</td>
<td>------------------</td>
<td>-------------------</td>
<td>------------------</td>
<td>--------------------------</td>
<td>-----------------------</td>
</tr>
<tr>
<td>C55_l2DisableMIR,</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>C55_l2DisableMIR1</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>C55_l2EnableMIR,</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>C55_l2EnableMIR1</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>C55_l2SetIntPriority</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>C55_plug</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>CLK_countspms</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>CLK_cpuCyclesPerHtime</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>CLK_cpuCyclesPerLtime</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>CLK_gethtime</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>CLK_getHltime</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>CLK_getprd</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>CLK_reconfig</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>CLK_start</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>CLK_stop</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>DEV_createDevice</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>DEV_deleteDevice</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>DEV_match</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>GBL_getClkin</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>GBL_getFrequency</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>GBL_getProcId</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>GBL_getVersion</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>GBL_setFrequency</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>GBL_setProcId</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>No*</td>
</tr>
<tr>
<td>Gio_abort</td>
<td>Yes</td>
<td>No*</td>
<td>No*</td>
<td>Yes</td>
<td>No</td>
</tr>
<tr>
<td>Gio_control</td>
<td>Yes</td>
<td>No*</td>
<td>No*</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>Gio_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>Gio_delete</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>Gio_flush</td>
<td>Yes</td>
<td>No*</td>
<td>No*</td>
<td>Yes</td>
<td>No</td>
</tr>
<tr>
<td>Gio_new</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>Gio_read</td>
<td>Yes</td>
<td>No*</td>
<td>No*</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>Gio_submit</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>Gio_write</td>
<td>Yes</td>
<td>No*</td>
<td>No*</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>Hook_getenv</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>Hook_setenv</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
</tbody>
</table>
## Function Callability Table

<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>
<th>Callable from main()?</th>
</tr>
</thead>
<tbody>
<tr>
<td>HST_getpipe</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>HWI_disable</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>HWI_dispatchPlug</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>HWI_enable</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>HWI_enter</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>HWI_exit</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
</tr>
<tr>
<td>HWI_isHWI</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>HWI_restore</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>IDL_run</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>LCK_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>LCK_delete</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>LCK_pend</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>LCK_post</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>LOG_disable</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>LOG_enable</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>LOG_error</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>LOG_event</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>LOG_message</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>LOG_printf</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>LOG_reset</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MBX_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MBX_delete</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>MBX_pend</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>MBX_post</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes*</td>
</tr>
<tr>
<td>MEM_alloc</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_calloc</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_define</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_free</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_getBaseAddress</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_increaseTableSize</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_redefine</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_stat</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_undefine</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MEM_valloc</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_alloc</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>Function</td>
<td>Callable by TSKs?</td>
<td>Callable by SWIs?</td>
<td>Callable by HWIs?</td>
<td>Possible Context Switch?</td>
<td>Callable from main()?</td>
</tr>
<tr>
<td>--------------------------</td>
<td>-------------------</td>
<td>-------------------</td>
<td>-------------------</td>
<td>--------------------------</td>
<td>-----------------------</td>
</tr>
<tr>
<td>MSGQ_close</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_count</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>MSGQ_free</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_get</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>MSGQ_getAttrs</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_getDstQueue</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>MSGQ_getMsgId</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_isLocalQueue</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_locate</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
<td>No</td>
</tr>
<tr>
<td>MSGQ_locateAsync</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>MSGQ_open</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_put</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>MSGQ_release</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>MSGQ_setErrorHandler</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_setMsgId</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>MSGQ_setSrcQueue</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_alloc</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_free</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_get</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_getReaderAddr</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_getReaderNumFrames</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_getReaderSize</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_getWriterAddr</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_getWriterNumFrames</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_getWriterSize</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_peek</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_put</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_reset</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
</tr>
<tr>
<td>PIP_setWriterSize</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PRD_gettime</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PRD_start</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PRD_stop</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PRD_tick</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
</tr>
<tr>
<td>Function</td>
<td>Callable by TSKs?</td>
<td>Callable by SWIs?</td>
<td>Callable by HWIs?</td>
<td>Possible Context Switch?</td>
<td>Callable from main()?</td>
</tr>
<tr>
<td>---------------------------</td>
<td>-------------------</td>
<td>-------------------</td>
<td>-------------------</td>
<td>--------------------------</td>
<td>------------------------</td>
</tr>
<tr>
<td>PWRM_changeSetpoint</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>PWRM_configure</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_getCapabilities</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_getCurrentSetpoint</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_getDependencyCount</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_getNumSetpoints</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_getSetpointInfo</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_getTransitionLatency</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_idleClocks</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_registerNotify</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_releaseDependency</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_setDependency</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>PWRM_sleepDSP</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>PWRM_unregisterNotify</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>QUE_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_delete</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_dequeue</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_empty</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_enqueue</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_get</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_head</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_insert</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_new</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_next</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_prev</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_put</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>QUE_remove</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_channelBusy</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_CreateInputChannel</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_CreateOutputChannel</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_disableInput</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_disableOutput</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_enableInput</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_enableOutput</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_isInputEnabled</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>Function</td>
<td>Callable by TSKs?</td>
<td>Callable by SWIs?</td>
<td>Callable by HWIs?</td>
<td>Possible Context Switch?</td>
<td>Callable from main()?</td>
</tr>
<tr>
<td>------------------------</td>
<td>------------------</td>
<td>------------------</td>
<td>------------------</td>
<td>--------------------------</td>
<td>-----------------------</td>
</tr>
<tr>
<td>RTDX_isOutputEnabled</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_read</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>RTDX_readNB</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>RTDX_sizeofInput</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>RTDX_write</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>SEM_count</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SEM_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SEM_delete</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SEM_new</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SEM_pend</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SEM_pendBinary</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes*</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SEM_post</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SEM_postBinary</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SEM_reset</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SIO_bufsize</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SIO_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SIO_ctrl</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SIO_delete</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SIO_flush</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>SIO_get</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SIO_idle</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SIO_issue</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SIO_put</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SIO_ready</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>SIO_reclaim</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
<td>Yes*</td>
<td>Yes*</td>
</tr>
<tr>
<td>SIO_reclaimx</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
<td>Yes*</td>
<td>Yes*</td>
</tr>
<tr>
<td>SIO_segid</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SIO_select</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SIO_staticbuf</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>STS_add</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>STS_delta</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>STS_reset</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>STS_set</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SWI_andn</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SWI_andnHook</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
</tbody>
</table>
### Function Callability Table

<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>
<th>Callable from main()?</th>
</tr>
</thead>
<tbody>
<tr>
<td>SWI_create</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SWI_dec</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SWI_delete</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>Yes*</td>
<td>Yes</td>
</tr>
<tr>
<td>SWI_disable</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>SWI_enable</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SWI_getattrs</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SWI_getmbox</td>
<td>No</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>SWI_getpri</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SWI_inc</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SWI_isSWI</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SWI_or</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SWI_orHook</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SWI_post</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes*</td>
<td>No</td>
</tr>
<tr>
<td>SWI_raisepri</td>
<td>No</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>SWI_restorepri</td>
<td>No</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
<td>No</td>
</tr>
<tr>
<td>SWI_self</td>
<td>No</td>
<td>Yes</td>
<td>No</td>
<td>No</td>
<td>No</td>
</tr>
<tr>
<td>SWI_setattrs</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_abort</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_atexit</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_error</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_exit</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_printf</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_putchar</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_sprintf</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_vprintf</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>SYS_vsprintf</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TRC_disable</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TRC_enable</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<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>
</tbody>
</table>
## Function Callability Table

<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>
<th>Callable from main()?</th>
</tr>
</thead>
<tbody>
<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_geterr</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_getpri</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_getsts</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>Yes</td>
<td>No</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_seterr</td>
<td>Yes</td>
<td>Yes</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
</tr>
<tr>
<td>TSK_setpri</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>No</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>No</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>Yes</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>
</tbody>
</table>

Function Callability and Error Tables

A-9
## Function Callability Table

<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>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 2-511 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; 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; 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; 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; 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; An invalid parameter was passed.</td>
</tr>
<tr>
<td>SYS EBADIO</td>
<td>6</td>
<td>&quot;(SYS EBADIO): device failure&quot; 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; 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>SYS EDOMAIN</td>
<td>8</td>
<td>&quot;(SYS EDOMAIN): domain error&quot; 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; 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; 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; 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; 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; 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; 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; 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>B–2</td>
</tr>
<tr>
<td>B.2 Register Conventions</td>
<td>B–2</td>
</tr>
<tr>
<td>B.3 Status Register Conventions</td>
<td>B–4</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>
</tbody>
</table>
### Register Conventions

<table>
<thead>
<tr>
<th>Register</th>
<th>Register Name</th>
<th>Type</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<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,</td>
<td>Circular Buffer Start Address Registers</td>
<td>H</td>
<td></td>
</tr>
<tr>
<td>BSA45, BSA67,</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>BSAC</td>
<td></td>
<td></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 andHWIs. 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 2–13 Status Bit Handling

<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></td>
<td>AC0V3</td>
<td>AC3 overflow flag</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td></td>
<td>TC1</td>
<td>Test/control flag 1</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td></td>
<td>TC2</td>
<td>Test/control flag 2</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td></td>
<td>CARRY</td>
<td>Carry Bit</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td></td>
<td>AC0V0</td>
<td>AC0 overflow flag</td>
<td>X</td>
<td>Restored after int</td>
</tr>
<tr>
<td></td>
<td>AC0V1</td>
<td>AC1 overflow flag</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></td>
<td>CPL</td>
<td>Compiler mode</td>
<td>B-1</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>XF</td>
<td>External flag</td>
<td>X,P</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HM</td>
<td>Hold mode</td>
<td>X,P</td>
<td></td>
<td></td>
</tr>
<tr>
<td>INTM</td>
<td>Interrupt Mask</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>M40</td>
<td>Computation mode for the D unit</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>SATD</td>
<td>Saturation mode for the D unit</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>SXMD</td>
<td>Sign-extension mode for the D unit</td>
<td>B-1</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>C16</td>
<td>Dual 16-bit arithmetic mode</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>FRCT</td>
<td>Fractional mode</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>C54CM</td>
<td>C54x-compatible mode</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>ASM</td>
<td>Accumulator shift mode</td>
<td>X</td>
<td>Restored after int</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>DBGM</td>
<td>Debug mode</td>
<td>X</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>EALLOW</td>
<td>Emulation access enable</td>
<td>X</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>RDM</td>
<td>Rounding mode</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>CDPLC</td>
<td>CDP linear/circular configuration</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>AR0-7LC</td>
<td>ARn linear/circular configuration</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>ST3</td>
<td>CAFRZ</td>
<td>Cache freeze</td>
<td>X,P</td>
<td></td>
</tr>
<tr>
<td>CAEN</td>
<td>Cache enable</td>
<td>X,P</td>
<td></td>
<td></td>
</tr>
<tr>
<td>CACLR</td>
<td>Cache clear</td>
<td>X,P</td>
<td></td>
<td></td>
</tr>
<tr>
<td>HINT</td>
<td>Host interrupt</td>
<td>X,P</td>
<td></td>
<td></td>
</tr>
<tr>
<td>CBERR</td>
<td>CPU bus error</td>
<td>X,P</td>
<td></td>
<td></td>
</tr>
<tr>
<td>MPNMC</td>
<td>Microprocessor/Microcomputer mode</td>
<td>X,P</td>
<td></td>
<td></td>
</tr>
<tr>
<td>SATA</td>
<td>Saturation mode for A unit</td>
<td>B-0</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>CLKOFF</td>
<td>CLKOUT disable</td>
<td>X,P</td>
<td></td>
<td></td>
</tr>
<tr>
<td>SMUL</td>
<td>Saturation-on-multiplication mode</td>
<td>B-1</td>
<td>Restored after int</td>
<td></td>
</tr>
<tr>
<td>SST</td>
<td>Saturate-on-store mode</td>
<td>X</td>
<td>Restored after int</td>
<td></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.

<table>
<thead>
<tr>
<th>Topic</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>C.1 Overview</td>
<td>C–2</td>
</tr>
<tr>
<td>C.2 OMAP 2320 and the CLK Module</td>
<td>C–2</td>
</tr>
<tr>
<td>C.3 OMAP 2320 and the HWI Module</td>
<td>C–4</td>
</tr>
<tr>
<td>C.4 OMAP 2320 and the C55 Module</td>
<td>C–8</td>
</tr>
<tr>
<td>C.5 Building DSP/BIOS Applications for OMAP 2320</td>
<td>C–8</td>
</tr>
<tr>
<td>C.6 Usage Examples</td>
<td>C–9</td>
</tr>
</tbody>
</table>
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_getltime) 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.TIMERSELECT = "Timer 1"; // "Timer 0" or "Timer 1"

You can disable the low-resolution CLK function using the following Tconf script commands:

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:

bios.CLK.ENABLEHTIME = 0;  // 0 (disabled) or 1 (enabled)
In the Gconf configuration tool, the CLK properties for the OMAP 2320 are as follows:
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:

\[
bios.HWI.INTC_BASE = 0x7c4800; \quad // 0x7c4800 \text{ is default}
\]
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:

```assembly
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 Code Composer Studio, follow these steps:

1) Open the application's CCStudio 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
#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);
}
```
Usage Examples

C.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)%32);
}

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);
}
```
C.6.3 Enabling an L2 Interrupt Using "interrupt" Keyword

This C code example plugs and enables OMAP 23xx 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, (Fxnr)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.

rief

;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".

```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 43
    C55_enableInt(C55_L2_INT43);
}

-----------------------------------------------
TCONF script
-----------------------------------------------
/*
 * ======== l2_example4.tcf ========
 */

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>D–2</td>
</tr>
<tr>
<td>D.2 OMAP 2420 and the CLK Module</td>
<td>D–2</td>
</tr>
<tr>
<td>D.3 OMAP 2420 and the HWI Module</td>
<td>D–5</td>
</tr>
<tr>
<td>D.4 OMAP 2420 and the C55 Module</td>
<td>D–9</td>
</tr>
<tr>
<td>D.5 Building DSP/BIOS Applications for OMAP 2420</td>
<td>D–9</td>
</tr>
<tr>
<td>D.6 Usage Examples</td>
<td>D–10</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:

\[
\begin{align*}
&\text{bios.PRD.USECLK = false;} \\
&\text{bios.CLK.ENABLECLK = false;}
\end{align*}
\]

ENABLEHTIME. For OMAP 2420, this property enables/disables the high-resolution clock independent of the low-resolution clock. For example:

\[
\text{bios.CLK.ENABLEHTIME = false;}
\]

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 CCStudio) or dedicated ARM code.

```c
hotmenu ProgramMMU()
{
    /* DSP MMU_SYSCONFIG - Set bit 1 to perform a SOFTRESET */
    *(int *)0x5A000010 |= 0x2;

    /* TLB 0 - GPTIMER5 = 0x7000, BigEndian */
    *(int *)0x5A000050 = 0x00000000;    /* DSP MMU_LOCK */
    *(int *)0x5A000058 = 0x00fde00e;    /* DSP MMU_CAM */
    *(int *)0x5A00005C = 0x4807c340;    /* DSP MMU_RAM */
    *(int *)0x5A000054 = 0x00000001;    /* DSP MMU_LD_TLB */

    /* TLB 1 - GPTIMER6 = 0x7400, BigEndian */
    *(int *)0x5A000050 = 0x00000000;    /* 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, BigEndian */
    *(int *)0x5A000050 = 0x00000000;    /* 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;
}
```
OMAP 2420 and the CLK Module

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;
}
```
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:

```
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):
// 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:
H WI 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

H WI 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 Code Composer Studio, follow these steps:

1) Open the application's CCStudio 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 <hwil.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
", ArgToInt(id)%32);
}

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 <hw1.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**

```tcf
/* ======== l2_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
```
# Index

## A
- abort function 2-453
- aborting program 2-454
- AC registers, conventions for B-2
- allocators
  - for messages sent by MSGQ module 2-233
  - interface for 2-285
- AND operation
  - signed integers 2-3
  - unsigned integers 2-4
- AR registers, conventions for B-2
- Arg data type 1-4
- ArgToInt macro 2-511
- ArgToPtr macro 2-511
- arguments for functions 1-4
- assembly language
  - callable functions (DSP/BIOS) A-2
  - calling C functions from 1-3
- atexit function 2-511
- ATM module 2-2
  - function capability A-2
  - functions in, list of 1-5, 2-2
- ATM_andi function 2-3
- ATM_andu function 2-4
- ATM_cleari function 2-5
- ATM_clearu function 2-6
- ATM_deci function 2-7
- ATM_decu function 2-8
- ATM_inc function 2-9
- ATM_incu function 2-10
- ATM_ori function 2-11
- ATM_oru function 2-12
- ATM_seti function 2-13
- ATM_setu function 2-14
- atomic queue manager 2-336
- average statistics for data series 2-413

## B
- BIOS clock (see timer)
- BIOS library
  - instrumented or non-instrumented 2-111
- BK registers, conventions for B-3
- board clock frequency 2-109
- board input clock 2-112
- board name 2-109
- Bool data type 1-4
- Boolean values 1-4
- BR registers, conventions for B-3
- BSA registers, conventions for B-3
- BUF module 2-15
  - configuration properties 2-15
  - function capability A-2
  - functions in, list of 1-5, 2-15
  - global properties 2-17
  - object properties 2-17
- BUF_alloc function 2-19
- BUF_create function 2-20
- BUF_delete function 2-22
- BUF_free function 2-23
- BUF_maxbuff function 2-24
- BUF_stat function 2-25
- buffer pool
  - allocating fixed-size buffer 2-19
  - creating 2-20
  - deleting 2-22
  - fixed-size buffers 2-15
  - freeing fixed-size buffer 2-23
  - maximum number of buffers 2-24
  - status of 2-25
- buffered pipe manager 2-265
- buffers, splitting 2-103

## C
- C functions
  - calling from assembly language 1-3
- C_library_stdlib 2-511
- C5000 boards
  - memory segments 2-213
- C55 module
  - function capability A-2
  - functions in, list of 1-5
- OMAP 2320 and C-8
- OMAP 2420 and D-9
- C55_disableIER0 function 2-27
- C55_disableIER1 function 2-27
Index

C55_disableInt function 2-28, C-8, D-9
C55_enableIER0 function 2-29
C55_enableIER1 function 2-29
C55_enableInt function 2-31, C-8, D-9
C55_l2AckInt function 2-32, C-8, D-9
C55_l2DisableMIR function 2-33, C-8, D-9
C55_l2DisableMIR1 function 2-34
C55_l2EnableMIR function 2-35, C-8, D-9
C55_l2EnableMIR1 function 2-36
C55_l2SetIntPriority function 2-37, C-8, D-9
C55_plug function 2-38, C-8, D-9
callability of functions A-2
calling context (see context)
calloc function 2-511
not callable from SWI or HWI A-9
CDP register, conventions for B-3
CFCT register, conventions for B-3
channels (see communication channels; data channels; host channels)
character, outputting 2-466
class driver 2-62
CLK module 2-39
checking calling context 2-170
configuration properties 2-39
function callability 2-150, A-3
functions in, list of 1-6, 2-39
global properties 2-43
object properties 2-46
OMAP 2320 and C-2
OMAP 2420 and D-2
property differences for OMAP 2320 C-2
property differences for OMAP 2420 D-2
timer for, driving PRD ticks 2-291, 2-292
trace types for 2-467
CLK_countspms function 2-48
CLK_cpuCyclesPerHtime function 2-49
CLK_cpuCyclesPerLtime function 2-50
CLK_gethtime function 2-51
CLK_gettime function 2-52
CLK_getprd function 2-53
CLK_reconfig function 2-54
CLK_start function 2-56
CLK_stop function 2-57
CLKMD - (PLL) Clock Mode Register 2-110
CLKMD register 2-110
clock domains
  idling 2-300, 2-304, 2-314, 2-324
  idling during deep sleep 2-307
clock function
  not callable from SWI or HWI A-9
Clock Mode Register 2-110
clocks (see clock domains; real-time clock; system clock; timer)
communication channels
  closing 2-127
count statistics for data series 2-413
counts per millisecond, timer 2-48
CPU clock domains (see clock domains)
CPU cycles
  converting high-resolution time to 2-49
  converting low-resolution time to 2-50
CPU frequency 2-113, 2-116
CSR register, conventions for B-3
data channels
  busy status, checking 2-356
  initializing 2-357
  initializing for output 2-358
  input, disabling 2-359
  input, enabling 2-361
  input, number of MADUs read from 2-367
  input, reading from 2-365, 2-366
  input, status of 2-363
  output, disabling 2-360
  output, enabling 2-362
  output, status of 2-364
  output, writing to 2-368
data pipes 2-265
  allocating empty frame from 2-271
  getting frame from 2-274
  number of frames available to read 2-276
  number of frames available to write 2-279
  number of words written, setting 2-284
  putting frame in 2-282
  recycling frame that has been read to 2-273
  writerAddr point of, getting 2-278
data types 1-4
  Arg 1-4
  Bool 1-4
  EnumInt 1-4
  EnumString 1-4
  Extern 1-4
  Int16 1-4
  Int32 1-4
  Numeric 1-4
  Reference 1-4
Index

String 1-4
DBIER0 register, conventions for B-3
DBIER1 register, conventions for B-3
deep sleep, enabling 2-307
default values
  for properties 1-4
dependencies
  declaring 2-332
  number of, determining 2-318
  releasing 2-331
DEV module 2-58
  configuration properties 2-61
  function callability A-3
  functions in, list of 1-6, 2-58
  object properties 2-62
  properties 2-61
DEV_createDevice function 2-64
DEV_deleteDevice function 2-67
DEV_match function 2-69
device
  closing 2-70
  control operation of 2-71
  creating 2-64
  deleting 2-67
  idling 2-72
  initializing 2-73
  matching with driver 2-69
  opening 2-76
  readiness of, checking 2-77
  retrieving buffer from 2-78
  sending buffer to 2-74
device drivers 2-58
  DGN driver 2-80
  DGS driver 2-84
  DHL driver 2-88
  DIO adapter 2-92
  DNL driver 2-95
  DOV driver 2-96
  DPI driver 2-99
  DST driver 2-103
  DTR driver 2-105
  drfr.h file 2-106
  DTR_multiply function 2-105
  DTR_multiplyInt16 function 2-105
  DTR_Params structure 2-106
  Dxx_close function 2-70
  Dxx_ctrl function 2-71
  Dxx_idle function 2-72
  Dxx_init function 2-73
  Dxx_issue function 2-74
  Dxx_open function 2-76
  Dxx_ready function 2-77
  Dxx_reclaim function 2-78
development environment for HOOK and TSK objects 2-141
  environment pointer for HOOK and TSK objects 2-142
  error condition
    flagging 2-456
  error function 2-453
  error handling
    error codes A-11
    MSGQ module 2-260
  error message, writing to system log 2-188
  error number for tasks 2-494
  events
    power, function to be called on 2-326, 2-329
    scheduling functions based on 2-291
    tracing 2-467
    unregistering notification function for 2-335
  exit function 2-453, 2-511
Index

exit handler
stacking  2-455
Extern data type  1-4

F
f32toi16 function  2-86
false/true values  1-4
fixed-size buffers
  allocating  2-19
  freeing  2-23
  maximum number of  2-24
  pools of  2-15
formatted data, outputting  2-458, 2-460, 2-462, 2-464
fprintf function
  not callable from SWI or HWI A-9
frame
  available to read to, getting number of  2-276
  available to write, getting number of  2-279
  getting from pipe  2-274
  number of words in, getting  2-277
  number of words that can be written to  2-280
  putting in pipe  2-282
  recycling  2-273
  size and address of, determining  2-281
free function  2-511
  not callable from SWI or HWI A-9
frequency
  changing  2-310
  for setpoint, determining  2-320
frequency scaling  2-306
  reprogramming clock after  2-303
functions
  arguments for  1-4
  callability of A-2
  calling conventions for  1-3
  external  1-4
  list of  1-5
  naming conventions for  1-3

G
gather/scatter driver  2-84
GBL module  2-108
  configuration properties  2-108
  function callability A-3
  functions in, list of  1-7, 2-108
  global properties  2-109
GBL_getClkin function  2-112
GBL_getFrequency function  2-113
GBL_getProcId function  2-114
GBL_getVersion function  2-115
GBL_setFrequency function  2-116
GGL_setProcId function  2-117
Gconf
  underscore preceding C function names  1-3, 2-47, 2-174, 2-426
GEL configuration D-3
General Purpose (GP) Timers C-2, D-2
generators  2-80
getenv function  2-511
  not callable from SWI or HWI A-9
GIO module  2-118
  configuration properties  2-120
  function callability A-3
  functions in, list of  1-8, 2-118
  global properties  2-121
  object properties  2-122
GIO_abort function  2-123
GIO_control function  2-124
GIO_create function  2-125
GIO_delete function  2-127
GIO_flush function  2-128
GIO_new function  2-129
GIO_read function  2-131
GIO_submit function  2-133
GIO_write function  2-135
global settings  2-108
GP (General Purpose) Timers C-2, D-2

H
hardware interrupts  2-148
  callable functions A-2
  context of, determining if in  2-170
  disabled, manipulating variables while  2-2
  disabling  2-159
  enabling  2-162
  plugging dispatcher  2-160
  preserving registers across B-2
  restoring context before interrupt  2-167
  restoring global interrupt enable state  2-171
  saving context of  2-163
  target-specific, acknowledging  2-26, 2-32
  target-specific, disabling  2-27, 2-28, 2-33, 2-34
  target-specific, enabling  2-29, 2-31, 2-35, 2-36
  target-specific, enabling and disabling  2-26
  target-specific, setting priority of  2-37
hardware registers
  MEM module and  2-204
  hardware timer counter register ticks  2-39
  heap, address  2-223
  high-resolution time  2-39, 2-40, 2-42
  converting to CPU cycles  2-49
  getting  2-51
hook functions  2-137
HOOK module  2-137

Index-4
configuration properties 2-137
function callability A-3
functions in, list of 1-8, 2-137
object properties 2-139
properties 2-139
HOOK_getenv function 2-141
HOOK_setenv function 2-142
host channel manager 2-143
host link driver 2-62, 2-88
HST module 2-143
configuration properties 2-143
function callability A-4
functions in, list of 1-8, 2-143
global properties 2-144
object properties 2-145
HST object 2-88
HST_getpipe function 2-147
HWI module 2-148
configuration properties 2-148
function callability A-4
functions in, list of 1-8, 2-148
global properties 2-152
object properties 2-153
OMAP 2320 and C-4
OMAP 2420 and D-5
statistics units for 2-413
HWI_disable function 2-159
HWI_dispatchPlug function C-6, D-7
HWI_dispatchplug function 2-160
HWI_enable function 2-162
HWI_enter function 2-150, 2-163, C-7, D-7
HWI_exit function 2-150, 2-167, C-7, D-7
HWI_isHWI function 2-170
HWI_restore function 2-171

I/O availability, scheduling functions based on 2-291
i16tof32 function 2-86
i16toi32 function 2-86
i16tou8 function 2-86
i32toi16 function 2-86
IDL module 2-172
configuration properties 2-172
function callability A-4
functions in, list of 1-9, 2-172
global properties 2-173
object properties 2-174
IDL_run function 2-175
idle functions, running 2-175
idle thread manager 2-172
IER (Interrupt Enable Register)
disable interrupts using 2-27
enable interrupts using 2-29
IER0 register, conventions for B-3
IER1 register, conventions for B-3
IFR0 register, conventions for B-3
IFR1 register, conventions for B-3
initialization 2-137
input channels
declaring 2-357
disabling 2-359
enabling 2-361
number of MADUs read from 2-367
reading from 2-365, 2-366
status of, determining 2-363
input streams 2-382
Input/Output
aborting 2-123
closing communication channel 2-127
control call on communication channel 2-124
flushing input and output channels 2-128
opening communication channel 2-125, 2-129
submitting GIO packet 2-133
synchronous read 2-131
synchronous write 2-135
Int16 data type 1-4
Int32 data type 1-4
integers
enumerated 1-4
unsigned 1-4
interface for allocators 2-285
Interrupt Enable Register
disable interrupts using 2-27
enable interrupts using 2-29
Interrupt Mask Register 2-33, 2-34, 2-35, 2-36
interrupt service routines (see hardware interrupts)
interrupt threads 2-425
interrupt vector, plugging 2-26, 2-38
interrupts (see hardware interrupts; software inter-
rupts)
IOM model for device drivers 2-58
ISR epilog 2-167
ISR prolog 2-163
IVPD register, conventions for B-3
IVPH register, conventions for B-3

L
L2IC (Level 2 Interrupt Controller) C-2, D-2
base address C-4, D-5
objects and properties C-5, D-6
latency to scale between setpoints 2-322
LCK module 2-176
configuration properties 2-176
function callability A-4
functions in, list of 1-9, 2-176
global properties 2-176
Index

object properties 2-177
LCK_create function 2-178
LCK_delete function 2-179
LCK_pend function 2-180
  thread restrictions for 2-512
LCK_post function 2-182
  thread restrictions for 2-512
Level 2 Interrupt Controller (L2IC) C-2, D-2
  base address C-4, D-6
  objects and properties C-5, D-6
  level 2 interrupts 2-28, 2-31, 2-32
load addresses 2-209
localcopy function 2-86
LOG module 2-183
  configuration properties 2-183
  function callability A-4
  functions in, list of 1-9, 2-183
  global properties 2-184
  object properties 2-184
LOG_disable function 2-186
LOG_enable function 2-187
LOG_error function 2-188
LOG_event function 2-189
LOG_message function 2-190
LOG_printf function 2-191
LOG_reset function 2-194
low-resolution time 2-39, 2-40, 2-41
  converting to CPU cycles 2-50
  getting 2-52
  restarting 2-56
  stopping 2-57

M

MADUs 2-203
mailbox
  clear bits from 2-428, 2-430
  creating 2-197
  decrementing 2-433
  deleting 2-198
  get value of 2-439
  incrementing 2-441
  OR mask with value in 2-443, 2-444
  posting message to 2-200
  waiting for message from 2-199
mailbox manager 2-195
main function
  calling context 2-170
malloc function 2-511
  not callable from SWI or HWI A-9
maximum statistics for data series 2-413
MBX module 2-195
  configuration properties 2-195
  function callability A-4
  functions in, list of 1-10, 2-195
  global properties 2-196
  object properties 2-196
MBX_create function 2-197
MBX_delete function 2-198
MBX_pend function 2-199
MBX_post function 2-200
MEM module 2-201
  configuration properties 2-201
  function callability A-4
  functions in, list of 1-10, 2-201
  global properties 2-204
  object properties 2-211
MEM_alloc function 2-214
MEM_define function 2-220
MEM_free function 2-222
MEM_getBaseAddress function 2-223
MEM_increaseTableSize function 2-224
MEM_redefine function 2-225
MEM_stat function 2-226
MEM_undefined function 2-227
MEM_valloc function 2-228
memory block
  freeing 2-222
  increasing 2-224
memory model 2-110
memory segment manager 2-201
memory segments
  allocating and initializing 2-228
  allocating from 2-214
  C5000 boards 2-213
  defining 2-220
  existing, redefining 2-225
  status of, returning 2-226
  undefining 2-227
message log 2-183
  appending formatted message to 2-191
  disabling 2-186
  enabling 2-187
  resetting 2-194
  writing unformatted message to 2-189
message queues 2-232
  closing 2-240
  determining destination queue for message 2-245
  finding 2-252
  number of messages in 2-241
  open, finding 2-250
  opening 2-254
  placing message in 2-257
  receiving message from 2-243
  releasing 2-259
messages
  allocating 2-239
  determining destination message queue of 2-245
  freeing 2-242
ID for, setting 2-262
ID of, determining 2-246
number of, in message queue 2-241
placing in message queue 2-257
receiving from message queue 2-243
reply destination of, determining 2-248
reply destination of, setting 2-264
size of, determining 2-247
messaging, multi-processor 2-229
mini-drivers 2-92
deleting 2-127

minit function
not callable from SWI or HWI A-9
MIR (Interrupt Mask Register) 2-33, 2-34, 2-35, 2-36
modules
ATM module 2-2
BUF module 2-15
CLK module 2-39
DEV module 2-58
functions for, list of 1-5
GBL module 2-108
GIO module 2-118
HOOK module 2-137
HST module 2-143
HWI module 2-148
IDL module 2-172
LCK module 2-176
list of 1-2
LOG module 2-183
MBX module 2-195
MEM module 2-201
MSGQ module 2-229
PIP module 2-265
POOL module 2-285
PRD module 2-290
PWRM module 2-298
QUE module 2-336
SEM module 2-369
SIO module 2-382
STS module 2-412
SWI module 2-422
SYS module 2-451
trace types for 2-467
TRC module 2-467
TSK module 2-472
MSGQ API 2-232, 2-233
MSGQ_count function 2-241
MSGQ_free function 2-242
MSGQ_get function 2-243
MSGQ_getAttrs function 2-244
MSGQ_getDstQueue function 2-245
MSGQ_getMsgId function 2-246
MSGQ_getMsgSize function 2-247
MSGQ_getSrcQueue function 2-248
MSGQ_isLocalQueue function 2-249
MSGQ_locate function 2-250
MSGQ_locateAsync function 2-252
MSGQ_open function 2-254
MSGQ_put function 2-257
MSGQ_release function 2-259
MSGQ_setErrorHandler function 2-260
MSGQ_setMsgId function 2-262
MSGQ_setSsrcQueue function 2-264
multiple processors 2-117
multiprocessor application
converting single-processor application to 2-101
multi-processor applications 2-117
multi-processor messaging 2-229

N
naming conventions
functions 1-3
properties 1-4
NMI functions
calling HWI functions 2-151
notification function signatures 2-329
notification functions 2-335
notifyReader function 2-267
PIP API calls and 2-151
notifyWriter function 2-267
null driver 2-95
Numeric data type 1-4

O
object references
properties holding 1-4
OMAP 2320 C-2
C55 module and C-8
CLK module and C-2
HWI module and C-4
OMAP 2420 D-2
C55 module and D-9
CLK module and D-2
HWI module and D-5
on-chip timer (see timer)
operations (see functions)
OR operation
signed integers 2-11
Index

unsigned integers 2-12
output channels
  declaring 2-358
  disabling 2-360
  enabling 2-362
status of, determining 2-364
writing to 2-368
output streams 2-382
outputting formatted data 2-458, 2-460, 2-462, 2-464
outputting single character 2-466
overlap driver 2-96

packing/unpacking ratio, DGS driver 2-84
PC register, conventions for B-3
period register
  value of 2-53
periodic function
  starting 2-295
  stopping 2-296
periodic function manager 2-290
periodic rate 2-40

PIP module 2-265
  configuration properties 2-266
  function callability A-5
  functions in, list of 1-11, 2-265
  global properties 2-268
  object properties 2-268
  statistics units for 2-413
  trace types for 2-467

POO module 2-285
  configuration properties 2-285
  functions in, list of 2-285
  global properties 2-289
  posted mode 2-111
  power event
    function to be called on 2-326
    registered, function to be called on 2-329
  power management 2-298

PRD module 2-290
  configuration properties 2-290
  function callability A-5
  functions in, list of 1-12, 2-290
  global properties 2-291
  object properties 2-292
  statistics units for 2-413
  ticks driven by CLK timer 2-291, 2-292
  ticks, getting current count 2-294
  ticks, incrementing 2-297
  ticks, setting increments for 2-292
  trace types for 2-467

printf function
  not callable from SWI or HWI A-9

processors
  multiple 2-117

PROCID 2-117
producer, of data pipe 2-267
program
  aborting 2-454
  terminating 2-457
properties
  data types for 1-4
  default values for 1-4
  GIO object 2-122
  HOOK module 2-139
  MEM object 2-211
  naming conventions 1-4

putc function 2-453

PWRM module 2-298
  capabilities of, determining 2-315
  clock domains, idling 2-300, 2-304, 2-314, 2-324
  clock domains, idling during deep sleep 2-307
  configuration properties 2-301, 2-313
  function callability A-6
  functions in, list of 1-12, 2-298
Index

Q

QUE module 2-336
  configuration properties 2-336
  function callability A-6
  functions in, list of 1-13, 2-336
  global properties 2-337
  object properties 2-338
QUE_create function 2-339
QUE_delete function 2-340
QUE_dequeue function 2-341
QUE_empty function 2-342
QUE_enqueue function 2-343
QUE_get function 2-344
QUE_head function 2-345
QUE_insert function 2-346
QUE_new function 2-347
QUE_next function 2-348
QUE_prev function 2-349
QUE_put function 2-350
QUE_remove function 2-351
queue manager 2-336
queues
  creating 2-339
  deleting 2-340
  emptying 2-347
  getting element from front of 2-344
  inserting element at end of 2-343
  inserting element in middle of 2-346
  putting element at end of 2-350
  removing element from front of 2-341
  removing element from middle of 2-351
  returning pointer to element at front of 2-345
  returning pointer to next element of 2-348
  returning pointer to previous element of 2-349
  testing if empty 2-342

R

rand function
  not callable from SWI or HWI 2-150, 2-512
REA0 register, conventions for B-3
REA1 register, conventions for B-3
reader, of data pipe 2-267
readers, MSGQ module 2-231, 2-233
read-time data exchange settings 2-353
realloc function 2-354
  not callable from SWI or HWI A-9
real-time clock (see CLK module)
Reference data type 1-4
register conventions B-2
registers
  modification in multi-threaded application B-2
  preserving across task context switches or interrupts B-2
resource lock
  acquiring ownership of 2-354
  creating 2-180
  deleting 2-179
  relinquishing ownership of 2-182
resource lock manager 2-176
resources
  declaring dependency on 2-332
  number of dependencies on 2-318
  releasing dependency on 2-331
RETA register, conventions for B-3
RPTC register, conventions for B-3
RSA0 register, conventions for B-3
RSA1 register, conventions for B-3
RTDX module 2-353
  configuration properties 2-353
  function callability A-6
  functions in, list of 1-13
  object properties 2-355
  target configuration properties 2-354
RTDX_channelBusy function 2-356
RTDX_CreateInputChannel 2-357
RTDX_CreateOutputChannel function 2-358
RTDX_disableInput function 2-359
RTDX_disableOutput function 2-360
RTDX_enableInput function 2-361
RTDX_enableOutput function 2-362
RTDX_isInputEnabled function 2-363
RTDX_isOutputEnabled function 2-364
RTDX_read function 2-365
RTDX_readNB function 2-366
RTDX_sizeofInput function 2-367
RTDX_write function 2-368
RTS functions
  not calling in HWI or SWI threads 2-150, 2-512
RTS library 2-109

index-9
Index

S

scaling operation 2-105
SEM module 2-369
   configuration properties 2-369
   function callability A-7
   functions in, list of 1-14, 2-369
   global properties 2-371
   object properties 2-371
SEM_count function 2-372
SEM_create function 2-373
SEM_delete function 2-374
SEM_new function 2-375
SEM_pend function 2-376
SEM_pendBinary function 2-377
SEM_post function 2-379
SEM_postBinary function 2-380
SEM_reset 2-381
semaphore manager 2-369
semaphores
   binary, signaling 2-380
   binary, waiting for 2-377
   count of, determining 2-372
   count of, resetting 2-381
   creating 2-373
   deleting 2-374
   initializing 2-375
   signaling 2-379
   waiting for 2-376
setpoints (see V/F setpoints)
signal generators 2-80
signed integers
   AND operation 2-3
   clearing 2-5
   decrementing 2-7
   incrementing 2-9
   OR operation 2-11
   setting 2-13
single-processor application
   converting to multiprocessor application 2-101
SIO module 2-382
   configuration properties 2-383
   function callability A-7
   functions in, list of 1-14
   functions in, list of 2-382
   global properties 2-384
   object properties 2-384
SIO/DEV model for device drivers 2-59
SIO_bufsize function 2-388
SIO_create function 2-389
SIO_ctrl function 2-392
SIO_delete function 2-393
SIO_flush function 2-394
SIO_get function 2-395
SIO_idle function 2-397
SIO_issue function 2-398
SIO_ISSUERECLAIM streaming model
   DPI and 2-100
SIO_put function 2-400
SIO_ready function 2-402
SIO_reclaim function 2-403
SIO_reclaimx function 2-406
SIO_segid function 2-407
SIO_select function 2-408
SIO_staticbuf function 2-410
sleep
   changing sleep states 2-333
   deep sleep, enabling 2-307
   for tasks 2-506
software generator driver 2-61
software interrupt manager 2-422
software interrupts
   address of currently executing interrupt 2-448
   attributes of, returning 2-437
   attributes of, setting 2-449
   callable functions A-2
   checking to see if in context of 2-442
   clearing 2-431
   context of, determining if in 2-442
   deleting 2-434
   disabled, manipulating variables while 2-2
   enabling 2-436
   mailbox for, clearing bits 2-428, 2-430
   mailbox for, decrementing 2-433
   mailbox for, incrementing 2-441
   mailbox for, OR mask with value in 2-443, 2-444
   mailbox for, returning value of 2-439
   posting 2-443, 2-444, 2-445
   priority mask, returning 2-440
   raising priority of 2-446
   restoring priority of 2-447
SP register, conventions for B-3
split driver 2-103
sprintf function
   not callable from SWI or HWI A-9
srand function
   not callable from SWI or HWI A-10
SSP register, conventions for B-3
ST registers, conventions for B-4
stack
   allocating for tasks 2-479
   checking for overflow 2-482
   stack size for tasks 2-477, 2-480
stackable gather/scatter driver 2-84
stackable overlap driver 2-96
stackable split driver 2-103
stackable streaming transformer driver 2-105
STATICPOOL allocator 2-287
statistics
   resetting values of 2-419
saving values for delta 2-420
tracing 2-467
updating 2-417
updating with delta 2-418
statistics object manager 2-412
status register conventions B-4
std.h library
functions in 2-511
macros in, list of 1-18
stdlib.h library
functions in 2-511
functions in, list of 1-17
stream I/O manager 2-382
streams
acquiring static buffer from 2-410
closing 2-393
device for, determining if ready 2-402
device for, selecting ready device 2-408
device-dependent control operation, issuing 2-392
flushing 2-394
getting buffer from 2-395
idling 2-397
memory segment used by, returning 2-407
opening 2-389
putting buffer to 2-400
requesting buffer from 2-403, 2-406
sending buffer to 2-398
size of buffers used by, determining 2-388
strftime function
not callable from SWI or HWI A-10
String data type 1-4
strings 1-4
enumerated 1-4
STS module 2-412
configuration properties 2-412
function callability A-7
functions in, list of 1-15, 2-412
global properties 2-415
object properties 2-415
STS_add function 2-417
STS_delta function 2-418
STS_reset function 2-419
STS_set function 2-420
sum statistics for data series 2-413
SWI module 2-422
configuration properties 2-423
function callability A-7
functions in, list of 1-15, 2-422
global properties 2-426
object properties 2-426
statistics units for 2-413
trace types for 2-467
SWI_andn function 2-428
SWI_andnHook function 2-430
SWI_create function 2-431
SWI_dec function 2-433
SWI_delete function 2-434
SWI_enable function 2-436
SWI_getattrs function 2-437
SWI_getmbox function 2-439
SWI_getpri function 2-440
SWI_inc function 2-441
SWI_isSWI function 2-442
SWI_or function 2-443
SWI_orHook function 2-444
SWI_post function 2-445
SWI_raisepri function 2-446
SWI_restorepri function 2-447
SWI_self function 2-448
SWI_setattrs function 2-449
synchronous read 2-131
synchronous write 2-135
SYS module 2-451
configuration properties 2-451
function callability A-8
functions in, list of 1-16, 2-451
global properties 2-452
object properties 2-453
SYS_abort function 2-453, 2-454
SYS_atexit function 2-455
SYScalloc status A-11
SYS_free status A-11
SYS_exit function 2-453, 2-457
SYS_getconf function 2-453, 2-458
SYS_putchar function 2-453, 2-466
SYS_print function 2-453, 2-462
SYS_vprintf function 2-464
system clock 2-40
choosing module driving 2-478
incrementing in TSK module 2-499, 2-508
PRD module driving 2-478
returning current value of 2-509
system clock manager 2-39
system log 2-183
Index

writing error message to 2-188
writing program-supplied message to 2-190
system settings, managing 2-451

T

T0 register, conventions for B-3
T1 register, conventions for B-3
T2 register, conventions for B-3
T3 register, conventions for B-3
target board name 2-109
task context switches, preserving registers across B-2
task environment
setting 2-501
task manager 2-472
task scheduler
  disabling 2-490
  enabling 2-491
tasks
callable functions A-2
  checking if in context of 2-498
  creating 2-483
  currently executing, handle of 2-500
  default priority of 2-478
  delaying execution of (sleeping) 2-506
  deleting 2-487
  environment pointer for, getting 2-493
  error number for, getting 2-494
  error number for, setting 2-502
  execution priority of, setting 2-503
  handle of STS object, getting 2-497
  incrementing system clock for 2-499, 2-508
  name of, getting 2-495
  not shutting down system during 2-481
  priority of 2-480, 2-496
  resetting time statistics for 2-504
  status of, retrieving 2-507
  terminating 2-492
  updating time statistics for 2-488
  yielding to task of equal priority 2-510
Tconf
  underscore preceding C function names 1-3, 2-47, 2-174, 2-426
TDERR 2-39
terminating program 2-457
threads
  idle thread manager 2-172
  interrupt threads 2-425
  register modification and B-2
  RTS functions callable from 2-512
  tick counter, determining 2-294
  tick counter (see PRD module, ticks) timer 2-39, 2-40
counts per millisecond 2-48
  reprogramming after frequency scaling 2-303
  resetting 2-54
timer counter 2-41
timer divide-down register 2-39
timer period register
  resetting 2-54
trace buffer
  memory segment for 2-452
  size of 2-452
trace manager 2-467
tracing
  disabling 2-469
  enabling 2-470
  querying enabled trace types 2-471
transform function, DGS driver 2-84
transformer driver 2-105
transformers 2-105
transports array 2-117, 2-237
transports, MSGQ module 2-233
TRC module 2-467
  function callability A-8
  functions in, list of 1-16, 2-467
  TRC_disable function 2-469
  TRC_enable function 2-470
  TRC_query function 2-471
TRN0 register, conventions for B-3
TRN1 register, conventions for B-3
true/false values 1-4
TSK module 2-472
  configuration properties 2-474
  function callability A-8
  functions in, list of 1-16, 2-472
  global properties 2-477
  object properties 2-479
  statistics units for 2-413
  system clock driven by 2-478, 2-499, 2-508
  trace types for 2-467
TSK_checkstacks function 2-482
TSK_create function 2-483
TSK_delete function 2-487
TSK_deltatime function 2-488
TSK_disable function 2-490
TSK_enable function 2-491
TSK_exit function 2-492
TSK_getenv function 2-493
TSK_geterr function 2-494
TSK_getenv function 2-495
TSK_gettime function 2-496
TSK_gettime function 2-497
TSK_isTSK function 2-498
TSK_itick function 2-499
TSK_self function 2-500
TSK_setenv function 2-501
TSK_seterr function 2-502
Index

TSK_setpri function 2-503
TSK_settime function 2-504
TSK_sleep function 2-506
TSK_stat function 2-507
TSK_tick function 2-508
TSK_time function 2-509
TSK_yield function 2-510

U
u16tou32 function 2-86
u32tou16 function 2-86
u32tou8 function 2-86
u8tou16 function 2-86
u8tou32 function 2-86
underscore
preceeding C function names 1-3, 2-47, 2-174, 2-426
unsigned integers 1-4
AND operation 2-4
clearing 2-6
decrementing 2-8
incrementing 2-10
OR operation 2-12
setting 2-14
user hook function 2-303

V
V/F setpoints
changing 2-310
determining 2-317
frequency and voltage of, determining 2-320
latency to scale between 2-322
number of determining 2-319
variables
manipulating with interrupts disabled 2-2
vfprintf function
not callable from SWI or HWI A-10
voltage
changing 2-310
for setpoint, determining 2-320
voltage scaling 2-306
vprintf function
not callable from SWI or HWI A-10
vsprintf function
not callable from SWI or HWI A-10

W
writer, of data pipe 2-267
writers, MSGQ module 2-231, 2-234

X
XAR registers, conventions for B-2
XCDP register, conventions for B-3
XDP register, conventions for B-3
XSP register, conventions for B-3
XSSP register, conventions for B-3