TI DSP/BIOS Real-time Operating System v6.x User's Guide

Literature Number: SPRUEX3D
October 2009

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Preface

Read This First

About This Manual

This manual describes the TI DSP/BIOS Real-time Operating System. The latest version number as of the publication of this manual is DSP/BIOS 6.21.

DSP/BIOS gives developers of mainstream applications on Texas Instruments 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.

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.

  Here is a sample program listing:

  ```
  #include <xdc/runtime/System.h>

  int main(){
      System_printf("Hello World!\n");
      return (0);
  }
  ```

- 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

- *DSP/BIOS 6 Release Notes* (BIOS_INSTALL_DIR/Bios_#_#_release_notes.html). Includes information about software version, upgrades and compatibility, host and target device support, validation, and known issues.
- *DSP/BIOS 6 Getting Started Guide* (BIOS_INSTALL_DIR/docs/Bios_Getting_Started_Guide.pdf). Includes steps for installing and validating the installation. Provides a quick introduction to DSP/BIOS.
- RTSC-Pedia wiki: http://rtsc.eclipse.org/docs-tip
- Code Composer Studio Mediawiki: http://tiexpressdsp.com/wiki/index.php?title=CCSv4
- CCSv4 online help contains reference information about XDCtools and DSP/BIOS packages and their modules, APIs, XDCtools configuration, data structures, etc. See Section 1.5.1.
- *Migrating a DSP/BIOS 5 Application to DSP/BIOS 6* (SPRAAS7). (BIOS_INSTALL_DIR/docs/Bios_Legacy_App_Note.pdf)

Related Documentation

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

The C Programming Language (second edition), by Brian W. Kernighan and Dennis M. Ritchie, published by Prentice-Hall, Englewood Cliffs, New Jersey, 1988

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

Programming Embedded Systems in C and C++, by Michael Barr, Andy Oram (Editor), published by O'Reilly & Associates; ISBN: 1565923545, February 1999

Real-Time Systems, by Jane W. S. Liu, published by Prentice Hall; ISBN: 013099651, June 2000

Principles of Concurrent and Distributed Programming (Prentice Hall International Series in Computer Science), by M. Ben-Ari, published by Prentice Hall; ISBN: 013711821X, May 1990

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

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October 14, 2009

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Chapter 1

About DSP/BIOS

This chapter provides an overview of DSP/BIOS and describes its relationship to XDCtools.

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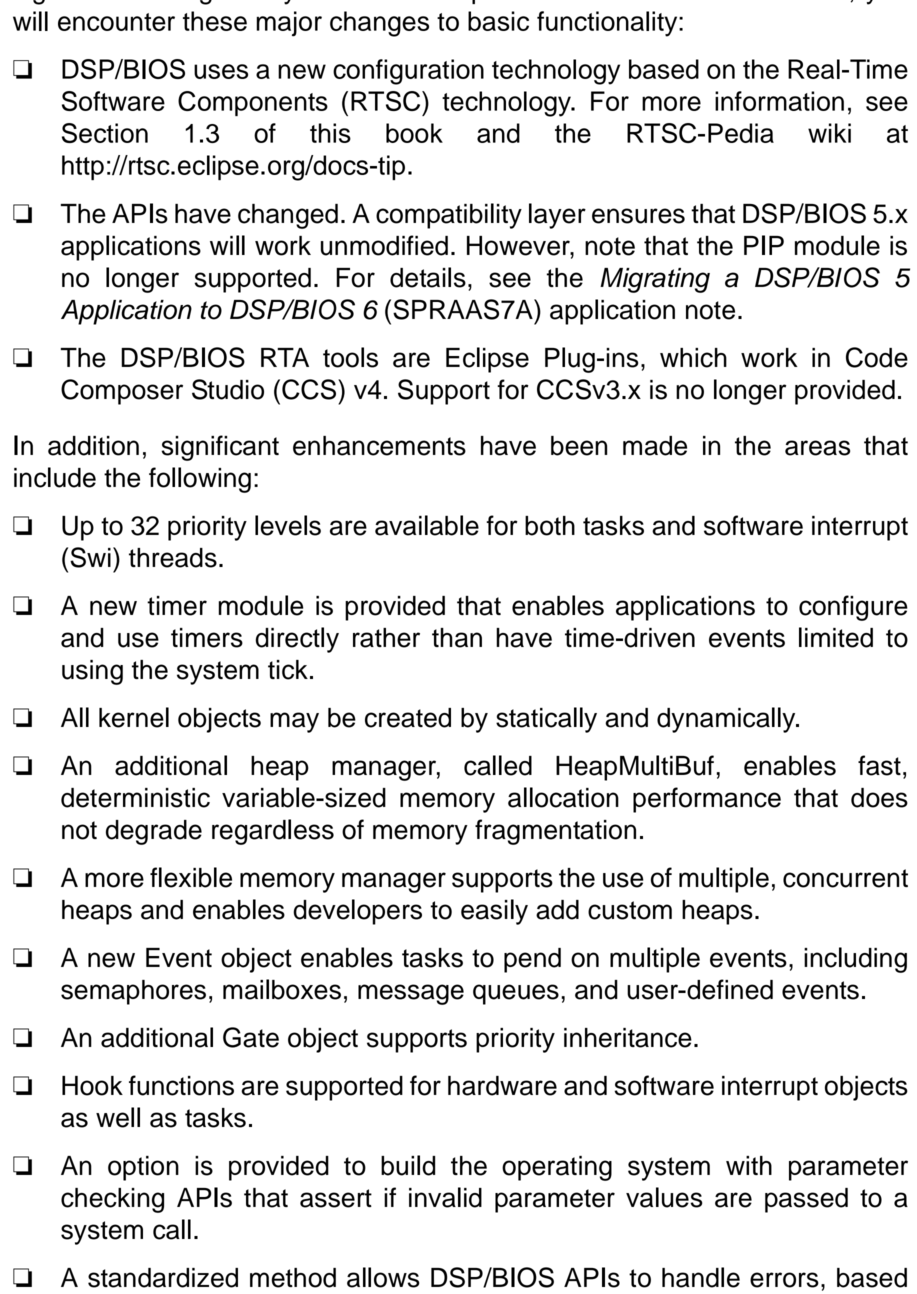
1.1 What is DSP/BIOS?

DSP/BIOS is a scalable real-time kernel. It is designed to be used by applications that require real-time scheduling and synchronization or real-time instrumentation. DSP/BIOS provides preemptive multi-threading, hardware abstraction, real-time analysis, and configuration tools. DSP/BIOS is designed to minimize memory and CPU requirements on the target.

DSP/BIOS provides the following benefits:

- All DSP/BIOS objects can be configured statically or dynamically.
- To minimize memory size, the APIs are modularized so that only those APIs that are used by the program need to be bound into the executable program. In addition, statically-configured objects reduce code size by eliminating the need to include object creation calls.
- Error checking and debug instrumentation is configurable and can be completely removed from production code versions to maximize performance and minimize memory size.
- Almost all system calls provide deterministic performance to enable applications to reliably meet real-time deadlines.
- To improve performance, instrumentation data (such as logs and traces) is formatted on the host.
- The threading model provides thread types for a variety of situations. Hardware interrupts, software interrupts, tasks, idle functions, and periodic functions are all supported. You can control the priorities and blocking characteristics of threads through your choice of thread types.
- Structures to support communication and synchronization between threads are provided. These include semaphores, mailboxes, events, gates, and variable-length messaging.
- Dynamic memory management services offering both variable-sized and fixed-sized block allocation.
- An interrupt dispatcher handles low-level context save/restore operations and enables interrupt service routines to be written entirely in C.
- System services support the enabling/disabling of interrupts and the plugging of interrupt vectors, including multiplexing interrupt vectors onto multiple sources.

1.2 What's New?



This book describes DSP/BIOS 6, a major new release that introduces significant changes. If you have used previous versions of DSP/BIOS, you will encounter these major changes to basic functionality:

- ❏ DSP/BIOS uses a new configuration technology based on the Real-Time Software Components (RTSC) technology. For more information, see Section 1.3 of this book and the RTSC-Pedia wiki at http://rtsc.eclipse.org/docs-tip.
- ❏ The APIs have changed. A compatibility layer ensures that DSP/BIOS 5.x applications will work unmodified. However, note that the PIP module is no longer supported. For details, see the *Migrating a DSP/BIOS 5 Application to DSP/BIOS 6* (SPRAAS7A) application note.
- ❏ The DSP/BIOS RTA tools are Eclipse Plug-ins, which work in Code Composer Studio (CCS) v4. Support for CCSv3.x is no longer provided.

In addition, significant enhancements have been made in the areas that include the following:

- ❏ Up to 32 priority levels are available for both tasks and software interrupt (Swi) threads.
- ❏ A new timer module is provided that enables applications to configure and use timers directly rather than have time-driven events limited to using the system tick.
- ❏ All kernel objects may be created by statically and dynamically.
- ❏ An additional heap manager, called HeapMultiBuf, enables fast, deterministic variable-sized memory allocation performance that does not degrade regardless of memory fragmentation.
- ❏ A more flexible memory manager supports the use of multiple, concurrent heaps and enables developers to easily add custom heaps.
- ❏ A new Event object enables tasks to pend on multiple events, including semaphores, mailboxes, message queues, and user-defined events.
- ❏ An additional Gate object supports priority inheritance.
- ❏ Hook functions are supported for hardware and software interrupt objects as well as tasks.
- ❏ An option is provided to build the operating system with parameter checking APIs that assert if invalid parameter values are passed to a system call.
- ❏ A standardized method allows DSP/BIOS APIs to handle errors, based on an error block approach. This enables errors to be handled efficiently without requiring the application to catch return codes. In addition, you

can easily have the application halted whenever a DSP/BIOS error occurs, because all errors now pass through a single handler.

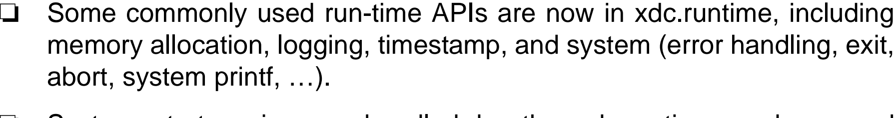
- The system log and execution graph in the Real-Time Analysis (RTA) tools support both dynamically and statically-created tasks.
- More powerful logging functions include a timestamp, up to 6 words per log entry, and the ability for logging events to span more than one log if additional storage is required.
- Per-task CPU load is now supported in addition to total CPU load.
- Host-native execution is provided. This enables developers to create prototype DSP/BIOS applications using Windows developer tools such as Visual C++, without the need for a DSP board or simulator.

1.3 How are DSP/BIOS and RTSC Related?

Real-Time Software Components (RTSC) provides a standard for packaging and configuring modules. DSP/BIOS is delivered as a set of RTSC packages that provide the modules that make up DSP/BIOS.

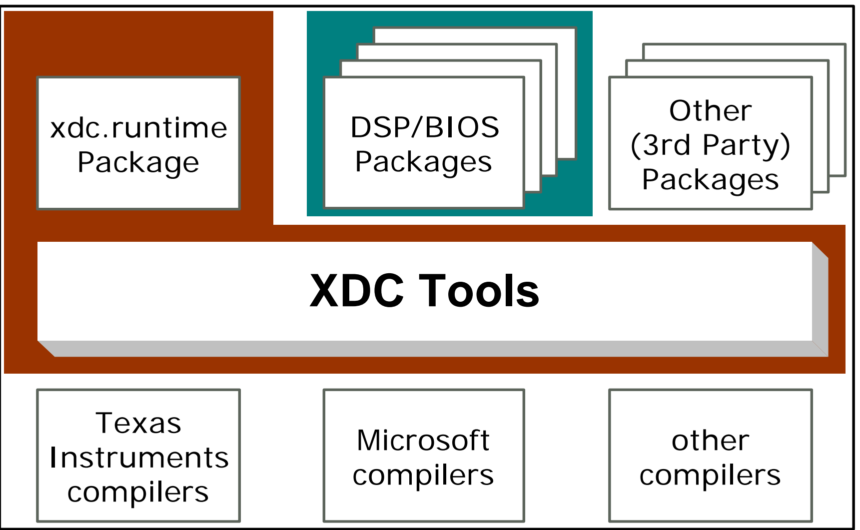
RTSC includes a set of tools (XDCtools) and a run-time (xdc.runtime) package that enable the development of real-time applications. DSP/BIOS uses both the XDCtools and run-time package. This is different from earlier releases (prior to DSP/BIOS 6.00), in which the configuration tools were included with the kernel and all target-resident functions were part of the kernel.

In addition the configuration tool changes, users should note the following significant differences, compared to previous versions:



- Some commonly used run-time APIs are now in xdc.runtime, including memory allocation, logging, timestamp, and system (error handling, exit, abort, system printf, …).
- System start-up is now handled by the xdc.runtime package and DSP/BIOS installs its start-up modules into the xdc.runtime package. Developers will now need to install their initialization code into the XDC runtime start-up, not DSP/BIOS.

You can picture the architecture of the tools used to create applications as shown in the following figure:



This book describes the DSP/BIOS packages. The *XDCtools Consumer User's Guide* describes the components with the red background (XDCtools and the xdc.runtime package).

Before continuing with this book, you may wish familiarize yourself with the basics of RTSC by visiting the RTSC-Pedia wiki at http://rtsc.eclipse.org/docs-tip. This book assumes that you know the general procedure for using XDCtools to configure objects: to create objects statically, to set module-wide and instance-only properties. It also assumes that you know the general procedure for including the header file of a package and calling a function from that package.

1.4 DSP/BIOS Packages

DSP/BIOS provides the following packages:

Table 1–1 Packages and Modules Provides by DSP/BIOS

Package	Description
ti.bios, ti.bios.tconf	Contains header files and configuration parameters used by DSP/BIOS 5.x programs. See SPRAAS7.
ti.bios.conversion	Provides a command-line conversion tool for DSP/BIOS 5.x applications. See SPRAAS7.
ti.sysbios.benchmark	Contains specifications for benchmark tests. Provides no modules, APIs, or configuration. See Appendix B.
ti.sysbios.family.*	Contains specifications for target/device-specific functions.
ti.sysbios.gates	Contains several implementations of the IGateProvider interface for use in various situations. These include GateHwi, GateSwi, GateTask, GateMutex, and GateMutexPri. See Section 3.3.
ti.sysbios.genx	Provides a command-line tool to build example applications.
ti.sysbios.hal	Contains Hwi, Timer, and Cache modules. See Section 6.2, Section 6.3, and Section 6.4.
ti.sysbios.heaps	Provides several implementations of the XDCtools IHeap interface. These include HeapBuf (fixed-size buffers), HeapMem (variable-sized buffers), and HeapMultiBuf (multiple fixed-size buffers). See Chapter 5.
ti.sysbios.interfaces	Contains interfaces for modules to be implemented, for example, on a device or platform basis.
ti.sysbios.ipc	Contains modules related to inter-process communication: Event, Mailbox, and Semaphore. See Chapter 3.
ti.sysbios.knl	Contains modules for the DSP/BIOS kernel, including Swi, Task, Idle, and Clock. See Chapter 2 and Chapter 4.
ti.sysbios.utils	Contains Load module, which provides global CPU load as well as thread-specific load.

1.5 For More Information

You can read the following additional documents to learn more about DSP/BIOS and XDCtools:

- *XDCtools Release Notes* (in XDC_INSTALL_DIR). Includes information about software version, upgrades and compatibility, host and target device support, validation, and known issues.
- *DSP/BIOS Release Notes* (BIOS_INSTALL_DIR/release_notes.html). Includes information about changes in each version, known issues, validation, and device support.
- *DSP/BIOS Getting Started Guide* (BIOS_INSTALL_DIR/docs/Bios_Getting_Started_Guide.doc). Includes steps for installing and validating the installation.
- *Migrating a DSP/BIOS 5 Application to DSP/BIOS 6* (SPRAAS7A). (BIOS_INSTALL_DIR/docs/Bios_Legacy_App_Note.pdf)
- RTSC-Pedia wiki: http://rtsc.eclipse.org/docs-tip
- Code Composer Studio Mediawiki: http://tiexpressdsp.com/wiki/index.php?title=CCSv4
- CCSv4 online help contains reference information about XDCtools and DSP/BIOS packages and their modules, APIs, XDCtools configuration, data structures, etc. See Section 1.5.1.

1.5.1 Using the API Reference Help System

To open the online help for DSP/BIOS, you can choose **DSP/BIOS API Documentation** from the **Texas Instruments > DSP/BIOS** group in the Windows **Start** menu.

To open online help for XDCtools, you can choose **XDCtools Documentation** from the **Texas Instruments > XDCtools** group in the Windows **Start** menu.

You can also open help for CCSv4, DSP/BIOS, and XDCtools together from within CCSv4.

To see the DSP/BIOS API documentation, you must have included your DSP/BIOS installation directory path in the XDCPATH environment variable. Please refer to the *XDCtools Getting Started Guide* for details on how to do this.

Click "+" next to a repository to expand its list of packages. Click "+" next to a package name to see the list of modules it provides. You can further expand the tree to see a list of the functions provided by a module. Double-click on a package or module to see its reference information.

The DSP/BIOS API documentation is under the "sysbios" package. To view API documentation on memory allocation, logs, timestamps, asserts, and system, expand the "xdc.runtime" package. The "bios" package contains only the compatibility modules for earlier versions of DSP/BIOS.

Notice the following icons in this window:

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To close a page and remove its tab, click the X on the tab.

The xs option '--xp' adds the DSP/BIOS 6.0 packages to the path searched for XDCtools packages. If you have added this directory to your XDCPATH environment variable definition as described in the *DSP/BIOS 6 Getting Started Guide*, you do not need to use the --xp command-line option.

Chapter 2

Threading Modules

This chapter describes the types of threads a DSP/BIOS program can use.

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2.1 DSP/BIOS Startup Sequence

The DSP/BIOS startup sequence is logically divided into two phases—those operations that occur prior to the application's "main()" function being called and those operations that are performed after the application's "main()" function is invoked. Control points are provided at various places in each of the two startup sequences for user startup functions to be inserted.

The "before main()" startup sequence is governed completely by the XDCtools runtime package. For more information about the boot sequence prior to main, refer to the "XDCtools Boot Sequence and Control Points" section in the *XDCtools Consumer User's Guide*.

The "after main()" startup sequence is governed by DSP/BIOS and is initiated by an explicit call to the BIOS_start() function at the end of the application's main() function.

The XDCtools runtime startup sequence is as follows:

1) Immediately after CPU reset, perform target/device-specific CPU initialization (beginning at c_int00).
2) Prior to cinit(), run the single user-supplied "reset function" (the xdc.runtime.Startup module provides this hook).
3) Run cinit() to initialize C runtime environment.
4) Run the user-supplied "first functions" (the xdc.runtime.Startup module provides this hook).
5) Run all the module initialization functions.
6) Run pinit().
7) Run the user-supplied "last functions" (the xdc.runtime.Startup module provides this hook).
8) Run main().

The DSP/BIOS startup sequence begins at the end of main() when BIOS_start() is called:

1) **Startup Functions.** Run the user-supplied "startup functions" (see BIOS.startupFxns).
2) **Enable Hardware Interrupts.**
3) **Enable Software Interrupts.** If the system supports software interrupts (Swis) (see BIOS.swiEnabled), then the DSP/BIOS startup sequence enables Swis at this point.

4) **Timer Startup.** If the system supports Timers, then at this point all configured timers are initialized per their user-configuration. If a timer was configured to start "automatically", it is started here.

5) **Task Startup.** If the system supports Tasks (see BIOS.taskEnabled), then task scheduling begins here. If there are no statically or dynamically created Tasks in the system, then execution proceeds directly to the idle loop.

The following configuration script excerpt installs a user-supplied startup function at every possible control point in the RTSC and DSP/BIOS startup sequence:

```
/* get handle to xdc Startup module */
var Startup = xdc.useModule('xdc.runtime.Startup');

/* install "reset function" */
Startup.resetFxn = '&myReset';

/* install a "first function" */
var len = Startup.firstFxns.length
Startup.firstFxns.length++;
Startup.firstFxns[len] = '&myFirst';

/* install a "last function" */
var len = Startup.lastFxns.length
Startup.lastFxns.length++;
Startup.lastFxns[len] = '&myLast';

/* get handle to BIOS module */
var BIOS = xdc.useModule('ti.sysbios.BIOS');

/* install a BIOS startup function */
BIOS.addUserStartupFunction('&myBiosStartup');
```

2.2 Overview of Threading Modules

Many real-time applications must perform a number of seemingly unrelated functions at the same time, often in response to external events such as the availability of data or the presence of a control signal. Both the functions performed and when they are performed are important.

These functions are called threads. Different systems define threads either narrowly or broadly. Within DSP/BIOS, the term is defined broadly to include any independent stream of instructions executed by the processor. A thread is a single point of control that can activate a function call or an interrupt service routine (ISR).

DSP/BIOS enables your applications to be structured as a collection of threads, each of which carries out a modularized function. Multithreaded programs run on a single processor by allowing higher-priority threads to preempt lower-priority threads and by allowing various types of interaction between threads, including blocking, communication, and synchronization.

Real-time application programs organized in such a modular fashion—as opposed to a single, centralized polling loop, for example—are easier to design, implement, and maintain.

DSP/BIOS provides support for several types of program threads with different priorities. Each thread type has different execution and preemption characteristics. The thread types (from highest to lowest priority) are:

❑ **Hardware interrupts (Hwi),** which includes Timer functions
❑ **Software interrupts (Swi),** which includes Clock functions
❑ **Tasks (Task)**
❑ **Background thread (Idle)**

These thread types are described briefly in the following section and discussed in more detail in the rest of this chapter.

2.2.1 Types of Threads

The four major types of threads in a DSP/BIOS program are:

❑ **Hardware interrupt (Hwi) threads**. Hwi threads (also called Interrupt Service Routines or ISRs) are the threads with the highest priority in a DSP/BIOS application. Hwi threads are used to perform time critical tasks that are subject to hard deadlines. They are triggered in response to external asynchronous events (interrupts) that occur in the real-time environment. Hwi threads always run to completion but can be preempted temporarily by Hwi threads triggered by other interrupts, if

enabled. See Section 4.2, Hardware Interrupts, page 4-11, for details about hardware interrupts. See Section 2.3, *Hardware Interrupts*, page 2-15, for details about hardware interrupts.

- **Software interrupt (Swi) threads**. Patterned after hardware interrupts (Hwi), software interrupt threads provide additional priority levels between Hwi threads and Task threads. Unlike Hwis, which are triggered by hardware interrupts, Swis are triggered programmatically by calling certain Swi module APIs. Swis handle threads subject to time constraints that preclude them from being run as tasks, but whose deadlines are not as severe as those of hardware ISRs. Like Hwi's, Swi's threads always run to completion. Swis allow Hwis to defer less critical processing to a lower-priority thread, minimizing the time the CPU spends inside an interrupt service routine, where other Hwis can be disabled. See Section 2.4, *Software Interrupts*, page 2-24, for details about Swis.
- **Task (Task) threads.** Task threads have higher priority than the background (Idle) thread and lower priority than software interrupts. Tasks differ from software interrupts in that they can wait (block) during execution until necessary resources are available. DSP/BIOS provides a number of mechanisms that can be used for inter-task communication and synchronization. These include Semaphores, Events, Message queues, and Mailboxes. See Section 2.5, *Tasks*, page 2-43, for details about tasks.
- **Idle Loop (Idle) thread**. Idle threads execute at the lowest priority in a DSP/BIOS application and are executed one after another in a continuous loop (the Idle Loop). After main returns, a DSP/BIOS application calls the startup routine for each DSP/BIOS module and then falls into the Idle Loop. Each thread must wait for all others to finish executing before it is called again. The Idle Loop runs continuously except when it is preempted by higher-priority threads. Only functions that do not have hard deadlines should be executed in the Idle Loop. See Section 2.6, *The Idle Loop*, page 2-61, for details about the background thread.

Another type of thread, a Clock thread, is run within the context of a Swi thread that is triggered by a Hwi thread invoked by a repetitive timer peripheral interrupt. See Section 4.2 for details.

2.2.2 Choosing Which Types of Threads to Use

The type and priority level you choose for each thread in an application program has an impact on whether the threads are scheduled on time and executed correctly. DSP/BIOS static configuration makes it easy to change a thread from one type to another.

A program can use multiple types of threads. Here are some rules for deciding which type of object to use for each thread to be performed by a program.

- **Swi or Task versus Hwi**. Perform only critical processing within hardware interrupt service routines. Hwis should be considered for processing hardware interrupts (IRQs) with deadlines down to the 5-microsecond range, especially when data may be overwritten if the deadline is not met. Swis or Tasks should be considered for events with longer deadlines—around 100 microseconds or more. Your Hwi functions should post Swis or tasks to perform lower-priority processing. Using lower-priority threads minimizes the length of time interrupts are disabled (interrupt latency), allowing other hardware interrupts to occur.
- **Swi versus Task.** Use Swis if functions have relatively simple interdependencies and data sharing requirements. Use tasks if the requirements are more complex. While higher-priority threads can preempt lower priority threads, only tasks can wait for another event, such as resource availability. Tasks also have more options than Swis when using shared data. All input needed by a Swi's function should be ready when the program posts the Swi. The Swi object's trigger structure provides a way to determine when resources are available. Swis are more memory-efficient because they all run from a single stack.
- **Idle**. Create Idle threads to perform noncritical housekeeping tasks when no other processing is necessary. Idle threads typically have no hard deadlines. Instead, they run when the system has unused processor time. You may use Idle threads to reduce power needs when other processing is not being performed. In this case, you should not depend upon housekeeping tasks to occur during power reduction times.
- **Clock**. Use Clock functions when you want a function to run at a rate based on a multiple of the interrupt rate of the peripheral that is driving the Clock tick. Clock functions can be configured to execute either periodically or just once. These functions run as Swi functions.
- **Clock versus Swi**. All Clock functions run at the same Swi priority, so one Clock function cannot preempt another. However, Clock functions can post lower-priority Swi threads for lengthy processing. This ensures that the Clock Swi can preempt those functions when the next system tick occurs and when the Clock Swi is posted again.

- **Timer.** Timer threads are run within the context of a Hwi thread. As such, they inherit the priority of the corresponding Timer interrupt. They are invoked at the rate of the programmed Timer period. Timer threads should do the absolute minimum necessary to complete the task required. If more processing time is required, consider posting a Swi to do the work or posting a Semaphore for later processing by a task so that CPU time is efficiently managed.

2.2.3 A Comparison of Thread Characteristics

Table 2-1 provides a comparison of the thread types supported by DSP/BIOS.

Table 2-1. Comparison of Thread Characteristics

Characteristic	Hwi	Swi	Task	Idle
Priority	Highest	2nd highest	2nd lowest	Lowest
Number of priority levels	family/device-specific	Up to 32. Periodic functions run at the priority of the Clock Swi.	Up to 32 (including 1 for the Idle Loop)	1
Can yield and pend	No, runs to completion except for preemption	No, runs to completion except for preemption	Yes	Should not pend. Pending would disable all registered Idle threads.
Execution states	Inactive, ready, running	Inactive, ready, running	Ready, running, blocked, terminated	Ready, running
Thread scheduler disabled by	Hwi_disable()	Swi_disable()	Task_disable()	Program exit
Posted or made ready to run by	Interrupt occurs	Swi_post(), Swi_andn(), Swi_dec(), Swi_inc(), Swi_or()	Task_create() and various task synchronization mechanisms (Event, Semaphore, Mailbox)	main() exits and no other thread is currently running
Stack used	System stack (1 per program)	System stack (1 per program)	Task stack (1 per task)	Task stack used by default (see Note 1)

Notes: 1) If you disable the Task Manager, Idle threads use the system stack.

Table 2.1. Comparison of Thread Characteristics (continued)

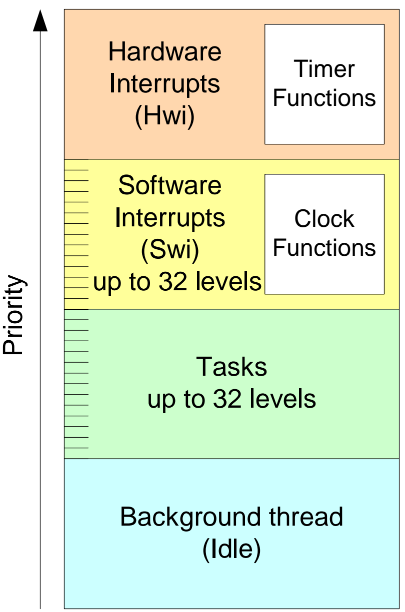
Characteristic	Hwi	Swi	Task	Idle
Context saved when preempts other thread	Entire context minus saved-by-callee registers (as defined by the TI C compiler) are saved to system.	Certain registers saved to system.	Entire context saved to task stack	--Not applicable--
Context saved when blocked	--Not applicable--	--Not applicable--	Saves the saved-by-callee registers (see optimizing compiler user's guide for your platform).	--Not applicable--
Share data with thread via	Streams, lists, pipes, global variables	Streams, lists, pipes, global variables	Streams, lists, pipes, gates, mailboxes, message queues, global variables	Streams, lists, pipes, global variables
Synchronize with thread via	--Not applicable--	Swi trigger	Semaphores, events, mailboxes	-Not applicable--
Function hooks	Yes: register, create, begin, end, delete	Yes:register, create, ready, begin, end, delete	Yes: register, create, ready, switch, exit, delete	No
Static creation	Yes	Yes	Yes	Yes
Dynamic creation	Yes	Yes	Yes	No
Dynamically change priority	See Note 1	Yes	Yes	No
Implicit logging	Interrupt event	Post, begin, end	Switch, yield, ready, exit	None
Implicit statistics	None	None	None	None

Notes: 1) Some devices allow hardware interrupt priorities to by modified.

2.2.4 Thread Priorities

Within DSP/BIOS, hardware interrupts have the highest priority. The priorities among the set of Hwi objects are not maintained implicitly by DSP/BIOS. The Hwi priority only applies to the order in which multiple interrupts that are ready on a given CPU cycle are serviced by the CPU. Hardware interrupts are preempted by another interrupt unless interrupts are globally disabled or when specific interrupts are individually disabled.

Figure 2-1. Thread Priorities



Swis have lower priority than Hwis. There are up to 32 priority levels available for Swis (16 by default). Swis can be preempted by a higher-priority Swi or any Hwi. Swis cannot block.

Tasks have lower priority than Swis. There are up to 32 task priority levels (16 by default). Tasks can be preempted by any higher-priority thread. Tasks can block while waiting for resource availability and lower-priority threads.

The background Idle Loop is the thread with the lowest priority of all. It runs in a loop when the CPU is not busy running another thread. When tasks are enabled, the Idle Loop is implemented as the only task running at priority 0. When tasks are disabled, the Idle Loop is fallen into after the application's "main()" function is called.

2.2.5 Yielding and Preemption

The DSP/BIOS thread schedulers run the highest-priority thread that is ready to run except in the following cases:

- The thread that is running disables some or all hardware interrupts temporarily with Hwi_disable() or Hwi_disableInterrupt(), preventing hardware ISRs from running.
- The thread that is running disables Swis temporarily with Swi_disable(). This prevents any higher-priority Swi from preempting the current thread. It does not prevent Hwis from preempting the current thread.
- The thread that is running disables task scheduling temporarily with Task_disable(). This prevents any higher-priority task from preempting the current task. It does not prevent Hwis and Swis from preempting the current task.

Both Hwis and Swis can interact with the DSP/BIOS task scheduler. When a task is blocked, it is often because the task is pending on a semaphore which is unavailable. Semaphores can be posted from Hwis and Swis as well as from other tasks. If a Hwi or Swi posts a semaphore to unblock a pending task, the processor switches to that task if that task has a higher priority than the currently running task (after the Hwi or Swi completes).

When running either a Hwi or Swi, DSP/BIOS uses a dedicated system interrupt stack, called the *system stack* (sometimes called the ISR stack). Each task uses its own private stack. Therefore, if there are no Tasks in the system, all threads share the same system stack. For performance reasons, sometimes it is advantageous to place the system stack in precious fast memory.

Table 2-2 shows what happens when one type of thread is running (top row) and another thread becomes ready to run (left column). The action shown is that of the newly posted (ready to run) thread.

Table 2-2. Thread Preemption

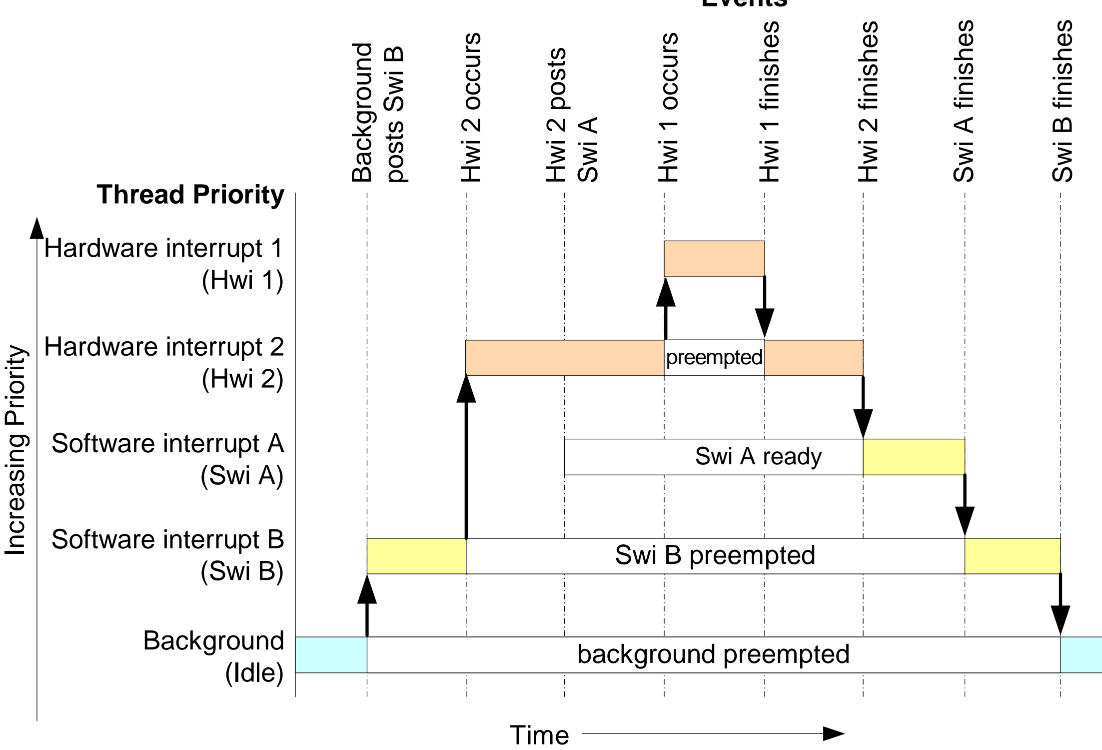
	Running Thread			
Newly Posted Thread	**Hwi**	**Swi**	**Task**	**Idle**
Enabled Hwi	Preempts if enabled*	Preempts	Preempts	Preempts
Disabled Hwi	Waits for reenable	Waits for reenable	Waits for reenable	Waits for reenable
Enabled, higher-priority Swi	Waits	Preempts	Preempts	Preempts
Lower-priority Swi	Waits	Waits	Preempts	Preempts
Enabled, higher-priority Task	Waits	Waits	Preempts	Preempts
Low-priority Task	Waits	Waits	Waits	Preempts

* On some targets, hardware interrupts can be individually enabled and disabled. This is not true on all targets. Also, some targets have controllers that support hardware interrupt prioritization, in which case a Hwi can only be preempted by a higher-priority Hwi.

Note that Table 2-2 shows the results if the type of thread that is posted is enabled. If that thread type is disabled (for example, by Task_disable), a thread cannot run in any case until its thread type is reenabled.

Figure 2-2 shows the execution graph for a scenario in which Swis and Hwis are enabled (the default), and a Hwi posts a Swi whose priority is higher than that of the Swi running when the interrupt occurs. Also, a second Hwi occurs while the first ISR is running and preempts the first ISR.

Figure 2-2. Preemption Scenario



In Figure 2-2, the low-priority Swi is asynchronously preempted by the Hwis. The first Hwi posts a higher-priority Swi, which is executed after both Hwis finish executing.

Here is sample pseudo-code for the example depicted in Figure 2-2:

```
backgroundThread()
{
   Swi_post(Swi_B) /* priority = 5 */
}

Hwi_1 ()
{
   . . .
}
Hwi_2 ()
{
   Swi_post(Swi_A) /* priority = 7 */
}
```

2.2.6 Hooks

Hwi, Swi, and Task threads optionally provide points in a thread's life cycle to insert user code for instrumentation, monitoring, or statistics gathering purposes. Each of these code points is called a "hook" and the user function provided for the hook is called a "hook function".

The following hook functions can be set for the various thread types:

Thread Type	Hook Functions
Hwi	Register, Create, Begin, End, and Delete. See Section 2.3.2.
Swi	Register, Create, Ready, Begin, End, and Delete. See Section 2.4.8.
Task	Register, Create, Ready, Switch, Exit, and Delete. See Section 2.5.4.

Hooks are declared as a set of hook functions called "hook sets". You do not need to define all hook functions within a set, only those that are required by the application.

Hook functions can only be declared statically (in an XDCtools configuration) so that they may be efficiently invoked when provided and result in *no runtime overhead* when a hook function is not provided.

Except for the Register hook, all hook functions are invoked with a handle to the object associated with that thread as its argument (that is, a Hwi object, a Swi object, or a Task object). Other arguments are provided for some thread-type-specific hook functions.

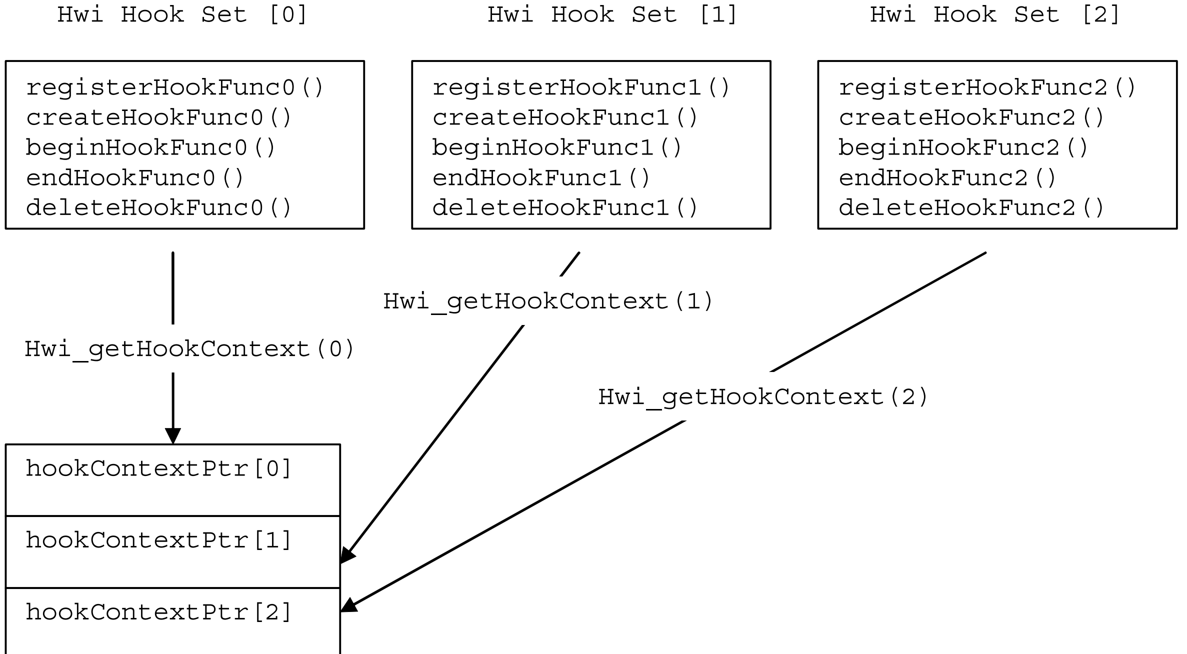
You can define as many hook sets as necessary for your application. When more than one hook set is defined, the individual hook functions within each set are invoked in hook ID order for a particular hook type. For example, during Task_create() the order that the Create hook within each Task hook set is invoked is the order in which the Task hook sets were originally defined.

The argument to a thread's Register hook (which is invoked only once) is an index (the "hook ID") indicating the hook set's relative order in the hook function calling sequence.

Each set of hook functions has a unique associated "hook context pointer". This general-purpose pointer can be used by itself to hold hook set specific information, or it can be initialized to point to a block of memory allocated by the Create hook function within a hook set if more space is required for a particular application.

An individual hook function obtains the value of its associated context pointer through thread-type-specific APIs—Hwi_getHookContext(), Swi_getHookContext(), and Task_getHookContext(). Corresponding APIs for initializing the context pointers are also provided—Hwi_setHookContext(), Swi_setHookContext(), and Task_setHookContext(). Each of these APIs take the hook ID as an argument.

The following diagram shows an application with three Hwi hook sets:



The hook context pointers are accessed using Hwi_getHookContext() using the index provided to the three Register hook functions.

Just prior to invoking your ISR functions, the Begin Hook functions are invoked in the following order:

1) beginHookFunc0();
2) beginHookFunc1();
3) beginHookFunc2();

Likewise, upon return from your ISR functions the End Hook functions are invoked in the following order:

1) endHookFunc0();
2) endHookFunc1();
3) endHookFunc2();

2.3 Hardware Interrupts

Hardware interrupts (Hwis) handle critical processing that the application must perform in response to external asynchronous events. The DSP/BIOS target/device specific Hwi modules are used to manage hardware interrupts.

In a typical embedded system, hardware interrupts are triggered either by on-device peripherals or by devices external to the processor. In both cases, the interrupt causes the processor to vector to the ISR address.

Any interrupt processing that may invoke DSP/BIOS APIs that affect Swi and Task scheduling must be written in C or C++. The HWI_enter()/HWI_exit() macros provided in earlier versions of DSP/BIOS for calling assembly language ISRs are no longer provided.

Assembly language ISRs that do not interact with DSP/BIOS can be specified with Hwi_plug(). Such ISRs must do their own context preservation. They may use the "interrupt" keyword, C functions, or assembly language functions.

All hardware interrupts run to completion. If a Hwi is posted multiple times before its ISR has a chance to run, the ISR runs only one time. For this reason, you should minimize the amount of code performed by a Hwi function.

If interrupts are globally enabled—that is, by calling Hwi_enable()—a hardware interrupt can be preempted by any interrupt that has been enabled.

Hwis must not use the Chip Support Library (CSL) for the target. Instead, see Chapter 6 for a description of Hardware Abstraction Layer APIs.

Associating an ISR function with a particular interrupt is done by creating a Hwi object.

2.3.1 Creating Hwi Objects

The Hwi module maintains a table of pointers to Hwi objects that contain information about each Hwi managed by the dispatcher. To create a Hwi object dynamically, use a call with this syntax:

```
Hwi_Handle hwi0;
Hwi_Params hwiParams;
Hwi_Params_init(&hwiParams);

hwiParams.arg = 5;
hwi0 = Hwi_create(id, hwiFunc, &hwiParams, &eb);
```

Here, hwi0 is a handle to the created Hwi object, id is the interrupt number being defined, hwiFunc is the name of the function associated with the Hwi, and hwiParams is a structure that contains Hwi instance parameters (enable/restore masks, the Hwi function argument, etc). Here, hwiParams.arg is set to 5. If NULL is passed instead of a pointer to an actual Hwi_Params struct, a default set of parameters is used. The "eb" is an error block that you can use to handle errors that may occur during Hwi object creation.

The corresponding static configuration Hwi object creation syntax is:

```
var Hwi = xdc.useModule('ti.sysbios.hal.Hwi');
var hwiParams = new Hwi.Params;

hwiParams.arg = 5;
Program.global.hwi0 = Hwi.create(id, '&hwiFunc', hwiParams);
```

Here, the "hwiParams = new Hwi.Params" statement does the equivalent of creating and initializing the hwiParams structure with default values. In the static configuration world, no Error Block (eb) is required for the "create" function. The "Program.global.hwi0" name becomes a a runtime-accessible handle (symbol name = "hwi0") to the statically-created Hwi object.

2.3.2 Hwi Hooks

The Hwi module supports the following set of Hook functions:

- **Register.** A function called before any statically created Hwis are initialized at runtime. The register hook is called at boot time before main() and before interrupts are enabled.
- **Create.** A function called when a Hwi is created. This includes Hwis that are created statically and those created dynamically using Hwi_create().
- **Begin.** A function called just prior to running a Hwi ISR function.
- **End.** A function called just after a Hwi ISR function finishes.
- **Delete.** A function called when a Hwi is deleted at runtime with Hwi_delete().

The following HookSet structure type definition encapsulates the hook functions supported by the Hwi module:

```
typedef struct Hwi_HookSet {
    Void (*registerFxn)(Int);                 /* Register Hook */
    Void (*createFxn)(Handle, Error.Block *); /* Create Hook */
    Void (*beginFxn)(Handle);                 /* Begin Hook */
    Void (*endFxn)(Handle);                   /* End Hook */
    Void (*deleteFxn)(Handle);                /* Delete Hook */
};
```

Hwi Hook functions can only be configured statically.

2.3.2.1 Register Function

The register function is provided to allow a hook set to store its corresponding hook ID. This ID can be passed to Hwi_setHookContext() and Hwi_getHookContext() to set or get hook-specific context. The Register function must be specified if the hook implementation needs to use Hwi_setHookContext() or Hwi_getHookContext().

The registerFxn hook function is called during system initialization before interrupts have been enabled.

The Register function has the following signature:

```
Void registerFxn(Int id);
```

2.3.2.2 Create and Delete Functions

The Create and Delete functions are called whenever a Hwi is created or deleted. The Create function is passed an Error_Block that is to be passed to Memory_alloc() for applications that require additional context storage space.

The createFxn and deleteFxn functions are called with interrupts enabled (unless called at boot time or from main()).

These functions have the following signatures:

```
Void createFxn(Hwi_Handle hwi, Error_Block *eb);
Void deleteFxn(Hwi_Handle hwi);
```

2.3.2.3 Begin and End Functions

The Begin and End hook functions are called with interrupts globally disabled, therefore any hook processing function contributes to overall system interrupt response latency. In order to minimize this impact, carefully consider the processing time spent in a Hwi beginFxn or endFxn hook function.

The beginFxn is invoked just prior to calling the ISR function. The endFxn is invoked immediately after the return from the ISR function.

These functions have the following signatures:

```
Void beginFxn(Hwi_Handle hwi);
Void endFxn(Hwi_Handle hwi);
```

When more than one Hook Set is defined, the individual hook functions of a common type are invoked in hook ID order.

2.3.2.4 Hwi Hooks Example

The following example application uses two Hwi hook sets. The Hwi associated with a statically-created Timer is used to exercise the Hwi hook functions. This example demonstrates how to read and write the Hook Context Pointer associated with each hook set.

The XDCtools configuration script and program output are shown after the C code listing.

This is the C code for the example:

```
/* ======== HwiHookExample.c ========
 * This example demonstrates basic Hwi hook usage. */

#include <xdc/std.h>
#include <xdc/runtime/Error.h>
#include <xdc/runtime/System.h>
#include <xdc/runtime/Timestamp.h>

#include <ti/sysbios/BIOS.h>
#include <ti/sysbios/knl/Task.h>
#include <ti/sysbios/hal/Timer.h>
#include <ti/sysbios/hal/Hwi.h>

extern Timer_Handle myTimer;
volatile Bool myEnd2Flag = FALSE;
Int myHookSetId1, myHookSetId2;

/* HookSet 1 functions */
```

```
/* ======== myRegister1 ========
 * invoked during Hwi module startup before main()
 * for each HookSet */
Void myRegister1(Int hookSetId)
{
    System_printf("myRegister1: assigned hookSet Id = %d\n",
                  hookSetId);
    myHookSetId1 = hookSetId;
}

/* ======== myCreate1 ========
 * invoked during Hwi module startup before main()
 * for statically created Hwis */
Void myCreate1(Hwi_Handle hwi, Error_Block *eb)
{
    Ptr pEnv;

    pEnv = Hwi_getHookContext(hwi, myHookSetId1);
    /* pEnv should be 0 at this point. If not, there's a bug. */
    System_printf("myCreate1: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Hwi_setHookContext(hwi, myHookSetId1, (Ptr)0xdead1);
}

/* ======== myBegin1 ========
 * invoked before Timer Hwi func */
Void myBegin1(Hwi_Handle hwi)
{
    Ptr pEnv;

    pEnv = Hwi_getHookContext(hwi, myHookSetId1);
    System_printf("myBegin1: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Hwi_setHookContext(hwi, myHookSetId1, (Ptr)0xbeef1);
}
```

```
/* ======== myEnd1 ========
 * invoked after Timer Hwi func */
Void myEnd1(Hwi_Handle hwi)
{
    Ptr pEnv;

    pEnv = Hwi_getHookContext(hwi, myHookSetId1);
    System_printf("myEnd1: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Hwi_setHookContext(hwi, myHookSetId1, (Ptr)0xc0de1);
}

/* HookSet 2 functions */
/* ======== myRegister2 ========
 * invoked during Hwi module startup before main
 * for each HookSet */
Void myRegister2(Int hookSetId)
{
    System_printf("myRegister2: assigned hookSet Id = %d\n",
                  hookSetId);
    myHookSetId2 = hookSetId;
}

/* ======== myCreate2 ========
 * invoked during Hwi module startup before main
 * for statically created Hwis */
Void myCreate2(Hwi_Handle hwi, Error_Block *eb)
{
    Ptr pEnv;

    pEnv = Hwi_getHookContext(hwi, myHookSetId2);
    /* pEnv should be 0 at this point. If not, there's a bug. */
    System_printf("myCreate2: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Hwi_setHookContext(hwi, myHookSetId2, (Ptr)0xdead2);
}

/* ======== myBegin2 ========
 * invoked before Timer Hwi func */
Void myBegin2(Hwi_Handle hwi)
{
    Ptr pEnv;

    pEnv = Hwi_getHookContext(hwi, myHookSetId2);
    System_printf("myBegin2: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Hwi_setHookContext(hwi, myHookSetId2, (Ptr)0xbeef2);
}
```

```
/* ======== myEnd2 ========
 * invoked after Timer Hwi func */
Void myEnd2(Hwi_Handle hwi)
{
    Ptr pEnv;

    pEnv = Hwi_getHookContext(hwi, myHookSetId2);
    System_printf("myEnd2: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Hwi_setHookContext(hwi, myHookSetId2, (Ptr)0xc0de2);
    myEnd2Flag = TRUE;
}

/* ======== myTimerFunc ========
 * Timer interrupt handler */
Void myTimerFunc(UArg arg)
{
    System_printf("Entering myTimerHwi\n");
}

/* ======== myTaskFunc ======== */
Void myTaskFunc(UArg arg0, UArg arg1)
{
    System_printf("Entering myTask.\n");

    Timer_start(myTimer);
    /* wait for timer interrupt and myEnd2 to complete */
    while (!myEnd2Flag) {
       ;
    }
    System_printf("myTask exiting ...\n");
}

/* ======== myIdleFunc ======== */
Void myIdleFunc()
{
    System_printf("Entering myIdleFunc().\n");
    System_exit(0);
}
```

```
/* ======== main ======== */
Int main(Int argc, Char* argv[])
{
    System_printf("Starting HwiHookExample...\n");
    BIOS_start();
    return (0);
}
```

This is the XDCtools configuration script for the example:

```
/* pull in Timestamp to print time in hook functions */
xdc.useModule('xdc.runtime.Timestamp');

/* Disable Clock so that ours is the only Timer allocated */
var BIOS = xdc.useModule('ti.sysbios.BIOS');
BIOS.clockEnabled = false;

var Idle = xdc.useModule('ti.sysbios.knl.Idle');
Idle.addFunc('&myIdleFunc');

/* Create myTask with default task params */
var Task = xdc.useModule('ti.sysbios.knl.Task');
var taskParams = new Task.Params();
Program.global.myTask = Task.create('&myTaskFunc', taskParams);

/* Create myTimer as source of Hwi */
var Timer = xdc.useModule('ti.sysbios.hal.Timer');
var timerParams = new Timer.Params();
timerParams.startMode = Timer.StartMode_USER;
timerParams.runMode = Timer.RunMode_ONESHOT;
timerParams.period = 1000; // 1ms
Program.global.myTimer = Timer.create(Timer.ANY,
    "&myTimerFunc", timerParams);
```

```
/* Define and add two Hwi HookSets
 * Notice, no deleteFxn is provided.
 */
var Hwi = xdc.useModule('ti.sysbios.hal.Hwi');

/* Hook Set 1 */
Hwi.addHookSet({
      registerFxn: '&myRegister1',
      createFxn: '&myCreate1',
      beginFxn: '&myBegin1',
      endFxn: '&myEnd1',
});

/* Hook Set 2 */
Hwi.addHookSet({
      registerFxn: '&myRegister2',
      createFxn: '&myCreate2',
      beginFxn: '&myBegin2',
      endFxn: '&myEnd2',
});
```

The program output is as follows:

```
myRegister1: assigned hookSet Id = 0
myRegister2: assigned hookSet Id = 1
myCreate1: pEnv = 0x0, time = 0
myCreate2: pEnv = 0x0, time = 0
Starting HwiHookExample...
Entering myTask.
myBegin1: pEnv = 0xdead1, time = 75415
myBegin2: pEnv = 0xdead2, time = 75834
Entering myTimerHwi
myEnd1: pEnv = 0xbeef1, time = 76427
myEnd2: pEnv = 0xbeef2, time = 76830
myTask exiting ...
Entering myIdleFunc().
```

2.4 Software Interrupts

Software interrupts are patterned after hardware ISRs. The Swi module in DSP/BIOS provides a software interrupt capability. Software interrupts are triggered programmatically, through a call to a DSP/BIOS API such as Swi_post(). Software interrupts have priorities that are higher than tasks but lower than hardware interrupts.

Note: The Swi module should not be confused with the SWI instruction that exists on many processors. The DSP/BIOS Swi module is independent from any target/device-specific software interrupt features.

Swi threads are suitable for handling application tasks that occur at slower rates or are subject to less severe real-time deadlines than those of Hwis.

The DSP/BIOS APIs that can trigger or post a Swi are:

- Swi_andn()
- Swi_dec()
- Swi_inc()
- Swi_or()
- Swi_post()

The Swi Manager controls the execution of all Swi functions. When the application calls one of the APIs above, the Swi Manager schedules the function corresponding to the specified Swi for execution. To handle Swi functions, the Swi Manager uses Swi objects.

If a Swi is posted, it runs only after all pending Hwis have run. A Swi function in progress can be preempted at any time by a Hwi; the Hwi completes before the Swi function resumes. On the other hand, Swi functions always preempt tasks. All pending Swis run before even the highest priority task is allowed to run. In effect, a Swi function is like a task with a priority higher than all ordinary tasks.

Note:

Two things to remember about Swi functions are:

A Swi function runs to completion unless it is interrupted by a Hwi or preempted by a higher-priority Swi.

Any Hwi ISR that triggers or posts a Swi must have been invoked by the Hwi dispatcher.

2.4.1 Creating Swi Objects

As with many other DSP/BIOS objects, you can create Swi objects either dynamically—with a call to Swi_create()—or statically in the configuration. Swis you create dynamically can also be deleted during program execution.

To add a new Swi to the configuration, create a new Swi object in the configuration script. Set the function property for each Swi to run a function when the object is triggered by the application. You can also configure up to two arguments to be passed to each Swi function.

As with all modules with instances, you can determine from which memory segment Swi objects are allocated. Swi objects are accessed by the Swi Manager when Swis are posted and scheduled for execution.

For complete reference information on the Swi API, configuration, and objects, see the Swi module in the "ti.sysbios.knl" package documentation in the online documentation. (For information on running online help, see Section 1.5.1, *Using the API Reference Help System*, page 1-7.)

To create a Swi object dynamically, use a call with this syntax:

```
Swi_Handle swi0;
Swi_Params swiParams;
Swi_Params_init(swiParams);

swi0 = Swi_create(swiFunc, &swiParams, &eb);
```

Here, swi0 is a handle to the created Swi object, swiFunc is the name of the function associated with the Swi, and swiParams is a structure of type Swi_Params that contains the Swi instance parameters (priority, arg0, arg1, etc). If NULL is passed instead of a pointer to an actual Swi_Params struct, a default set of parameters is used. "eb" is an error block you can use to handle errors that may occur during Swi object creation.

Note:

Swi_create() can only be called from the task level, not from a Hwi or another Swi.

To create a Swi object in an XDCtools configuration file, use statements like these:

```
var Swi = xdc.useModule('ti.sysbios.knl.Swi');
var swiParams = new Swi.Params();
program.global.swi0 = Swi.create(swiParams);
```

2.4.2 Setting Software Interrupt Priorities

There are different priority levels among Swis. You can create as many Swis as your memory constraints allow for each priority level. You can choose a higher priority for a Swi that handles a thread with a shorter real-time deadline, and a lower priority for a Swi that handles a thread with a less critical execution deadline.

The number of Swi priorities supported within an application is configurable up to a maximum 32. The default number of priority levels is 16. The lowest priority level is 0. Thus, by default, the highest priority level is 15.

You cannot sort Swis within a single priority level. They are serviced in the order in which they were posted.

2.4.3 Software Interrupt Priorities and Application Stack Size

When a Swi is posted, its associated Swi function is invoked using the system stack. While you can have up to 32 Swi priority levels, keep in mind that in the worst case, each Swi priority level can result in a nesting of the Swi scheduling function (that is, the lowest priority Swi is preempted by the next highest priority Swi, which, in turn, is preempted by the next highest, …). This results in an increasing stack size requirement for each Swi priority level actually used. Thus, giving Swis the same priority level is more efficient in terms of stack size than giving each Swi a separate priority.

The default system stack size is 4096 bytes. You can set the system stack size by adding the following line to your config script:

```
Program.stack = yourStackSize;
```

Note: The Clock module creates and uses a Swi with the maximum Swi priority (that is, if there are 16 Swi priorities, the Clock Swi has priority 15).

2.4.4 Execution of Software Interrupts

Swis can be scheduled for execution with a call to Swi_andn(), Swi_dec(), Swi_inc(), Swi_or(), and Swi_post(). These calls can be used virtually anywhere in the program—Hwi functions, Clock functions, Idle functions, or other Swi functions.

When a Swi is posted, the Swi Manager adds it to a list of posted Swis that are pending execution. The Swi Manager checks whether Swis are currently enabled. If they are not, as is the case inside a Hwi function, the Swi Manager returns control to the current thread.

If Swis are enabled, the Swi Manager checks the priority of the posted Swi object against the priority of the thread that is currently running. If the thread currently running is the background Idle Loop or a lower priority Swi, the Swi Manager removes the Swi from the list of posted Swi objects and switches the CPU control from the current thread to start execution of the posted Swi function.

If the thread currently running is a Swi of the same or higher priority, the Swi Manager returns control to the current thread, and the posted Swi function runs after all other Swis of higher priority or the same priority that were previously posted finish execution.

There are two important things to remember about Swi:

- When a Swi starts executing it must run to completion without blocking.
- When called from within a Hwi, the code sequence calling any Swi function that can trigger or post a Swi must be invoked by the Hwi dispatcher.

Swi functions can be preempted by threads of higher priority (such as a Hwi or a Swi of higher priority). However, Swi functions cannot block. You cannot suspend a Swi while it waits for something—like a device—to be ready.

If a Swi is posted multiple times before the Swi Manager has removed it from the posted Swi list, its Swi function executes only once, much like a Hwi is executed only once if the Hwi is triggered multiple times before the CPU clears the corresponding interrupt flag bit in the interrupt flag register. (See Section 2.4.5, *Using a Swi Object's Trigger Variable*, page 2-27, for more information on how to handle Swis that are posted multiple times before they are scheduled for execution.)

Applications should not make any assumptions about the order in which Swi functions of equal priority are called. However, a Swi function can safely post itself (or be posted by another interrupt). If more than one is pending, all Swi functions are called before any tasks run.

2.4.5 Using a Swi Object's Trigger Variable

Each Swi object has an associated 32-bit trigger variable for C6x targets and a 16-bit trigger variable for C5x targets. This is used either to determine whether to post the Swi or to provide values that can be evaluated within the Swi function.

Swi_post(), Swi_or(), and Swi_inc() post a Swi object unconditionally:

- Swi_post() does not modify the value of the Swi object trigger when it is used to post a Swi.

- ❏ Swi_or() sets the bits in the trigger determined by a mask that is passed as a parameter, and then posts the Swi.
- ❏ Swi_inc() increases the Swi's trigger value by one before posting the Swi object.

Swi_andn() and Swi_dec() post a Swi object only if the value of its trigger becomes 0:

- ❏ Swi_andn() clears the bits in the trigger determined by a mask passed as a parameter.
- ❏ Swi_dec() decreases the value of the trigger by one.

Table 2-3 summarizes the differences between these functions.

Table 2-3. Swi Object Function Differences

Action	**Treats Trigger as Bitmask**	**Treats Trigger as Counter**	**Does not Modify Trigger**
Always post	Swi_or()	Swi_inc()	Swi_post()
Post if it becomes zero	Swi_andn()	Swi_dec()	—

The Swi trigger allows you to have tighter control over the conditions that should cause a Swi function to be posted, or the number of times the Swi function should be executed once the Swi is posted and scheduled for execution.

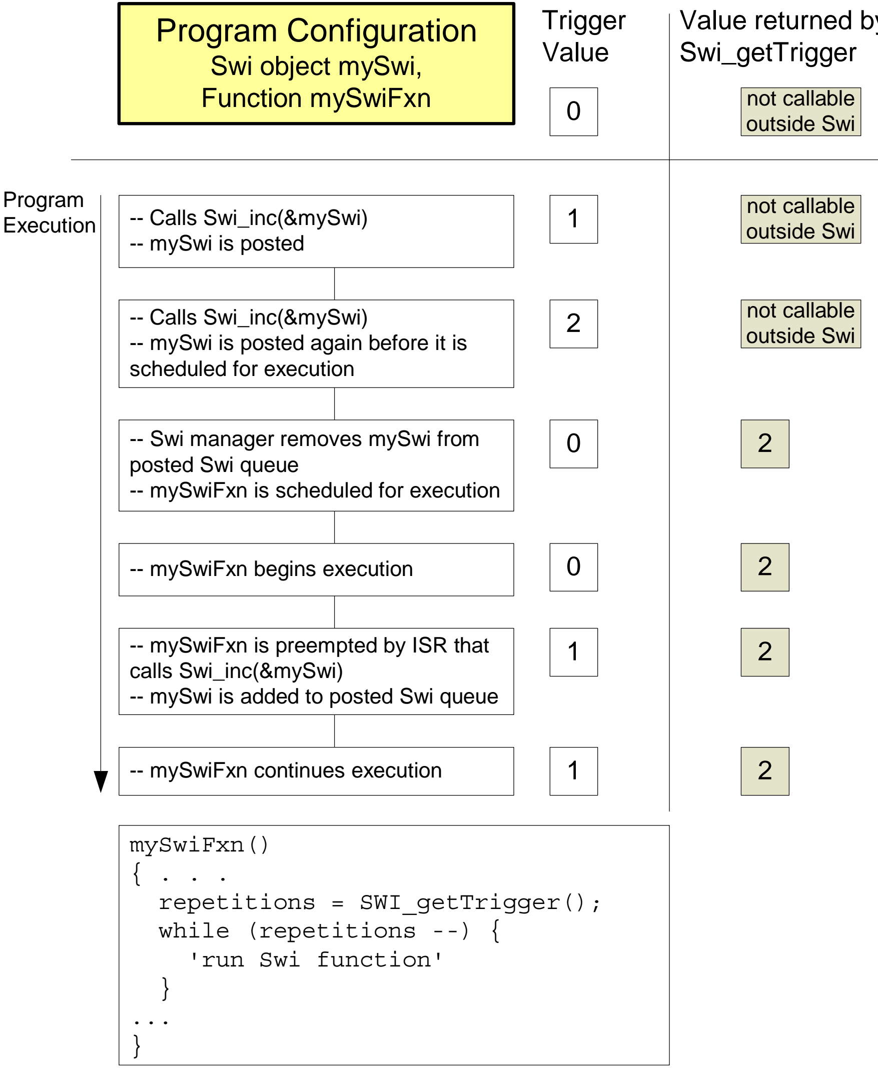
To access the value of its trigger, a Swi function can call Swi_getTrigger(). Swi_getTrigger() can be called only from the Swi object's function. The value returned by Swi_getTrigger() is the value of the trigger before the Swi object was removed from the posted Swi queue and the Swi function was scheduled for execution.

When the Swi Manager removes a pending Swi object from the posted object's queue, its trigger is reset to its initial value. The initial value of the trigger should be set in the application's configuration script. If while the Swi function is executing, the Swi is posted again, its trigger is updated accordingly. However, this does not affect the value returned by Swi_getTrigger() while the Swi function executes. That is, the trigger value that Swi_getTrigger() returns is the latched trigger value when the Swi was removed from the list of pending Swis. The Swi's trigger however, is immediately reset after the Swi is removed from the list of pending Swis and scheduled for execution. This gives the application the ability to keep updating the value of the Swi trigger if a new posting occurs, even if the Swi function has not finished its execution.

For example, if a Swi object is posted multiple times before it is removed from the queue of posted Swis, the Swi Manager schedules its function to execute only once. However, if a Swi function must always run multiple times when the Swi object is posted multiple times, Swi_inc() should be used to post the Swi as shown in Figure 2-3.

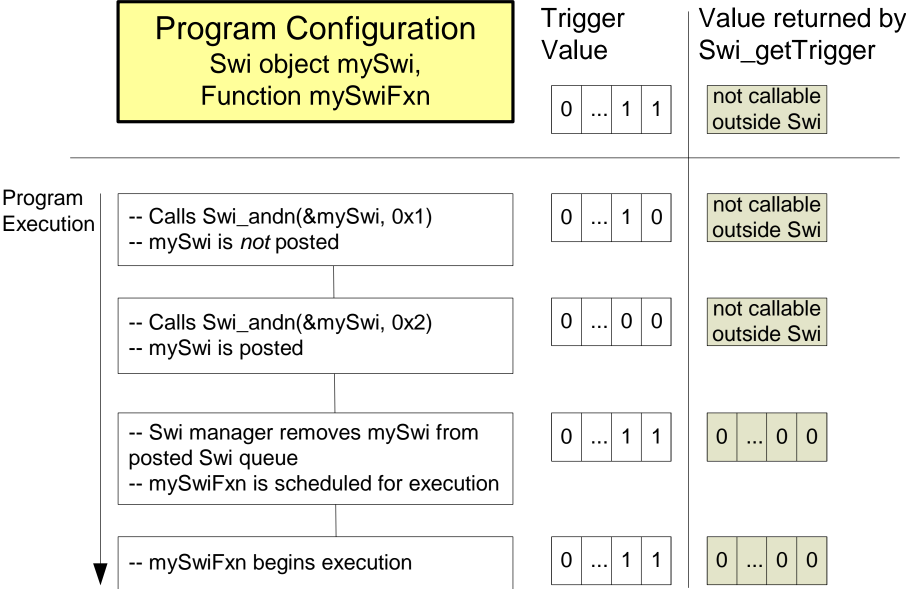
When a Swi has been posted using Swi_inc(), once the Swi Manager calls the corresponding Swi function for execution, the Swi function can access the Swi object trigger to know how many times it was posted before it was scheduled to run, and proceed to execute the same function as many times as the value of the trigger.

Figure 2-3. Using Swi_inc() to Post a Swi



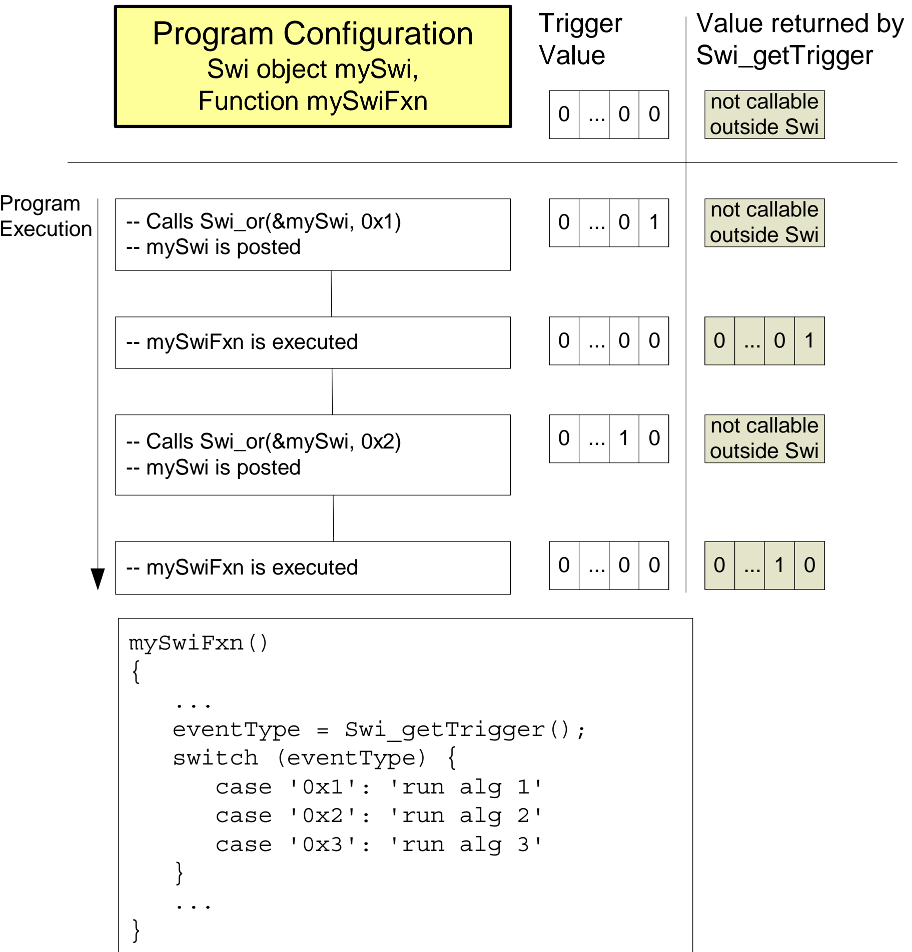
If more than one event must always happen for a given Swi to be triggered, Swi_andn() should be used to post the corresponding Swi object as shown in Figure 2-4. For example, if a Swi must wait for input data from two different devices before it can proceed, its trigger should have two set bits when the Swi object is configured. When both functions that provide input data have completed their tasks, they should both call Swi_andn() with complementary bitmasks that clear each of the bits set in the Swi trigger default value. Hence, the Swi is posted only when data from both processes is ready.

Figure 2-4. Using Swi_andn() to Post a Swi



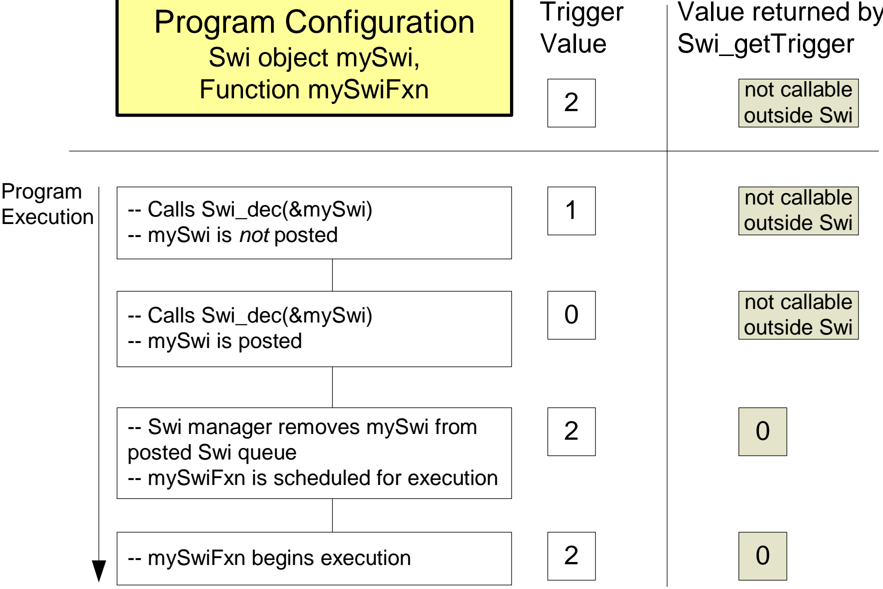
In some situations the Swi function can call different functions depending on the event that posted it. In that case the program can use Swi_or() to post the Swi object unconditionally when an event happens. This is shown in Figure 2-5. The value of the bitmask used by Swi_or() encodes the event type that triggered the post operation, and can be used by the Swi function as a flag that identifies the event and serves to choose the function to execute.

Figure 2-5. Using Swi_or() to Post a Swi.



If the program execution requires that multiple occurrences of the same event must take place before a Swi is posted, Swi_dec() should be used to post the Swi as shown in Figure 2-6. By configuring the Swi trigger to be equal to the number of occurrences of the event before the Swi should be posted and calling Swi_dec() every time the event occurs, the Swi is posted only after its trigger reaches 0; that is, after the event has occurred a number of times equal to the trigger value.

Figure 2-6. Using Swi_dec() to Post a Swi



2.4.6 Benefits and Tradeoffs

There are several benefits to using Swis instead of Hwis:

- ❑ By modifying shared data structures in a Swi function instead of a Hwi, you can get mutual exclusion by disabling Swis while a Task accesses the shared data structure (see page 2–33). This allows the system to respond to events in real-time using Hwis. In contrast, if a Hwi function modified a shared data structure directly, Tasks would need to disable Hwis to access data structures in a mutually exclusive way. Obviously, disabling Hwis may degrade the performance of a real-time system.
- ❑ It often makes sense to break long ISRs into two pieces. The Hwi takes care of the extremely time-critical operation and defers less critical processing to a Swi function by posting the Swi within the Hwi function.

Remember that a Swi function must complete before any blocked Task is allowed to run.

2.4.7 Synchronizing Swi Functions

Within an Idle, Task, or Swi function, you can temporarily prevent preemption by a higher-priority Swi by calling Swi_disable(), which disables all Swi preemption. To reenable Swi preemption, call Swi_restore().

Swis are enabled or disabled as a group. An individual Swi cannot be enabled or disabled on its own.

When DSP/BIOS finishes initialization and before the first task is called, Swis have been enabled. If an application wishes to disable Swis, it calls Swi_disable() as follows:

```
key = Swi_disable();
```

The corresponding enable function is Swi_restore().

```
Swi_restore(key);
```

where key is a value used by the Swi module to determine if Swi_disable() has been called more than once. This allows nesting of Swi_disable() / Swi_restore() calls, since only the outermost Swi_restore() call actually enables Swis. In other words, a task can disable and enable Swis without having to determine if Swi_disable() has already been called elsewhere.

When Swis are disabled, a posted Swi function does not run at that time. The interrupt is "latched" in software and runs when Swis are enabled and it is the highest-priority thread that is ready to run.

To delete a dynamically created Swi, use Swi_delete(). The memory associated with Swi is freed. Swi_delete() can only be called from the task level.

2.4.8 Swi Hooks

The Swi module supports the following set of Hook functions:

- **Register.** A function called before any statically created Swis are initialized at runtime. The register hook is called at boot time before main() and before interrupts are enabled.
- **Create.** A function called when a Swi is created. This includes Swis that are created statically and those created dynamically using Swi_create().
- **Ready.** A function called when any Swi becomes ready to run.
- **Begin.** A function called just prior to running a Swi function.
- **End.** A function called just after returning from a Swi function.

- **Delete.** A function called when a Swi is deleted at runtime with Swi_delete().

The following Swi_HookSet structure type definition encapsulates the hook functions supported by the Swi module:

```
typedef struct Swi_HookSet {
    Void (*registerFxn)(Int);                    /* Register Hook */
    Void (*createFxn)(Handle, Error.Block *); /* Create Hook */
    Void (*readyFxn)(Handle);                     /* Ready Hook */
    Void (*beginFxn)(Handle);                     /* Begin Hook */
    Void (*endFxn)(Handle);                       /* End Hook */
    Void (*deleteFxn)(Handle);                   /* Delete Hook */
};
```

Swi Hook functions can only be configured statically.

When more than one Hook Set is defined, the individual hook functions of a common type are invoked in hook ID order.

2.4.8.1 Register Function

The Register function is provided to allow a hook set to store its corresponding hook ID. This ID can be passed to Swi_setHookContext() and Swi_getHookContext() to set or get hook-specific context. The Register function must be specified if the hook implementation needs to use Swi_setHookContext() or Swi_getHookContext().

The registerFxn function is called during system initialization before interrupts have been enabled.

The Register functions has the following signature:

```
Void registerFxn(Int id);
```

2.4.8.2 Create and Delete Functions

The Create and Delete functions are called whenever a Swi is created or deleted. The Create function is passed an Error_Block that is to be passed to Memory_alloc() for applications that require additional context storage space.

The createFxn and deleteFxn functions are called with interrupts enabled (unless called at boot time or from main()).

These functions have the following signatures.

```
Void createFxn(Swi_Handle swi, Error_Block *eb);
Void deleteFxn(Swi_Handle swi);
```

2.4.8.3 Ready, Begin and End Functions

The Ready, Begin and End hook functions are called with interrupts enabled. The readyFxn function is called when a Swi is posted and made ready to run. The beginFxn function is called right before the function associated with the given Swi is run. The endFxn function is called right after returning from the Swi function.

These functions have the following signatures:

```
Void readyFxn(Swi_Handle swi);
Void beginFxn(Swi_Handle swi);
Void endFxn(Swi_Handle swi);
```

2.4.8.4 Swi Hooks Example

The following example application uses two Swi hook sets. This example demonstrates how to read and write the Hook Context Pointer associated with each hook set.

The XDCtools configuration script and program output are shown after the C code listing.

This is the C code for the example:

```
/* ======== SwiHookExample.c ========
 * This example demonstrates basic Swi hook usage */

#include <xdc/std.h>
#include <xdc/runtime/Error.h>
#include <xdc/runtime/System.h>
#include <xdc/runtime/Timestamp.h>

#include <ti/sysbios/BIOS.h>
#include <ti/sysbios/knl/Task.h>
#include <ti/sysbios/hal/Timer.h>
#include <ti/sysbios/knl/Swi.h>

Swi_Handle mySwi;
Int myHookSetId1, myHookSetId2;

/* HookSet 1 functions */
```

```
/* ======== myRegister1 ========
 * invoked during Swi module startup before main
 * for each HookSet */
Void myRegister1(Int hookSetId)
{
    System_printf("myRegister1: assigned hookSet Id = %d\n",
hookSetId);
    myHookSetId1 = hookSetId;
}

/* ======== myCreate1 ========
 * invoked during Swi_create for dynamically created Swis */
Void myCreate1(Swi_Handle swi, Error_Block *eb)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId1);

    /* pEnv should be 0 at this point. If not, there's a bug. */
    System_printf("myCreate1: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Swi_setHookContext(swi, myHookSetId1, (Ptr)0xdead1);
}

/* ======== myReady1 ========
 * invoked when Swi is posted */
Void myReady1(Swi_Handle swi)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId1);

    System_printf("myReady1: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Swi_setHookContext(swi, myHookSetId1, (Ptr)0xbeef1);
}
```

```
/* ======== myBegin1 ========
 * invoked just before Swi func is run */
Void myBegin1(Swi_Handle swi)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId1);

    System_printf("myBegin1: pEnv = 0x%x, time = %d\n", pEnv,
                   Timestamp_get32());
    Swi_setHookContext(swi, myHookSetId1, (Ptr)0xfeeb1);
}

/* ======== myEnd1 ========
 * invoked after Swi func returns */
Void myEnd1(Swi_Handle swi)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId1);

    System_printf("myEnd1: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Swi_setHookContext(swi, myHookSetId1, (Ptr)0xc0de1);
}

/* ======== myDelete1 ========
 * invoked upon Swi deletion */
Void myDelete1(Swi_Handle swi)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId1);

    System_printf("myDelete1: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
}
```

```
/* HookSet 2 functions */

/* ======== myRegister2 ========
 * invoked during Swi module startup before main
 * for each HookSet */
Void myRegister2(Int hookSetId)
{
    System_printf("myRegister2: assigned hookSet Id = %d\n",
                  hookSetId);
    myHookSetId2 = hookSetId;
}

/* ======== myCreate2 ========
 * invoked during Swi_create for dynamically created Swis */
Void myCreate2(Swi_Handle swi, Error_Block *eb)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId2);

    /* pEnv should be 0 at this point. If not, there's a bug. */
    System_printf("myCreate2: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Swi_setHookContext(swi, myHookSetId2, (Ptr)0xdead2);
}

/* ======== myReady2 ========
 * invoked when Swi is posted */
Void myReady2(Swi_Handle swi)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId2);

    System_printf("myReady2: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Swi_setHookContext(swi, myHookSetId2, (Ptr)0xbeef2);
}
```

```
/* ======== myBegin2 ========
 * invoked just before Swi func is run */
Void myBegin2(Swi_Handle swi)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId2);

    System_printf("myBegin2: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
    Swi_setHookContext(swi, myHookSetId2, (Ptr)0xfeeb2);
}

/* ======== myEnd2 ========
 * invoked after Swi func returns */
Void myEnd2(Swi_Handle swi)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId2);

    System_printf("myEnd2: pEnv = 0x%x, time = %d\n", pEnv,
Timestamp_get32());
    Swi_setHookContext(swi, myHookSetId2, (Ptr)0xc0de2);
}

/* ======== myDelete2 ========
 * invoked upon Swi deletion */
Void myDelete2(Swi_Handle swi)
{
    Ptr pEnv;

    pEnv = Swi_getHookContext(swi, myHookSetId2);

    System_printf("myDelete2: pEnv = 0x%x, time = %d\n", pEnv,
                  Timestamp_get32());
}

/* ======== mySwiFunc ======== */
Void mySwiFunc(UArg arg0, UArg arg1)
{
    System_printf("Entering mySwi.\n");
}
```

```
/* ======== myTaskFunc ======== */
Void myTaskFunc(UArg arg0, UArg arg1)
{
    System_printf("Entering myTask.\n");

    System_printf("Posting mySwi.\n");
    Swi_post(mySwi);

    System_printf("Deleting mySwi.\n");
    Swi_delete(&mySwi);

    System_printf("myTask exiting ...\n");
}

/* ======== myIdleFunc ======== */
Void myIdleFunc()
{
    System_printf("Entering myIdleFunc().\n");
    System_exit(0);
}

/* ======== main ======== */
Int main(Int argc, Char* argv[])
{
    System_printf("Starting SwiHookExample...\n");

    /* Create mySwi with default params
     * to exercise Swi Hook Functions    */
    mySwi = Swi_create(mySwiFunc, NULL, NULL);

    BIOS_start();
    return (0);
}
```

This is the XDCtools configuration script for the example:

```
/* pull in Timestamp to print time in hook functions */
xdc.useModule('xdc.runtime.Timestamp');

/* Disable Clock so that ours is the
 * only Swi in the application */
var BIOS = xdc.useModule('ti.sysbios.BIOS');
BIOS.clockEnabled = false;

var Idle = xdc.useModule('ti.sysbios.knl.Idle');
Idle.addFunc('&myIdleFunc');

/* Create myTask with default task params */
var Task = xdc.useModule('ti.sysbios.knl.Task');
var taskParams = new Task.Params();
Program.global.myTask = Task.create('&myTaskFunc', taskParams);

/* Define and add two Swi Hook Sets */
var Swi = xdc.useModule("ti.sysbios.knl.Swi");

/* Hook Set 1 */
Swi.addHookSet({
      registerFxn: '&myRegister1',
      createFxn: '&myCreate1',
      readyFxn: '&myReady1',
      beginFxn: '&myBegin1',
      endFxn: '&myEnd1',
      deleteFxn: '&myDelete1'
});

/* Hook Set 2 */
Swi.addHookSet({
      registerFxn: '&myRegister2',
      createFxn: '&myCreate2',
      readyFxn: '&myReady2',
      beginFxn: '&myBegin2',
      endFxn: '&myEnd2',
      deleteFxn: '&myDelete2'
});
```

This is the output for the application:

```
myRegister1: assigned hookSet Id = 0
myRegister2: assigned hookSet Id = 1
Starting SwiHookExample...
myCreate1: pEnv = 0x0, time = 315
myCreate2: pEnv = 0x0, time = 650
Entering myTask.
Posting mySwi.
myReady1: pEnv = 0xdead1, time = 1275
myReady2: pEnv = 0xdead2, time = 1678
myBegin1: pEnv = 0xbeef1, time = 2093
myBegin2: pEnv = 0xbeef2, time = 2496
Entering mySwi.
myEnd1: pEnv = 0xfeeb1, time = 3033
myEnd2: pEnv = 0xfeeb2, time = 3421
Deleting mySwi.
myDelete1: pEnv = 0xc0de1, time = 3957
myDelete2: pEnv = 0xc0de2, time = 4366
myTask exiting ...
Entering myIdleFunc().
```

2.5 Tasks

DSP/BIOS task objects are threads that are managed by the Task module. Tasks have higher priority than the Idle Loop and lower priority than hardware and software interrupts.

The Task module dynamically schedules and preempts tasks based on the task's priority level and the task's current execution state. This ensures that the processor is always given to the highest priority thread that is ready to run. There are up to 32 priority levels available for tasks, with the default number of levels being 16. The lowest priority level (0) is reserved for running the Idle Loop.

The Task module provides a set of functions that manipulate task objects. They access Task objects through handles of type Task_Handle.

The kernel maintains a copy of the processor registers for each task object. Each task has its own runtime stack for storing local variables as well as for further nesting of function calls.

Stack size can be specified separately for each Task object. Each stack must be large enough to handle normal function calls as well as a single task preemption context and two interrupting Hwi contexts. 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. If the task blocks, only those registers that a C function must save are saved to the task stack. To find the correct stack size, you can make the stack size large and then use Code Composer Studio software to find the stack size actually used.

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.

Communication between the target and the DSP/BIOS Analysis Tools is performed in a Real-Time Analysis (RTA) task. The priority of this task is configurable and defaults to "1", the lowest priority. This ensures that the DSP/BIOS Analysis Tools do not interfere with higher-priority processing.

2.5.1 Creating Tasks

You can create Task objects either dynamically with a call to Task_create() or statically in the configuration. Tasks that you create dynamically can also be deleted during program execution.

2.5.1.1 Creating and Deleting Tasks Dynamically

You can spawn DSP/BIOS tasks by calling the function Task_create(), whose parameters include the address of a C function in which the new task begins its execution. The value returned by Task_create() is a handle of type Task_Handle, which you can then pass as an argument to other Task functions.

```
Task_Handle Task_create(Task_FuncPtr  fxn,
                        Task_Params   *params,
                        Error_Block   *eb);
```

A task becomes active when it is created and preempts the currently running task if it has a higher priority.

The memory used by Task objects and stacks can be reclaimed by calling Task_delete(). Task_delete() removes the task from all internal queues and frees the task object and stack.

Any Semaphores or other resources held by the task are *not* released. Deleting a task that holds such resources is often an application design error, although not necessarily so. In most cases, such resources should be released prior to deleting the task. It is only safe to delete a Task that is either in the Terminated or Inactive State.

```
Void Task_delete(Task_Handle *task);
```

2.5.1.2 Creating Tasks Statically

You can also create tasks statically within a configuration script. The configuration allows you to set a number of properties for each task and for the Task Manager itself.

For a complete description of all Task properties, see the Task module in the "ti.sysbios.knl" package documentation in the online documentation. (For information on running online help, see Section 1.5.1, *Using the API Reference Help System*, page 1-7.)

While it is running, a task that was created statically behaves exactly the same as a task created with Task_create(). You cannot use the Task_delete() function to delete statically-created tasks. See the *XDCtools Consumer User's Guide* for a discussion of the benefits of creating objects statically.

The Task module automatically creates the Task_idle task and gives it the lowest task priority (0). It runs the functions defined for the Idle objects when no higher-priority Hwi, Swi, or Task is running.

When you configure tasks to have equal priority, they are scheduled in the order in which they are created in the configuration script. Tasks can have up to 32 priority levels with 16 being the default. The highest level is the number of priorities defined minus 1, and the lowest is 0. The priority level of 0 is reserved for the system idle task. You cannot sort tasks within a single priority level by setting the order property.

If you want a task to be initially inactive, set its priority to -1. Such tasks are not scheduled to run until their priority is raised at runtime.

2.5.2 Task Execution States and Scheduling

Each Task object is always in one of four possible states of execution:

❑ **Task_Mode_RUNNING**, which means the task is the one actually executing on the system's processor;

❑ **Task_Mode_READY,** which means the task is scheduled for execution subject to processor availability;

❑ **Task_Mode_BLOCKED,** which means the task cannot execute until a particular event occurs within the system; or

❑ **Task_Mode_TERMINATED,** which means the task is "terminated" and does not execute again.

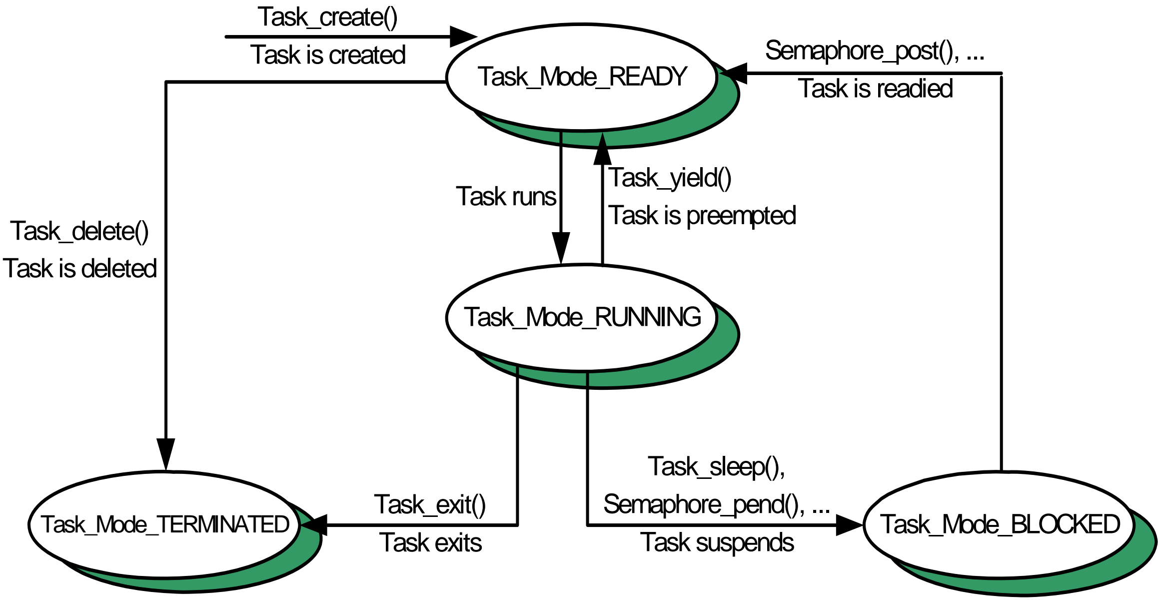
❑ **Task_Mode_INACTIVE,** which means the task was created with priority equal to -1 and is in a pre-Ready state.

Tasks are scheduled for execution according to a priority level assigned to the application. There can be no more than one running task. As a rule, no ready task has a priority level greater than that of the currently running task, since Task preempts the running task in favor of the higher-priority ready task. Unlike many time-sharing operating systems that give each task its "fair share" of the processor, DSP/BIOS *immediately* preempts the current task whenever a task of higher priority becomes ready to run.

The maximum priority level is Task_numPriorities-1 (default=15; maximum=31). The minimum priority is 1. If the priority is less than 0, the task is barred from further execution until its priority is raised at a later time by another task. If the priority equals Task_numPriorities-1, the task execution effectively locks out all other program activity except for the handling of Hwis and Swis.

During the course of a program, each task's mode of execution can change for a number of reasons. Figure 2-7 shows how execution modes change.

Figure 2-7. Execution Mode Variations



Functions in the Task, Semaphore, Event, and Mailbox modules alter the execution state of task objects: blocking or terminating the currently running task, readying a previously suspended task, re-scheduling the current task, and so forth.

There is *one* task whose execution mode is Task_Mode_RUNNING. If all program tasks are blocked and no Hwi or Swi is running, Task executes the Task_idle task, whose priority is lower than all other tasks in the system. When a task is preempted by a Hwi or Swi, the task execution mode returned for that task by Task_stat() is still Task_Mode_RUNNING because the task will run when the preemption ends.

Note:

Do not make blocking calls, such as Semaphore_pend() or Task_sleep(), from within an Idle function. Doing so causes the application to terminate.

When the Task_Mode_RUNNING task transitions to any of the other three states, control switches to the highest-priority task that is ready to run (that is, whose mode is Task_Mode_READY). A Task_Mode_RUNNING task transitions to one of the other modes in the following ways:

- The running task becomes Task_Mode_TERMINATED by calling Task_exit(), which is automatically called if and when a task returns from

its top-level function. After all tasks have returned, the Task Manager terminates program execution by calling System_exit() with a status code of 0.

- The running task becomes Task_Mode_BLOCKED when it calls a function (for example, Semaphore_pend() or Task_sleep()) that causes the current task to suspend its execution; tasks can move into this state when they are performing certain I/O operations, awaiting availability of some shared resource, or idling.
- The running task becomes Task_Mode_READY and is preempted whenever some other, higher-priority task becomes ready to run. Task_setpri() can cause this type of transition if the priority of the current task is no longer the highest in the system. A task can also use Task_yield() to yield to other tasks with the same priority. A task that yields becomes ready to run.

A task that is currently Task_Mode_BLOCKED transitions to the ready state in response to a particular event: completion of an I/O operation, availability of a shared resource, the elapse of a specified period of time, and so forth. By virtue of becoming Task_Mode_READY, this task is scheduled for execution according to its priority level; and, of course, this task immediately transitions to the running state if its priority is higher than the currently executing task. Task schedules tasks of equal priority on a first-come, first-served basis.

2.5.3 Testing for Stack Overflow

When a task uses more memory than its stack has been allocated, it can write into an area of memory used by another task or data. This results in unpredictable and potentially fatal consequences. Therefore, a means of checking for stack overflow is useful.

Two functions, Task_checkstacks(), and Task_stat(), can be used to watch stack size. The structure returned by Task_stat() contains both the size of its stack and the maximum number of MADUs ever used on its stack, so this code segment could be used to warn of a nearly full stack:

```
Task_Stat statbuf;              /* declare buffer */

Task_stat(Task_self(), &statbuf); /* call func to get status */
if (statbuf.used > (statbuf.stacksize * 9 / 10)) {
   Log_printf(&trace, "Over 90% of task's stack is in use.\n")
}
```

See the Task_stat() and Task_checkstacks() information in the "ti.sysbios.knl" package documentation in the online documentation.

2.5.4 Task Hooks

The Task module supports the following set of Hook functions:

- **Register.** A function called before any statically created Tasks are initialized at runtime. The register hook is called at boot time before main() and before interrupts are enabled.
- **Create.** A function called when a Task is created. This includes Tasks that are created statically and those created dynamically using Task_create() or Task_construct(). The Create hook is called outside of a Task_disable/enable block and before the task has been added to the ready list.
- **Ready.** A function called when a Task becomes ready to run. The ready hook is called from within a Task_disable/enable block with interrupts enabled.
- **Switch.** A function called just before a task switch occurs. The 'prev' and 'next' task handles are passed to the Switch hook. 'prev' is set to NULL for the initial task switch that occurs during DSP/BIOS startup. The Switch hook is called from within a Task_disable/enable block with interrupts enabled.
- **Exit.** A function called when a task exits using Task_exit(). The exit hook is passed the handle of the exiting task. The exit hook is called outside of a Task_disable/enable block and before the task has been removed from the kernel lists.
- **Delete.** A function called when a task is deleted at runtime with Task_delete().

The following HookSet structure type definition encapsulates the hook functions supported by the Task module:

```
typedef struct Task_HookSet {
    Void (*registerFxn)(Int);                /* Register Hook */
    Void (*createFxn)(Handle, Error.Block *); /* Create Hook */
    Void (*readyFxn)(Handle);                 /* Ready Hook */
    Void (*switchFxn)(Handle, Handle);        /* Switch Hook */
    Void (*exitFxn)(Handle);                  /* Exit Hook */
    Void (*deleteFxn)(Handle);                /* Delete Hook */
};
```

When more than one hook set is defined, the individual hook functions of a common type are invoked in hook ID order.

Task hook functions can only be configured statically.

2.5.4.1 Register Function

The Register function is provided to allow a hook set to store its corresponding hook ID. This ID can be passed to Task_setHookContext() and Task_getHookContext() to set or get hook-specific context. The Register function must be specified if the hook implementation needs to use Task_setHookContext() or Task_getHookContext().

The registerFxn function is called during system initialization before interrupts have been enabled.

The Register function has the following signature:

```
Void registerFxn(Int id);
```

2.5.4.2 Create and Delete Functions

The Create and Delete functions are called whenever a Task is created or deleted. The Create function is passed an Error_Block which is to be passed to Memory_alloc() for applications that require additional context storage space.

The createFxn and deleteFxn functions are called with interrupts enabled (unless called at boot time or from main()).

These functions have the following signatures.

```
Void createFxn(Task_Handle task, Error_Block *eb);
Void deleteFxn(Task_Handle task);
```

2.5.4.3 Switch Function

If a switch function is specified, it is invoked just before the new task is switched to. The switch function is called with interrupts enabled.

This function can be used for purposes such as saving/restoring additional task context (for example, external hardware registers), checking for task stack overflow, and monitoring the time used by each task.

The switchFxn has the following signature:

```
Void switchFxn(Task_Handle prev, Task_Handle next);
```

2.5.4.4 Ready Function

If a Ready Function is specified, it is invoked whenever a task is made ready to run. The Ready Function is called with interrupts enabled (unless called at boot time or from main()).

The readyFxn has the following signature:

```
Void readyFxn(Task_Handle task);
```

2.5.4.5 Exit Function

If an Exit Function is specified, it is invoked when a task exits (via call to Task_exit() or when a task returns from its' main function). The exitFxn is called with interrupts enabled.

The exitFxn has the following signature:

```
Void exitFxn(Task_Handle task);
```

2.5.4.6 Task Hooks Example

The following example application uses a single Task hook set. This example demonstrates how to read and write the Hook Context Pointer associated with each hook set.

The XDCtools configuration script and program output are shown after the C code listing.

This is the C code for the example:

```
/* ======== TaskHookExample.c ========
 * This example demonstrates basic task hook processing
 * operation for dynamically created tasks. */

#include <xdc/std.h>
#include <xdc/runtime/Error.h>
#include <xdc/runtime/Memory.h>
#include <xdc/runtime/System.h>
#include <xdc/runtime/Types.h>

#include <ti/sysbios/BIOS.h>
#include <ti/sysbios/knl/Task.h>

Task_Handle myTsk0, myTsk1, myTsk2;
Int myHookSetId, myHookSetId2;

/* HookSet functions */

/* ======== myRegister ========
 * invoked during Swi module startup before main()
 * for each HookSet */
Void myRegister(Int hookSetId)
{
    System_printf("myRegister: assigned HookSet Id = %d\n",
                  hookSetId);
    myHookSetId = hookSetId;
}
```

```
/* ======== myCreate ========
 * invoked during Task_create for dynamically
 * created Tasks */
Void myCreate(Task_Handle task, Error_Block *eb)
{
    String name;
    Ptr pEnv;

    name = Task_Handle_name(task);
    pEnv = Task_getHookContext(task, myHookSetId);

    System_printf("myCreate: task name = '%s', pEnv = 0x%x\n",
                  name, pEnv);
    Task_setHookContext(task, myHookSetId, (Ptr)0xdead);
}

/* ======== myReady ========
 * invoked when Task is made ready to run */
Void myReady(Task_Handle task)
{
    String name;
    Ptr pEnv;

    name = Task_Handle_name(task);
    pEnv = Task_getHookContext(task, myHookSetId);

    System_printf("myReady: task name = '%s', pEnv = 0x%x\n",
                  name, pEnv);
    Task_setHookContext(task, myHookSetId, (Ptr)0xc0de);
}

/* ======== mySwitch ========
 * invoked whenever a Task switch occurs/is made ready to run */
Void mySwitch(Task_Handle prev, Task_Handle next)
{
    String prevName;
    String nextName;
    Ptr pPrevEnv;
    Ptr pNextEnv;

    if (prev == NULL) {
     System_printf("mySwitch: ignoring dummy 1st prev Task\n");
    }
```

```
    else {
       prevName = Task_Handle_name(prev);
       pPrevEnv = Task_getHookContext(prev, myHookSetId);

       System_printf("mySwitch: prev name = '%s',
                     pPrevEnv = 0x%x\n", prevName, pPrevEnv);
      Task_setHookContext(prev, myHookSetId, (Ptr)0xcafec0de);
    }
    nextName = Task_Handle_name(next);
    pNextEnv = Task_getHookContext(next, myHookSetId);

   System_printf("        next name = '%s', pNextEnv = 0x%x\n",
                 nextName, pNextEnv);
    Task_setHookContext(next, myHookSetId, (Ptr)0xc001c0de);
}

/* ======== myExit ========
 * invoked whenever a Task calls Task_exit() or falls through
 * the bottom of its task function. */
Void myExit(Task_Handle task)
{
    Task_Handle curTask = task;
    String name;
    Ptr pEnv;

    name = Task_Handle_name(curTask);
    pEnv = Task_getHookContext(curTask, myHookSetId);

   System_printf("myExit: curTask name = '%s', pEnv = 0x%x\n",
                 name, pEnv);
   Task_setHookContext(curTask, myHookSetId, (Ptr)0xdeadbeef);
}

/* ======== myDelete ========
 * invoked upon Task deletion */
Void myDelete(Task_Handle task)
{
    String name;
    Ptr pEnv;

    name = Task_Handle_name(task);
    pEnv = Task_getHookContext(task, myHookSetId);

   System_printf("myDelete: task name = '%s', pEnv = 0x%x\n",
                 name, pEnv);
}
```

```
/* Define 3 identical tasks */
Void myTsk0Func(UArg arg0, UArg arg1)
{
    System_printf("myTsk0 Entering\n");
    System_printf("myTsk0 Calling Task_yield\n");
    Task_yield();
    System_printf("myTsk0 Exiting\n");
}

Void myTsk1Func(UArg arg0, UArg arg1)
{
    System_printf("myTsk1 Entering\n");
    System_printf("myTsk1 Calling Task_yield\n");
    Task_yield();
    System_printf("myTsk1 Exiting\n");
}

Void myTsk2Func(UArg arg0, UArg arg1)
{
    System_printf("myTsk2 Entering\n");
    System_printf("myTsk2 Calling Task_yield\n");
    Task_yield();
    System_printf("myTsk2 Exiting\n");
}

/* ======== main ======== */
Int main(Int argc, Char* argv[])
{
    Task_Params params;
    Task_Params_init(&params);

    params.instance->name = "myTsk0";
    myTsk0 = Task_create(myTsk0Func, &params, NULL);

    params.instance->name = "myTsk1";
    myTsk1 = Task_create(myTsk1Func, &params, NULL);

    params.instance->name = "myTsk2";
    myTsk2 = Task_create(myTsk2Func, &params, NULL);

    BIOS_start();
    return (0);
}
```

```
/* ======== myIdleFunc ======== */
Void myIdleFunc()
{
    System_printf("Entering idleFunc().\n");

    Task_delete(&myTsk0);
    Task_delete(&myTsk1);
    Task_delete(&myTsk2);

    System_exit(0);
}
```

The XDCtools configuration script is as follows:

```
/* Lots of System_printf() output requires a bigger bufSize */
SysMin = xdc.useModule('xdc.runtime.SysMin');
SysMin.bufSize = 4096;

var Idle = xdc.useModule('ti.sysbios.knl.Idle');
Idle.addFunc('&myIdleFunc');

var Task = xdc.useModule('ti.sysbios.knl.Task');

/* Enable instance names */
Task.common$.namedInstance = true;

/* Define and add one Task Hook Set */
Task.addHookSet({
    registerFxn: '&myRegister',
    createFxn: '&myCreate',
    readyFxn: '&myReady',
    switchFxn: '&mySwitch',
    exitFxn: '&myExit',
    deleteFxn: '&myDelete',
});
```

The program output is as follows:

```
myRegister: assigned HookSet Id = 0
myCreate: task name = 'ti.sysbios.knl.Task.IdleTask', pEnv = 0x0
myReady: task name = 'ti.sysbios.knl.Task.IdleTask', pEnv =
0xdead
myCreate: task name = 'myTsk0', pEnv = 0x0
myReady: task name = 'myTsk0', pEnv = 0xdead
myCreate: task name = 'myTsk1', pEnv = 0x0
myReady: task name = 'myTsk1', pEnv = 0xdead
myCreate: task name = 'myTsk2', pEnv = 0x0
myReady: task name = 'myTsk2', pEnv = 0xdead
mySwitch: ignoring dummy 1st prev Task
          next name = 'myTsk0', pNextEnv = 0xc0de
myTsk0 Entering
myTsk0 Calling Task_yield
mySwitch: prev name = 'myTsk0', pPrevEnv = 0xc001c0de
          next name = 'myTsk1', pNextEnv = 0xc0de
myTsk1 Entering
myTsk1 Calling Task_yield
mySwitch: prev name = 'myTsk1', pPrevEnv = 0xc001c0de
          next name = 'myTsk2', pNextEnv = 0xc0de
myTsk2 Entering
myTsk2 Calling Task_yield
mySwitch: prev name = 'myTsk2', pPrevEnv = 0xc001c0de
          next name = 'myTsk0', pNextEnv = 0xcafec0de
myTsk0 Exiting
myExit: curTask name = 'myTsk0', pEnv = 0xc001c0de
mySwitch: prev name = 'myTsk0', pPrevEnv = 0xdeadbeef
          next name = 'myTsk1', pNextEnv = 0xcafec0de
myTsk1 Exiting
myExit: curTask name = 'myTsk1', pEnv = 0xc001c0de
mySwitch: prev name = 'myTsk1', pPrevEnv = 0xdeadbeef
          next name = 'myTsk2', pNextEnv = 0xcafec0de
myTsk2 Exiting
myExit: curTask name = 'myTsk2', pEnv = 0xc001c0de
mySwitch: prev name = 'myTsk2', pPrevEnv = 0xdeadbeef
          next name = 'ti.sysbios.knl.Task.IdleTask', pNextEnv
= 0xc0de
Entering idleFunc().
myDelete: task name = 'myTsk0', pEnv = 0xcafec0de
myDelete: task name = 'myTsk1', pEnv = 0xcafec0de
myDelete: task name = 'myTsk2', pEnv = 0xcafec0de
```

2.5.5 Task Yielding for Time-Slice Scheduling

Example 2-1 demonstrates a time-slicing scheduling model that can be managed by a user. This model is preemptive and does not require any cooperation (that is, code) by the tasks. The tasks are programmed as if they were the only thread running. Although DSP/BIOS tasks of differing priorities can exist in any given application, the time-slicing model only applies to tasks of equal priority.

In this example, a periodic Clock object is configured to run a simple function that calls the Task_yield() function every 4 clock ticks. Another periodic Clock object is to run a simple function that calls the Semaphore_post() function every 16 milliseconds.

The output of the example code is shown after the code.

Example 2-1. Time-Slice Scheduling

```
/*
 * ======== slice.c ========
 * This example utilizes time-slice scheduling among three
 * tasks of equal priority. A fourth task of higher
 * priority periodically preempts execution.
 *
 * A periodic Clock object drives the time-slice scheduling.
 * Every 4 milliseconds, the Clock object calls Task_yield()
 * which forces the current task to relinquish access to
 * to the CPU.
 *
 * Because a task is always ready to run, this program
 * does not spend time in the idle loop. Calls to Idle_run()
 * are added to give time to the Idle loop functions
 * occasionally. The call to Idle_run() is within a
 * Task_disable(), Task_restore() block because the call
 * to Idle_run() is not reentrant.
 */
```

```
#include <xdc/std.h>
#include <xdc/runtime/System.h>

#include <ti/sysbios/BIOS.h>
#include <ti/sysbios/ipc/Semaphore.h>
#include <ti/sysbios/knl/Clock.h>
#include <ti/sysbios/knl/Clock.h>
#include <ti/sysbios/knl/Idle.h>
#include <ti/sysbios/knl/Task.h>

#include <xdc/cfg/global.h>

Void hiPriTask(UArg arg0, UArg arg1);
Void task(UArg arg0, UArg arg1);
Void clockHandler1(UArg arg);
Void clockHandler2(UArg arg);
Semaphore_Handle sem;

/* ======== main ======== */
Void main()
{
    Task_Params taskParams;
    Clock_Params clockParams;
    UInt i;

    System_printf("Slice example started!\n");

    /* Create 1 task with priority 15 */
    Task_Params_init(&taskParams);
    taskParams.stackSize = 512;
    taskParams.priority = 15;
    Task_create((Task_FuncPtr)hiPriTask, &taskParams, NULL);

    /* Create 3 tasks with priority 1 */
    /* re-uses taskParams */
    taskParams.priority = 1;
    for (i = 0; i < 3; i++) {
        taskParams.arg0 = i;
        Task_create((Task_FuncPtr)task, &taskParams, NULL);
    }
```

```
    /*
     * Create clock that calls Task_yield() every
     * 4 Clock ticks
     */
    Clock_Params_init(&clockParams);
    clockParams.period = 4;/* every 4 Clock ticks */
    clockParams.startFlag = TRUE;/* start immediately */
    Clock_create((Clock_FuncPtr)clockHandler1, 4, &clockParams,
                 NULL);

    /*
     * Create clock that calls Semaphore_post() every
     * 16 Clock ticks
     */
    clockParams.period = 16;/* every 16 Clock ticks */
    clockParams.startFlag = TRUE;/* start immediately */
    Clock_create((Clock_FuncPtr)clockHandler2, 16,
                 &clockParams, NULL);

    /*
     * Create semaphore with
     * initial count = 0
     * and default params
     */
    sem = Semaphore_create(0, NULL, NULL);

    /* Start DSP/BIOS */
    BIOS_start();
}

/* ======== clockHandler1 ======== */
Void clockHandler1(UArg arg)
{
    /* Call Task_yield every 4 ms */
    Task_yield();
}

/* ======== clockHandler2 ======== */
Void clockHandler2(UArg arg)
{
    /* Call Semaphore_post every 16 ms */
    Semaphore_post(sem);
}
```

```
/* ======== task ======== */
Void task(UArg arg0, UArg arg1)
{
    Int time;
    Int prevtime = -1;
    UInt taskKey;

    /* While loop simulates work load of time-sharing tasks */
    while (1) {
        time = Clock_getTicks();

        /* print time once per clock tick */
        if (time >= prevtime + 1) {
            prevtime = time;
            System_printf("Task %d: time is %d\n",
               (Int)arg0, time);
        }

        /* check for rollover */
        if (prevtime > time) {
            prevtime = time;
        }

        /* Process the Idle Loop functions */
        taskKey = Task_disable();
        Idle_run();
        Task_restore(taskKey);
    }
}

/* ======== hiPriTask ======== */
Void hiPriTask(UArg arg0, UArg arg1)
{
    static Int numTimes = 0;

    while (1) {
        System_printf("hiPriTask here\n");
        if (++numTimes < 3) {
            Semaphore_pend(sem, BIOS_WAIT_FOREVER);
        }
        else {
            System_printf("Slice example ending.\n");
            System_exit(0);
        }
    }
}
```

The System_printf() output for this example is as follows:

```
Slice example started!
hiPriTask here
Task 0: time is 0
Task 0: time is 1
Task 0: time is 2
Task 0: time is 3
Task 1: time is 4
Task 1: time is 5
Task 1: time is 6
Task 1: time is 7
Task 2: time is 8
Task 2: time is 9
Task 2: time is 10
Task 2: time is 11
Task 0: time is 12
Task 0: time is 13
Task 0: time is 14
Task 0: time is 15
hiPriTask here
Task 1: time is 16
Task 1: time is 17
Task 1: time is 18
Task 1: time is 19
Task 2: time is 20
Task 2: time is 21
Task 2: time is 22
Task 2: time is 23
Task 0: time is 24
Task 0: time is 25
Task 0: time is 26
Task 0: time is 27
Task 1: time is 28
Task 1: time is 29
Task 1: time is 30
Task 1: time is 31
hiPriTask here
Slice example ending.
```

2.6 The Idle Loop

The Idle Loop is the background thread of DSP/BIOS, which runs continuously when no Hwi, Swi, or Task is running. Any other thread can preempt the Idle Loop at any point.

The Idle Manager allows you to insert functions that execute within the Idle Loop. The Idle Loop runs the Idle functions you configured. Idle_loop calls the functions associated with each one of the Idle objects one at a time, and then starts over again in a continuous loop. The functions are called in the same order in which they were created. Therefore, an Idle function must run to completion before the next Idle function can start running. When the last idle function has completed, the Idle Loop starts the first Idle function again. Idle Loop functions are often used to poll non-real-time devices that do not (or cannot) generate interrupts, monitor system status, or perform other background activities.

The Idle Loop is the thread with lowest priority in a DSP/BIOS application. The Idle Loop functions run only when no Hwis, Swis, or Tasks need to run.

The CPU load and thread load are computed in an Idle loop function. (Data transfer for between the target and the host is handled by a low-priority task.)

2.7 Example Using Hwi, Swi, and Task Threads

This example depicts a stylized version of the DSP/BIOS Clock module design. It uses a combination of Hwi, Swi, and Task threads.

A periodic timer interrupt posts a Swi that processes the Clock object list. Each entry in the Clock object list has its own period and Clock function. When an object's period has expired, the Clock function is invoked and the period restarted.

Since there is no limit to the number of Clock objects that can be placed in the list and no way to determine the overhead of each Clock function, the length of time spent servicing all the Clock objects is non-deterministic. As such, servicing the Clock objects in the timer's Hwi thread is impractical. Using a Swi for this function is a relatively (as compared with using a Task) lightweight solution to this problem.

The XDCtools configuration script and program output are shown after the C code listing. This is the C code for the example:

```
/*
 * ======== HwiSwiTaskExample.c ========
 */

#include <xdc/std.h>
#include <xdc/runtime/System.h>

#include <ti/sysbios/BIOS.h>
#include <ti/sysbios/hal/Timer.h>
#include <ti/sysbios/ipc/Semaphore.h>
#include <ti/sysbios/knl/Swi.h>
#include <ti/sysbios/knl/Task.h>
#include <ti/sdo/utils/List.h>

#include <xdc/cfg/global.h>

typedef struct {
    List_Elem elem;
    UInt32 timeout;
    UInt32 period;
    Void (*fxn)(UArg);
    UArg arg;
} Clock_Object;
```

```
Clock_Object clk1, clk2;
Timer_Handle timer;
Semaphore_Handle sem;
Swi_Handle swi;
Task_Handle task;
List_Handle clockList;

/* Here on Timer interrupt */
Void hwiFxn(UArg arg)
{
    Swi_post(swi);
}

/* Swi thread to handle Timer interrupt */
Void swiFxn(UArg arg1, UArg arg2)
{
    List_Elem *elem;
    Clock_Object *obj;

    /* point to first clock object in the clockList */
    elem = List_next(clockList, NULL);

    /* service all the Clock Objects in the clockList */
    while (elem != NULL) {
        obj = (Clock_Object *)elem;

        /* decrement the timeout counter */
        obj->timeout -= 1;

        /* if period has expired, refresh the timeout
         * value and invoke the clock func */
        if (obj->timeout == 0) {
            obj->timeout = obj->period;
            (obj->fxn)(obj->arg);
        }

        /* advance to next clock object in clockList */
        elem = List_next(clockList, elem);
    }
}
```

```
/* Task thread pends on Semaphore posted by Clock thread */
Void taskFxn(UArg arg1, UArg arg2)
{
    System_printf("In taskFxn pending on Sempahore.\n");
    Semaphore_pend(sem, BIOS_WAIT_FOREVER);
    System_printf("In taskFxn returned from Sempahore.\n");
    System_exit(0);
}

/* First Clock function, invoked every 5 timer interrupts */
Void clk1Fxn(UArg arg)
{
    System_printf("In clk1Fxn, arg = %d.\n", arg);
    clk1.arg++;
}

/* Second Clock function, invoked every 20 timer interrupts */
Void clk2Fxn(UArg sem)
{
    System_printf("In clk2Fxn, posting Semaphore.\n");
    Semaphore_post((Semaphore_Object *)sem);
}

/* main() */
Int main(Int argc, char* argv[])
{
    Timer_Params timerParams;
    Task_Params taskParams;

    System_printf("Starting HwiSwiTask example.\n");

    Timer_Params_init(&timerParams);
    Task_Params_init(&taskParams);

    /* Create a Swi with default priority (15).
     * Swi handler is 'swiFxn' which runs as a Swi thread. */
    swi = Swi_create(swiFxn, NULL, NULL);

    /* Create a Task with priority 3.
    * Task function is 'taskFxn' which runs as a Task thread. */
    taskParams.priority = 3;
    task = Task_create(taskFxn, &taskParams, NULL);

    /* Create a binary Semaphore for example task to pend on */
    sem = Semaphore_create(0, NULL, NULL);
```

```
    /* Create a List to hold the Clock Objects on */
    clockList = List_create(NULL, NULL);

    /* setup clk1 to go off every 5 timer interrupts. */
    clk1.fxn = clk1Fxn;
    clk1.period = 5;
    clk1.timeout = 5;
    clk1.arg = 1;
    /* add the Clock object to the clockList */
    List_put(clockList, &clk1.elem);

    /* setup clk2 to go off every 20 timer interrupts. */
    clk2.fxn = clk2Fxn;
    clk2.period = 20;
    clk2.timeout = 20;
    clk2.arg = (UArg)sem;
    /* add the Clock object to the clockList */
    List_put(clockList, &clk2.elem);

    /* Configure a periodic interrupt using any available Timer
     * with a 1000 microsecond (1ms) interrupt period.
     *
     * The Timer interrupt will be handled by 'hwiFxn' which
     * will run as a Hwi thread.
     */
    timerParams.period = 1000;
   timer = Timer_create(Timer_ANY, hwiFxn, &timerParams, NULL);

    BIOS_start();

    return(0);
}
```

The XDCtools configuration script is as follows:

```
/*
 * ======== HwiSwiTaskExample.cfg ========
 */

/* Configure System to use SysMin */
System = xdc.useModule('xdc.runtime.System');
System.SupportProxy = xdc.useModule('xdc.runtime.SysMin')

/* Use HeapMem for default heap manager and give it 8192
 * bytes to work with */
var Memory = xdc.useModule('xdc.runtime.Memory');
var HeapMem = xdc.useModule('ti.sysbios.heaps.HeapMem');

var heapParams = new HeapMem.Params;
heapParams.size = 8192;

Memory.defaultHeapInstance = HeapMem.create(heapParams);

/* Pull in Timer, Semaphore, Swi, Task, and List modules
 * used in this example. */
xdc.useModule('ti.sysbios.hal.Timer');
xdc.useModule('ti.sysbios.ipc.Semaphore');
xdc.useModule('ti.sysbios.knl.Swi');
xdc.useModule('ti.sysbios.knl.Task');
xdc.useModule('ti.sdo.utils.List');
```

The program output is as follows:

```
Starting HwiSwiTask example.
In taskFxn pending on Semaphore.
In clk1Fxn, arg = 1.
In clk1Fxn, arg = 2.
In clk1Fxn, arg = 3.
In clk1Fxn, arg = 4.
In clk2Fxn, posting Semaphore.
In taskFxn returned from Semaphore
```

Chapter 3

Synchronization Modules

This chapter describes modules that can be used to synchronize access to shared resources.

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3.1 Semaphores

DSP/BIOS provides a fundamental set of functions for inter-task synchronization and communication based upon *semaphores*. Semaphores are often used to coordinate access to a shared resource among a set of competing tasks. The Semaphore module provides functions that manipulate semaphore objects accessed through handles of type Semaphore_Handle.

Semaphore objects can be declared as either counting or binary semaphores. They can be used for task synchronization and mutual exclusion. The same APIs are used for both counting and binary semaphores.

Binary semaphores are either available or unavailable. Their value cannot be incremented beyond 1. Thus, they should be used for coordinating access to a shared resource by a maximum of two tasks. Binary semaphores provide better performance than counting semaphores.

Counting semaphores keep an internal count of the number of corresponding resources available. When count is greater than 0, tasks do not block when acquiring a semaphore. The maximum count value for a semaphores plus one is the number of tasks a counting semaphore can coordinate.

To configure the type of semaphore, use the following configuration parameter:

```
config Mode mode = Mode_COUNTING;
```

The functions Semaphore_create() and Semaphore_delete() are used to create and delete semaphore objects, respectively, as shown in Example 3-1. You can also create semaphore objects statically. See the *XDCtools Consumer User's Guide* for a discussion of the benefits of creating objects statically.

Example 3-1. Creating and Deleting a Semaphore

```
Semaphore_Handle Semaphore_create(Uns              count,
                                  Semaphore_Params  *attrs);

Void Semaphore_delete(Semaphore_Handle *sem);
```

The semaphore count is initialized to count when it is created. In general, count is set to the number of resources that the semaphore is synchronizing.

Semaphore_pend() waits for a semaphore. If the semaphore count is greater than 0, Semaphore_pend() simply decrements the count and returns. Otherwise, Semaphore_pend() waits for the semaphore to be posted by Semaphore_post().

The timeout parameter to Semaphore_pend(), as shown in Example 3-2, allows the task to wait until a timeout, to wait indefinitely (BIOS_WAIT_FOREVER), or to not wait at all (BIOS_NO_WAIT). Semaphore_pend()'s return value is used to indicate if the semaphore was acquired successfully.

Example 3-2. Setting a Timeout with Semaphore_pend()

```
Bool Semaphore_pend(Semaphore_Handle  sem,
                    UInt              timeout);
```

Example 3-3 shows Semaphore_post(), which is used to signal a semaphore. If a task is waiting for the semaphore, Semaphore_post() removes the task from the semaphore queue and puts it on the ready queue. If no tasks are waiting, Semaphore_post() simply increments the semaphore count and returns.

Example 3-3. Signaling a Semaphore with Semaphore_post()

```
Void Semaphore_post(Semaphore_Handle sem);
```

3.1.1 Semaphore Example

Example 3-4 provides sample code for three writer tasks that create unique messages and place them on a list for one reader task. The writer tasks call Semaphore_post() to indicate that another message is available on the list. The reader task calls Semaphore_pend() to wait for messages. Semaphore_pend() returns only when a message is available on the list. The reader task prints the message using the System_printf() function.

The three writer tasks, a reader task, a semaphore, and a list in this example program were created statically as follows:

```
Program.system = xdc.useModule('xdc.runtime.SysMin');

var Sem = xdc.useModule('ti.sysbios.ipc.Semaphore');
Program.global.sem = Sem.create(0);
Program.global.sem.mode = Sem.Mode_COUNTING;

var Task = xdc.useModule('ti.sysbios.knl.Task');
Task.idleTaskVitalTaskFlag = false;
var reader = Task.create('&reader');
reader.priority = 5;

var writer0 = Task.create('&writer');
writer0.priority = 3;
writer0.arg0 = 0;
```

```
var writer1 = Task.create('&writer');
writer1.priority = 3;
writer1.arg0 = 1;

var writer2 = Task.create('&writer');
writer2.priority = 3;
writer2.arg0 = 2;

var List = xdc.useModule('ti.sdo.utils.List');
Program.global.msgList = List.create();
Program.global.freeList = List.create();
```

Since this program employs multiple tasks, a counting semaphore is used to synchronize access to the list. Figure 3-1 provides a view of the results from Example 3-3. Though the three writer tasks are scheduled first, the messages are read as soon as they have been put on the list because the reader's task priority is higher than that of the writer.

Example 3-4. Semaphore Example Using Three Writer Tasks

```
/* ======== semtest.c ======== */
#include <xdc/std.h>
#include <xdc/runtime/Memory.h>
#include <xdc/runtime/System.h>
#include <ti/sysbios/BIOS.h>
#include <ti/sdo/utils/List.h>
#include <ti/sysbios/ipc/Semaphore.h>
#include <ti/sysbios/knl/Task.h>

#define NUMMSGS 3     /* number of messages */
#define NUMWRITERS 3 /* number of writer tasks created with */

/* Config Tool */
typedef struct MsgObj {
    List_Elem elem;     /* first field for List */
    Int id;             /* writer task id */
    Char val;           /* message value */
} MsgObj, *Msg;

Void reader();
Void writer();

/* The following objects are created statically. */
extern Semaphore_Handle sem;
extern List_Handle msgList;
extern List_Handle freeList;
```

```
/* ======== main ======== */
Int main(Int argc, Char* argv[])
{
    Int i;
    MsgObj *msg;

   msg = (MsgObj *) Memory_alloc(NULL, NUMMSGS * sizeof(MsgObj),
                         0, NULL);

    /* Put all messages on freeList */
    for (i = 0; i < NUMMSGS; msg++, i++) {
        List_put(freeList, (List_Elem *) msg);
    }
    BIOS_start();
    System_exit(0);
    return(0);
}

/* ======== reader ======== */
Void reader()
{
    Msg msg;
    Int i;
    for (i = 0; i < NUMMSGS * NUMWRITERS; i++) {
        /* Wait for semaphore to be posted by writer(). */
        Semaphore_pend(sem, BIOS_WAIT_FOREVER);

        /* get message */
        msg = List_get(msgList);
        /* print value */
        System_printf("read '%c' from (%d).\n", msg->val,
        msg->id);
        /* free msg */
        List_put(freeList, (List_Elem *) msg);
    }
    System_printf("reader done.\n");
}
```

```
/* ======== writer ======== */
Void writer(Int id)
{
    Msg msg;
    Int i;

    for (i = 0; i < NUMMSGS; i++) {
        /* Get msg from the free list. Since reader is higher
         * priority and only blocks on sem, list is never
         * empty. */
        msg = List_get(freeList);

        /* fill in value */
        msg->id = id;
        msg->val = (i & 0xf) + 'a';
       System_printf("(%d) writing '%c' ...\n", id, msg->val);

        /* put message */
        List_put(msgList, (List_Elem *) msg);

        /* post semaphore */
        Semaphore_post(sem);
    }

    System_printf("writer (%d) done.\n", id);
}
```

Figure 3-1. Trace Window Results from Example 3-4

```
(0) writing 'a' ...
read 'a' from (0).
(0) writing 'b' ...
read 'b' from (0).
(0) writing 'c' ...
read 'c' from (0).
writer (0) done.
(1) writing 'a' ...
read 'a' from (1).
(1) writing 'b' ...
read 'b' from (1).
(1) writing 'c' ...
read 'c' from (1).
writer (1) done.
(2) writing 'a' ...
read 'a' from (2).
(2) writing 'b' ...
read 'b' from (2).
(2) writing 'c' ...
read 'c' from (2).
reader done.
writer (2) done.
```

3.2 Event Module

Events provide a means for communicating between and synchronizing threads. They are similar to Semaphores (see Section 3.1), except that they allow you to specify multiple conditions ("events") that must occur before the waiting thread returns.

An Event instance is used with calls to "pend" and "post", just as for a Semaphore. However, calls to Event_pend() additionally specify which events to wait for, and calls to Event_post() specify which events are being posted.

Note: Only a single Task can pend on an Event object at a time.

A single Event instance can manage up to 32 events, each represented by an event ID. Event IDs are simply bit masks that correspond to a unique event managed by the Event object.

Each Event behaves like a binary semaphore.

A call to Event_pend() takes an "andMask" and an "orMask". The andMask consists of the event IDs of all the events that must occur, and the orMask consists of the event IDs of any events of which only one must occur.

As with Semaphores, a call to Event_pend() takes a timeout value and returns 0 if the call times out. If a call to Event_pend() is successful, it returns a mask of the "consumed" events—that is, the events that occurred to satisfy the call to Event_pend(). The task is then responsible for handling ALL of the consumed events.

Only Tasks can call Event_pend(), whereas Hwis, Swis, and other Tasks can all call Event_post().

The Event_pend() prototype is as follows:

```
UInt Event_pend(Event_Handle event,
                UInt         andMask,
                UInt         orMask,
                UInt         timeout);
```

The Event_post() prototype is as follows:

```
Void Event_post(Event_Handle event,
                UInt         eventIds);
```

Configuration example: These XDCtools configuration statements create an event statically. The Event object has an Event_Handle named "myEvent".

```
var Event = xdc.useModule("ti.sysbios.ipc.Event");
Program.global.myEvent = Event.create();
```

Runtime example: The following C code creates an Event object with an Event_Handle named "myEvent".

```
Event_Handle myEvent;

/* Default instance configuration params and NULL Error Block */
myEvent = Event_create(NULL, NULL);
```

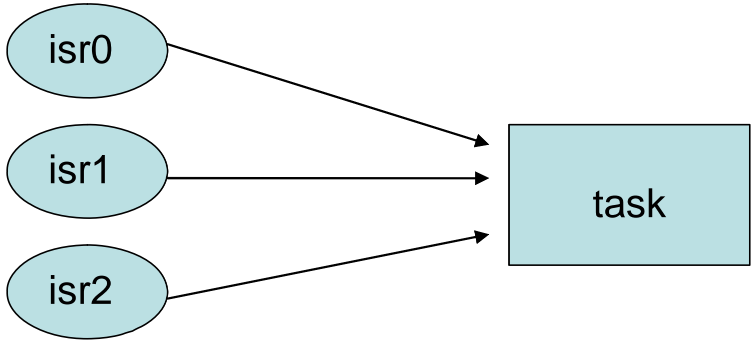
Runtime example: The following C code blocks on an event. It wakes the task only when both events 0 and 6 have occurred. It sets the andMask to enable both Event_Id_00 and Event_Id_06. It sets the orMask to Event_Id_NONE.

```
Event_pend(myEvent, (Event_Id_00 + Event_Id_06), Event_Id_NONE,
           BIOS_WAIT_FOREVER);
```

Runtime example: The following C code has a call to Event_post() to signal which events have occurred. The eventMask should contain the IDs of the events that are being posted.

```
Event_post(myEvent, Event_Id_00);
```

Runtime Example: The following C code example shows a task that provides the background processing required for three Interrupt Service Routines:




```
Event_Handle myEvent;

main()
{
   /* create an Event object. All events are binary */
   myEvent = Event_create(NULL, NULL);
}

isr0()
{
   ...
   Event_post(myEvent, Event_Id_00);
   ...
}

isr1()
{
   ...
   Event_post(myEvent, Event_Id_01);
   ...
}

isr2()
{
   ...
   Event_post(myEvent, Event_Id_02);
   ...
}
```

```
task()
{
   UInt events;

   while (TRUE) {
      /* Wait for ANY of the ISR events to be posted *
      events = Event_pend(myEvent, Event_Id_NONE,
            Event_Id_00 + Event_Id_01 + Event_Id_02,
            BIOS_WAIT_FOREVER);

      /* Process all the events that have occurred */
      if (events & Event_Id_00) {
         processISR0();
      }
      if (events & Event_Id_01) {
         processISR1();
      }
      if (events & Event_Id_02) {
         processISR2();
      }
   }
}
```

3.2.1 Implicitly Posted Events

In addition to supporting the explicit posting of events through the Event_post() API, some DSP/BIOS objects support implicit posting of events associated with their objects. For example, a Mailbox can be configured to post an associated event whenever a message is available (that is, whenever Mailbox_post() is called) thus allowing a task to block while waiting for a Mailbox message and/or some other event to occur.

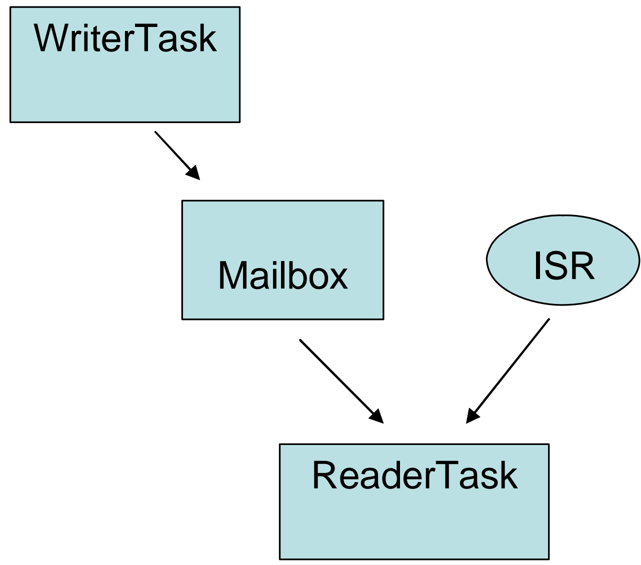
Mailbox and Semaphore objects currently support the posting of events associated with their resources becoming available.

DSP/BIOS objects that support implicit event posting must be configured with an event object and event ID when created. You can decide which event ID to associate with the specific resource availability signal (that is, a message available in Mailbox, room available in Mailbox, or Semaphore available).

> **Note:** As mentioned earlier, only one Task can pend on an Event object at a time. Consequently, DSP/BIOS objects that are configured for implicit event posting should only be waited on by a single Task at a time.

When Event_pend() is used to acquire a resource from implicitly posting objects, the BIOS_NO_WAIT timeout parameter should be used to subsequently retrieve the resource from the object.

Runtime example: The following C code example shows a task processing the messages posted to a Mailbox message as well as performing an ISR's post-processing requirements.




```
Event_Handle myEvent;
Mailbox_Handle mbox;

typedef struct msg {
   UInt id;
   Char buf[10];
}

main()
{
   Mailbox_Params &mboxParams;

   myEvent = Event_create(NULL, NULL);
   Mailbox_Params_init(mboxParams);
   mboxParams.notEmptyEvent = myEvent;

   /* Assign Event_Id_00 to Mailbox "not empty" event */
   mboxParams.notEmptyEventId = Event_Id_00;
   mbox = Mailbox_create(sizeof(msg), 50, &mboxParams, NULL);

   /* Mailbox_create() sets Mailbox's notEmptyEvent to
    * counting mode and initial count = 50 */
}
```

```
writerTask()
{
   ...
   Mailbox_post(mbox, &msgA, FOREVER);
   /* implicitly posts Event_Id_00 to myEvent */
   ...
}

isr()
{
   Event_post(myEvent, Event_Id_01);
}

readerTask()
{
   while (TRUE) { /* Wait for either ISR or Mailbox message */
      events = Event_pend(myEvent,
                  Event_Id_NONE,                /* andMask = 0 */
                  Event_Id_00 + Event_Id_01, /* orMask */
                  BIOS_WAIT_FOREVER);         /* timeout */
      if (events & Event_Id_00) {
         /* Get the posted message.
          * Mailbox_pend() will not block since Event_pend()
          * has guaranteed that a message is available.
          * Notice that the special BIOS_NO_WAIT
          * parameter tells Mailbox that Event_pend()
          * was used to acquire the available message.
          */
         Mailbox_pend(mbox, &msgB, BIOS_NO_WAIT);
         processMsg(&msgB);
      }
      if (events & Event_Id_01) {
         processISR();
      }
   }
}
```

3.3 Gates

A "Gate" is a module that implements the IGateProvider interface. Gates are devices for preventing concurrent accesses to critical regions of code. The various Gate implementations differ in how they attempt to lock the critical regions.

Since xdc.runtime.Gate is provided by XDCtools, the base module is documented in the online help and the RTSC-pedia wiki. Implementations of Gates provided by DSP/BIOS are discussed here.

Threads can be preempted by other threads of higher priority, and some sections of code need to be completed by one thread before they can be executed by another thread. Code that modifies a linked list is a common example of a critical region that may need to be protected by a Gate.

Gates generally work by either disabling some level of preemption such as disabling task switching or even hardware interrupts, or by using a binary semaphore.

All Gate implementations support nesting through the use of a "key". For Gates that function by disabling preemption, it is possible that multiple threads would call Gate_enter(), but preemption should not be restored until all of the threads have called Gate_leave(). This functionality is provided through the use of a key. A call to Gate_enter() returns a key that must then be passed back to Gate_leave(). Only the outermost call to Gate_enter() returns the correct key for restoring preemption. (The actual module name for the implementation is used instead of "Gate" in the function name.)

Runtime example: The following C code protects a critical region with a Gate. This example uses a GateHwi, which disables and enables interrupts as the locking mechanism.

```
UInt gateKey;
GateHwi_Handle gateHwi;
GateHwi_Params prms;
GateHwi_Params_init(&prms);

gateHwi = GateHwi_create(&prms, NULL);

/* Simultaneous operations on a List by multiple threads could
 * corrupt the List structure, so modifications to the List
 * are protected with a Gate. */
gateKey = GateHwi_enter(gateHwi);
List_get(myList);
GateHwi_leave(gateHwi, gateKey);
```

3.3.1 Preemption-Based Gate Implementations

The following implementations of gates use some form of preemption disabling:

- ti.sysbios.gates.GateHwi
- ti.sysbios.gates.GateSwi
- ti.sysbios.gates.GateTask

3.3.1.1 GateHwi

GateHwi disables and enables interrupts as the locking mechanism. Such a gate guarantees exclusive access to the CPU. This gate can be used when the critical region is shared by Task, Swi, or Hwi threads.

The duration between the enter and leave should be as short as possible to minimize Hwi latency.

3.3.1.2 GateSwi

GateSwi disables and enables software interrupts as the locking mechanism. This gate can be used when the critical region is shared by Swi or Task threads. This gate cannot be used by a Hwi thread.

The duration between the enter and leave should be as short as possible to minimize Swi latency.

3.3.1.3 GateTask

GateTask disables and enables tasks as the locking mechanism. This gate can be used when the critical region is shared by Task threads. This gate cannot be used by a Hwi or Swi thread.

The duration between the enter and leave should be as short as possible to minimize Task latency.

3.3.2 Semaphore-Based Gate Implementations

The following implementations of gates use a semaphore:

- ti.sysbios.gates.GateMutex
- ti.sysbios.gates.GateMutexPri

3.3.2.1 GateMutex

GateMutex uses a binary Semaphore as the locking mechanism. Each GateMutex instance has its own unique Semaphore. Because this gate can potentially block, it should not be used a Swi or Hwi thread, and should only be used by Task threads.

3.3.2.2 GateMutexPri

GateMutexPri is a mutex Gate (it can only be held by one thread at a time) that implements "priority inheritance" in order to prevent priority inversion. Priority inversion occurs when a high-priority Task has its priority effectively "inverted" because it is waiting on a Gate held by a lower-priority Task. Issues and solutions for priority inversion are described in Section 3.3.3.

Configuration example: The following example specifies a GateType to be used by HeapMem. (See section 5.1.1, *HeapMem* for further discussion.)

```
var GateMutexPri = xdc.useModule('ti.sysbios.gates.GateMutexPri');
var HeapMem = xdc.useModule('ti.sysbios.heaps.HeapMem');

HeapMem.common$.gate = GateMutexPri.create();
```

3.3.3 Priority Inversion

The following example shows the problem of priority inversion. A system has three tasks—Low, Med, and High—each with the priority suggested by its name. Task Low runs first and acquires the gate. Task High is scheduled and preempts Low. Task High tries to acquire the gate, and waits on it. Next, task Med is scheduled and preempts task Low. Now task High must wait for both task Med and task Low to finish before it can continue. In this situation, task Low has, in effect, lowered task High's priority to that of Low.

Solution: Priority Inheritance
To guard against priority inversion, GateMutexPri implements priority inheritance. When task High tries to acquire a gate that is owned by task Low, task Low's priority is temporarily raised to that of High, as long as High is waiting on the gate. So, task High "donates" its priority to task Low.

When multiple tasks wait on the gate, the gate owner receives the highest priority of any of the tasks waiting on the gate.

Caveats
Priority inheritance is not a complete guard against priority inversion. Tasks only donate their priority on the call to enter a gate, so if a task has its priority raised while waiting on a gate, that priority is not carried through to the gate owner.

This can occur in situations involving multiple gates. For example, a system has four tasks: VeryLow, Low, Med, and High, each with the priority suggested by its name. Task VeryLow runs first and acquires gate A. Task Low runs next and acquires gate B, then waits on gate A. Task High runs and waits on gate B. Task High has donated its priority to task Low, but Low is blocked on VeryLow, so priority inversion occurs despite the use of the gate. The solution to this problem is to design around it. If gate A may be needed by a high-priority, time-critical task, then it should be a design rule that no task holds this gate for a long time or blocks while holding this gate.

When multiple tasks wait on this gate, they receive the gate in order of priority (higher-priority tasks receive the gate first). This is because the list of tasks waiting on a GateMutexPri is sorted by priority, not FIFO.

Calls to GateMutexPri_enter() may block, so this gate can only be used in the task context.

GateMutexPri has non-deterministic calls because it keeps the list of waiting tasks sorted by priority.

3.4 Mailboxes

The ti.sysbios.ipc.Mailbox module provides a set of functions to manage mailboxes. Mailboxes can be used to pass buffers from one task to another on the same processor.

A Mailbox instance can be used by multiple readers and writers.

The Mailbox module copies the buffer to fixed-size internal buffers. The size and number of these buffers are specified when a Mailbox instance is created (or constructed). A copy is done when a buffer is sent via Mailbox_post(). Another copy occurs when the buffer is retrieved via a Mailbox_pend().

Mailbox_create() and Mailbox_delete() are used to create and delete mailboxes, respectively. You can also create mailbox objects statically. See the *XDCtools Consumer User's Guide* for a discussion of the benefits of creating objects statically.

Mailboxes can be used to ensure that the flow of incoming buffers does not exceed the ability of the system to process those buffers. The examples given later in this section illustrate just such a scheme.

You specify the number of internal mailbox buffers and size of each of these buffers when you create a mailbox. Since the size is specified when you create the Mailbox, all buffers sent and received with the Mailbox instance must be of this same size.

```
Mailbox_Handle Mailbox_create(SizeT          bufsize,
                              UInt           numBufs,
                              Mailbox_Params *params,
                              Error_Block    *eb)


Void Mailbox_delete(Mailbox_Handle *handle);
```

Mailbox_pend() is used to read a buffer from a mailbox. If no buffer is available (that is, the mailbox is empty), Mailbox_pend() blocks. The timeout parameter allows the task to wait until a timeout, to wait indefinitely (BIOS_WAIT_FOREVER), or to not wait at all (BIOS_NO_WAIT). The unit of time is system clock ticks.

```
Bool Mailbox_pend(Mailbox_Handle handle,
                  Ptr            buf,
                  UInt           timeout);
```

Mailbox_post() is used to post a buffer to the mailbox. If no buffer slots are available (that is, the mailbox is full), Mailbox_post() blocks. The timeout parameter allows the task to wait until a timeout, to wait indefinitely (BIOS_WAIT_FOREVER), or to not wait at all (BIOS_NO_WAIT).

```
Bool Mailbox_post(Mailbox_Handle handle,
                  Ptr            buf,
                  UInt           timeout);
```

Mailbox provides configuration parameters to allow you to associate events with a mailbox. This allows you to wait on a mailbox message and another event at the same time. Mailbox provides two configuration parameters to support events for the reader(s) of the mailbox—notEmptyEvent and notEmptyEventId. These allow a mailbox reader to use an event object to wait for the mailbox message. Mailbox also provides two configuration parameters for the mailbox writer(s)—notFullEvent and notFullEventId. These allow mailbox writers to use an event object to wait for room in the mailbox.

When using events, a thread calls Event_pend() and waits on several events. Upon returning from Event_pend(), the thread must call Mailbox_pend() or Mailbox_post()—depending on whether it is a writer or a reader—with a special timeout value of BIOS_EVENT_ACQUIRED. This timeout value allows the thread to get/put the message into the mailbox. This special timeout value is necessary for correct operation of the mailbox when using Events.

Chapter 4

Timing Services

This chapter describes modules that can be used for timing purposes.

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4.1 Overview of Timing Services

Several modules are involved in timekeeping and clock-related services within DSP/BIOS and XDCtools:

- **The ti.sysbios.knl.Clock module** is responsible for the periodic system tick that the kernel uses to keep track of time. All DSP/BIOS APIs that expect a timeout parameter interpret the timeout in terms of Clock ticks. The Clock module is used to schedule functions that run at intervals specified in clock ticks. By default, the Clock module uses the hal.Timer module to get a hardware-based tick. Alternately, the Clock module can be configured to use an application-provided tick source. See Section 4.2 for details. (The Clock module replaces both the CLK and PRD modules in earlier versions of DSP/BIOS.)
- **The ti.sysbios.hal.Timer module** provides a standard interface for using timer peripherals. It hides any target/device-specific characteristics of the timer peripherals. Target/device-specific properties for timers are supported by the ti.sysbios.family.xxx.Timer modules (for example, ti.sysbios.family.c64.Timer). You can use the Timer module to select a timer that calls a tickFxn when the timer expires. See Section 4.3 and Section 6.3 for details.
- **The xdc.runtime.Timestamp module** provides simple timestamping services for benchmarking code and adding timestamps to logs. This module uses a target/device-specific TimestampProvider in DSP/BIOS to control how timestamping is implemented. See Section 4.4 for details.

4.2 Clock

The ti.sysbios.knl.Clock module is responsible for the periodic system tick that the kernel uses to keep track of time. All DSP/BIOS APIs that expect a timeout parameter interpret the timeout in terms of Clock ticks.

The Clock module, by default, uses the ti.sysbios.hal.Timer module to create a timer to generate the system tick, which is basically a periodic call to Clock_tick(). See Section 4.3 for more about the Timer module.

The Clock module can be configured not to use the timer with either of the following configuration statements:

```
ti.sysbios.knl.Clock.tickSource = Clock.tickSource_USER
     or
ti.sysbios.knl.Clock.tickSource = Clock.tickSource_NULL
```

The period for the system tick is set by the configuration parameter Clock.tickPeriod. This is set in microseconds.

The Clock_tick() and the tick period are used as follows:

- **If the tickSource is Clock.tickSource_TIMER** (the default), Clock uses ti.sysbios.hal.Timer to create a timer to generate the system tick, which is basically a periodic call to Clock_tick(). Clock uses Clock.tickPeriod to create the timer. Clock.timerId can be changed to make Clock use a different timer.
- **If the tickSource is Clock.tickSource_USER**, then your application must call Clock_tick() from a user interrupt and set the tickPeriod to the approximate frequency of the user interrupt in microseconds.
- **If the tickSource is Clock.tickSource_NULL**, you cannot call any DSP/BIOS APIs with a timeout value and cannot call any Clock APIs. You can still use the Task module but you cannot call APIs that require a timeout, for example, Task_sleep(). Clock.tickPeriod values is not valid in this configuration.

Clock_getTicks() gets the number of Clock ticks that have occurred since startup. The value returned wraps back to zero after it reaches the maximum value that can be stored in 32 bits.

The Clock module provides APIs to start, stop and reconfigure the tick. These APIs allow you to make frequency changes at runtime. These three APIs are not reentrant and gates need to be used to protect them.

- **Clock_tickStop()** stops the timer used to generate the Clock tick by calling Timer_stop().
- **Clock_tickReconfig()** calls Timer_setPeriodMicroseconds() internally to reconfigure the timer. Clock_tickReconfig() fails if the timer cannot support Clock.tickPeriod at the current CPU frequency.
- **Clock_tickStart()** restarts the timer used to generate the Clock tick by calling Timer_start().

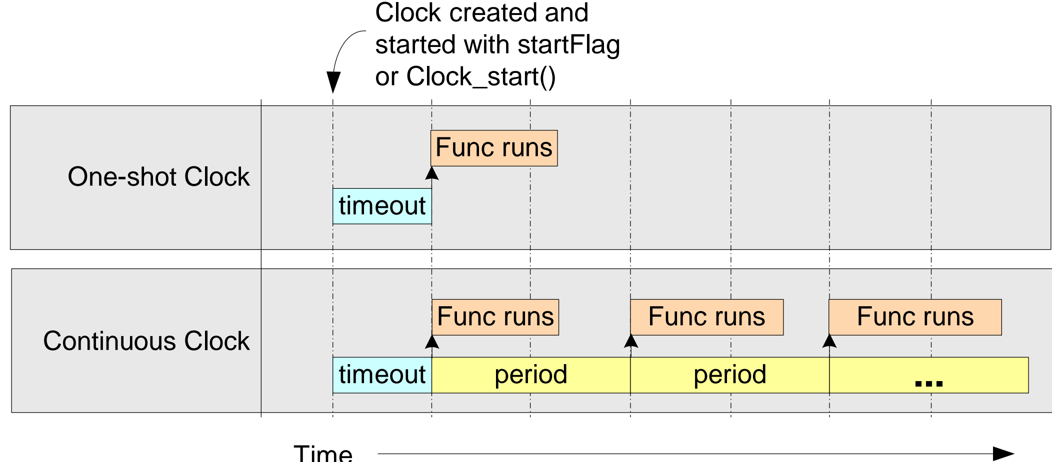
The Clock module lets you create Clock object instances, which reference functions that run when a timeout value specified in Clock ticks expires.

All Clock functions run in the context of a Swi. That is, the Clock module automatically creates a Swi for its use and run the Clock functions within that Swi. The priority of the Swi used by Clock can be changed by configuring Clock.swiPriority.

You can dynamically create clock instances using Clock_create(). Clock instances can be "one-shot" or continuous. You can start a clock instance when it is created or start it later by calling Clock_start(). This is controlled by the startFlag configuration parameter.

A function and a non-zero timeout value are required arguments to Clock_create(). The function is called when the timeout expires. The timeout value is used to compute the first expiration time. For one-shot Clock instances, the timeout value used to compute the single expiration time, and the period is zero. For periodic Clock instances, the timeout value is used to compute the first expiration time; the period value (part of the params) is used after the first expiration.

Table 4–1 Timeline for One-shot and Continuous Clocks



Clock instances (both one-shot and periodic) can be stopped and restarted by calling Clock_start() and Clock_stop(). Notice that while Clock_tickStop() stops the timer used to generate the Clock tick, Clock_stop() stops only one instance of a clock object. The expiration value is recomputed when you call Clock_start().

APIs that start or stop a Clock Instance—Clock_create(), Clock_start(), and Clock_stop()—can only be called in the Swi context.

The Clock module provides the Clock_setPeriod(), Clock_setTimeout(), and Clock_setFunc() APIs to modify Clock instance properties for Clock instances that have been stopped.

Runtime example: This C example shows how to create a Clock instance. This instance is dynamic (runs repeatedly) and starts automatically. It runs the myHandler function every 5 ticks. A user argument (UArg) is passed to the function.

```
Clock_Params clockParams;
Error_Block eb;

Clock_Params_init(&clockParams);
clockParams.period = 5;
clockParams.startFlag = TRUE;
clockParams.arg = (UArg)0x5555;
obj1 = Clock_create(myHandler1, 5, &clockParams, &eb);
```

Configuration example: This example uses XDCtools to create a Clock instance with the same properties as the previous example.

```
var Clock = xdc.useModule('ti.sysbios.knl.Clock');

var clockParams = new Clock.Params();
clockParams.period = 5;
clockParams.startFlag = true;
clockParams.arg = (UArg)0x5555;
Program.global.clockInst1 = Clock.create("&myHandler1", 5,
   clockParams);
```

Runtime example: This C example uses some of the Clock APIs to print messages about how long a Task sleeps.

```
UInt32 time1, time2;
. . .

System_printf("task going to sleep for 10 ticks... \n");
time1 = Clock_getTicks();
Task_sleep(10);

time2 = Clock_getTicks();
System_printf("...awake! Delta time is: %lu\n",
      (ULong) (time2 - time1));
```

Runtime example: This C example uses some of the Clock APIs to lower the Clock module frequency.

```
BIOS_getCpuFreq(&cpuFreq);
cpuFreq.lo = cpuFreq.lo / 2;
BIOS_setCpuFreq(&cpuFreq);

key = Hwi_disable();
Clock_tickStop();
Clock_tickReconfig();
Clock_tickStart();
Hwi_restore(key);
```

4.3 Timer Module

The ti.sysbios.hal.Timer module presents a standard interface for using the timer peripherals. This module is described in detail in Section 6.3 because it is part of the Hardware Abstraction Layer (HAL) package

You can use this module to create a timer (that is, to mark a timer for use) and configure it to call a tickFxn when the timer expires. Use this module only if you do not need to do any custom configuration of the timer peripheral.

The timer can be configured as a one-shot or a continuous mode timer. The period can be specified in timer counts or microseconds.

4.4 Timestamp Module

The xdc.runtime.Timestamp module, as the name suggests, provides timestamping services. The Timestamp module can be used for benchmarking code and adding timestamps to logs. (In previous versions of DSP/BIOS, this is the functionality provided by CLK_gethtime().)

Since xdc.runtime.Timestamp is provided by XDCtools, it is documented in the online help and the RTSC-pedia wiki.

Chapter 5

Memory

This chapter describes modules that can be used to allocate memory.

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5.1 Memory Allocation

A "Heap" is a module that implements the IHeap interface. Heaps are memory managers: they manage a specific piece of memory and support allocating and freeing pieces ("blocks") of that memory.

The xdc.runtime.Memory module is the common interface for all memory operations. The actual memory management is performed by a Heap instance, such as an instance of HeapMem or HeapBuf. For example, Memory_alloc() is used at runtime to dynamically allocate memory. All of the Memory APIs take a Heap instance as one of their parameters. Internally, the Memory module calls into the heap’s interface functions.

The xdc.runtime.Memory module is documented in the online help and the RTSC-pedia wiki. Implementations of Heaps provided by DSP/BIOS are discussed here.

Memory allocations sizes are measured in "Minimum Addressable Units" (MAUs) of memory. The size of an MAU in bits is determined by the target.

The different heap implementations optimize for different memory management traits. The HeapMem module (Section 5.1.1) accepts requests for all possible sizes of blocks, so it minimizes internal fragmentation. The HeapBuf module (Section 5.1.2), on the other hand, can only allocate blocks of a fixed size, so it minimizes external fragmentation in the heap and is also faster at allocating and freeing memory.

DSP/BIOS provides the following Heap implementations:

- **HeapMem.** Allocate variable-size blocks. Section 5.1.1
- **HeapBuf.** Allocate fixed-size blocks. Section 5.1.2
- **HeapMultiBuf.** Specify variable-size allocation, but internally allocate from a variety of fixed-size blocks. Section 5.1.3

5.1.1 HeapMem

HeapMem can be considered the most "flexible" of the Heaps because it allows you to allocate variable-sized blocks. When the size of memory requests is not known until runtime, it is ideal to be able to allocate exactly how much memory is required each time. For example, if a program needs to store an array of objects, and the number of objects needed isn't known until the program actually executes, the array will likely need to be allocated from a HeapMem.

The flexibility offered by HeapMem has a number of performance tradeoffs.

- **External Fragmentation.** Allocating variable-sized blocks can result in fragmentation. As memory blocks are "freed" back to the HeapMem, the available memory in the HeapMem becomes scattered throughout the heap. The total amount of free space in the HeapMem may be large, but because it is not contiguous, only blocks as large as the "fragments" in the heap can be allocated.

  This type of fragmentation is referred to as "external" fragmentation because the blocks themselves are allocated exactly to size, so the fragmentation is in the overall heap and is "external" to the blocks themselves.

- **Non-Deterministic Performance.** As the memory managed by the HeapMem becomes fragmented, the available chunks of memory are stored on a linked list. To allocate another block of memory, this list must be traversed to find a suitable block. Because this list can vary in length, it's not known how long an allocation request will take, and so the performance becomes "non-deterministic".

A number of suggestions can aide in the optimal use of a HeapMem.

- **Larger Blocks First.** If possible, allocate larger blocks first. Previous allocations of small memory blocks can reduce the size of the blocks available for larger memory allocations.
- **Overestimate Heap Size.** To account for the negative effects of fragmentation, use a HeapMem that is significantly larger than the absolute amount of memory the program will likely need.

When a block is freed back to the HeapMem, HeapMem combines the block with adjacent free blocks to make the available block sizes as large as possible.

Note: HeapMem uses a user-provided lock to lock access to the memory. For details, see Section 3.3, *Gates*.

The following examples create a HeapMem instance with a size of 1024 MAUs.

Configuration example: The first example uses XDCtools to statically configure the heap:

```
var HeapMem = xdc.useModule('ti.sysbios.heaps.HeapMem');

/* Create heap as global variable so it can be used in C code */
Program.global.myHeap = HeapMem.create();
Program.global.myHeap.size = 1024;
```

Runtime example: This second example uses C code to dynamically create a HeapMem instance:

```
HeapMem_Params prms;
static char *buf[1024];
HeapMem_Handle heap;

HeapMem_Params_init(&prms);
prms.size = 1024;
prms.buf = (Ptr)buf;
heap = HeapMem_create(&prms, NULL);
```

HeapMem uses a Gate (see the Gates section for an explanation of Gates) to prevent concurrent accesses to the code which operates on a HeapMem's list of free blocks. The type of Gate used by HeapMem is statically configurable through the HeapMem's common defaults.

Configuration example: This example configures HeapMem to use a GateMutexPri to protect critical regions of code.

```
var GateMutexPri = xdc.useModule('ti.sysbios.gates.GateMutexPri');
var HeapMem = xdc.useModule('ti.sysbios.heaps.HeapMem');


HeapMem.common$.gate = GateMutexPri.create();
```

The type of Gate used depends upon the level of protection needed for the application. If there is no risk of concurrent accesses to the heap, then "null" can be assigned to forgo the use of any Gate, which would improve performance. For an application that could have concurrent accesses, a GateMutex is a likely choice. Or, if it is possible that a critical thread will require the HeapMem at the same time as a low-priority thread, then a GateMutexPri would be best suited to ensuring that the critical thread receives access to the HeapMem as quickly as possible. See Section 3.3.2.2, *GateMutexPri* for more information.

5.1.2 HeapBuf

HeapBuf is used for allocating fixed-size blocks of memory, and is designed to be fast and deterministic. Often a program needs to create and delete a varying number of instances of a fixed-size object. A HeapBuf is ideal for allocating space for such objects, since it can handle the request quickly and without any fragmentation.

A HeapBuf may also be used for allocating objects of varying sizes when response time is more important than efficient memory usage. In this case, a HeapBuf will suffer from "internal" fragmentation. There will never be any

fragmented space in the heap overall, but the allocated blocks themselves may contain wasted space, so the fragmentation is "internal" to the allocated block.

Allocating from and freeing to a HeapBuf always takes the same amount of time, so a HeapBuf is a "deterministic" memory manager.

The following examples create a HeapBuf instance with a size of 1024 MAUs and a block size of 128 MAUs.

Configuration example: The first example uses XDCtools to statically configure the heap:

```
var HeapBuf = xdc.useModule('ti.sysbios.heaps.HeapBuf');

/* Create heap as global variable so it can be used in C code */
Program.global.myHeap = HeapBuf.create();
Program.global.myHeap.blockSize = 128;
Program.global.myHeap.numBlocks = 10;
```

Runtime example: This second example uses C code to dynamically create a HeapBuf instance:

```
HeapBuf_Params prms;
static char *buf[1280];
HeapBuf_Handle heap;

HeapBuf_Params_init(&prms);
prms.blockSize = 128;
prms.numBlocks = 10;
prms.buf = buf;
prms.bufSize = 1280;
heap = HeapBuf_create(&prms, NULL);
```

5.1.3 HeapMultiBuf

HeapMultiBuf is intended to balance the strengths of HeapMem and HeapBuf. Internally, a HeapMultiBuf maintains a collection of HeapBuf instances, each with a different block size, alignment, and number of blocks. A HeapMultiBuf instance can accept memory requests of any size, and simply determines which of the HeapBufs to allocate from.

A HeapMultiBuf provides more flexibility in block size than a single HeapBuf, but largely retains the fast performance of a HeapBuf. A HeapMultiBuf instance has the added overhead of looping through the HeapBufs to determine which to allocate from. In practice, though, the number of different block sizes is usually small and is always a fixed number, so a HeapMultiBuf can be considered deterministic by some definitions.

A HeapMultiBuf services a request for any memory size, but always returns one of the fixed-sized blocks. The allocation will not return any information about the actual size of the allocated block. When freeing a block back to a HeapMultiBuf, the size parameter is ignored. HeapMultiBuf determines the buffer to free the block to by comparing addresses.

When a HeapMultiBuf runs out of blocks in one of its buffers, it can be configured to allocate blocks from the next largest buffer. This is referred to as "block borrowing". See the online reference described in Section 1.5.1 for more about HeapMultiBuf.

The following examples create a HeapMultiBuf that manages 1024 MAUs of memory, which are divided into 3 buffers. It will manage 8 blocks of size 16 MAUs, 8 blocks of size 32 MAUs, and 5 blocks of size 128 MAUs as shown in the following diagram.

Program.global.myHeap

<table>
<tr><td>16 MAUs</td><td>16 MAUs</td><td>16 MAUs</td><td>16 MAUs</td><td>16 MAUs</td><td>16 MAUs</td><td>16 MAUs</td><td>16 MAUs</td></tr>
<tr><td colspan="2">32 MAUs</td><td colspan="2">32 MAUs</td><td colspan="2">32 MAUs</td><td colspan="2">32 MAUs</td></tr>
<tr><td colspan="2">32 MAUs</td><td colspan="2">32 MAUs</td><td colspan="2">32 MAUs</td><td colspan="2">32 MAUs</td></tr>
<tr><td colspan="8">128 MAUs</td></tr>
<tr><td colspan="8">128 MAUs</td></tr>
<tr><td colspan="8">128 MAUs</td></tr>
<tr><td colspan="8">128 MAUs</td></tr>
<tr><td colspan="8">128 MAUs</td></tr>
</table>

Configuration example: The first example uses XDCtools to statically configure the HeapMultiBuf instance:

```
var HeapMultiBuf = xdc.useModule('ti.sysbios.heaps.HeapMultiBuf');

/* HeapMultiBuf without blockBorrowing. */
/* Create as a global variable to access it from C Code. */
Program.global.myHeap = HeapMultiBuf.create();

Program.global.myHeap.numBufs = 3;
Program.global.myHeap.blockBorrow = false;
Program.global.myHeap.bufParams =
     [{blockSize: 16, numBlocks:8, align: 0},
      {blockSize: 32, numBlocks:8, align: 0},
      {blockSize: 128, numBlocks:5, align: 0}];
```

Runtime example: This second example uses C code to dynamically create a HeapMultiBuf instance:

```
HeapMultiBuf_Params prms;
HeapMultiBuf_Handle heap;

/* Create the buffers to manage */
Char buf0[128];
Char buf1[256];
Char buf2[640];

/* Create the array of HeapBuf_Params */
HeapBuf_Params bufParams[3];

/* Load the default values */
HeapMultiBuf_Params_init(&prms);
prms.numBufs = 3;
prms.bufParams = bufParams;

HeapBuf_Params_init(&prms.bufParams[0]);
prms.bufParams[0].align = 0;
prms.bufParams[0].blockSize = 16;
prms.bufParams[0].numBlocks = 8;
prms.bufParams[0].buf = (Ptr) buf0;
prms.bufParams[0].bufSize = 128;

HeapBuf_Params_init(&prms.bufParams[1]);
prms.bufParams[1].align = 0;
prms.bufParams[1].blockSize = 32;
prms.bufParams[1].numBlocks = 8;
prms.bufParams[1].buf = (Ptr) buf1;
prms.bufParams[1].bufSize = 256;

HeapBuf_Params_init(&prms.bufParams[2]);
prms.bufParams[2].align = 0;
prms.bufParams[2].blockSize = 128;
prms.bufParams[2].numBlocks = 5;
prms.bufParams[2].buf = (Ptr) buf2;
prms.bufParams[2].bufSize = 640;

heap = HeapMultiBuf_create(&prms, NULL);
```

Chapter 6

Hardware Abstraction Layer

This chapter describes modules that provide hardware abstractions.

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6.2 HWI Module 6-3

6.3 Timer Module 6-11

6.4 Cache Module 6-16

6.5 HAL Package Organization 6-18

6.1 Hardware Abstraction Layer APIs

DSP/BIOS provides services for configuration and management of interrupts, cache, and timers. Unlike other DSP/BIOS services such as threading, these modules directly program aspects of a device's hardware and are grouped together in the Hardware Abstraction Layer (HAL) package. Services such as enabling and disabling interrupts, plugging of interrupt vectors, multiplexing of multiple interrupts to a single vector, and cache invalidation or writeback are described in this chapter.

Note: Any configuration or manipulation of interrupts and their associated vectors, the cache, and timers in a DSP/BIOS application must be done through the DSP/BIOS HAL APIs. In earlier versions of DSP/BIOS, some HAL services were not available and developers were expected to use functions from the Chip Support Library (CSL) for a device. The most recent releases of CSL (3.0 or above) are designed for use in applications that do not use DSP/BIOS. Some of their services are not compatible with DSP/BIOS. Usage of CSL interrupt, cache, and timer functions and DSP/BIOS in the same application should be avoided since this combination is known to result in complex interrupt-related debugging problems.

The HAL APIs fall into two categories:

- ❏ Generic APIs that are available across all targets and devices
- ❏ Target/device-specific APIs that are available only for a specific device or ISA family

The generic APIs are designed to cover the great majority of use cases. Developers who are concerned with ensuring easy portability between different TI devices are best served by using the generic APIs as much as possible. In cases where the generic APIs cannot enable use of a device-specific hardware feature that is advantageous to the software application, you may choose to use the target/device-specific APIs, which provide full hardware entitlement.

In this chapter, an overview of the functionality of each HAL package is provided along with usage examples for that package’s generic API functions. After the description of the generic functions, examples of target/device-specific APIs, based on those provided for ’C64x+ devices, are also given. For a full description of the target/device-specific APIs available for a particular family or device, please refer to the API reference documentation. section 6.5, *HAL Package Organization* provides an overview of the generic HAL packages and their associated target/device-specific packages to facilitate finding the appropriate packages.

6.2 HWI Module

The ti.sysbios.hal.Hwi module provides a collection of APIs for managing hardware interrupts. These APIs are generic across all supported targets and devices and should provide sufficient functionality for most applications.

6.2.1 Associating a C Function with a System Interrupt Source

To associate a user-provided C function with a particular system interrupt, you create a Hwi object that encapsulates information regarding the interrupt required by the Hwi module.

The standard static and dynamic forms of the "create" function are supported by the ti.sysbios.hal.Hwi module.

Configuration example: The following example statically creates a Hwi object that associates interrupt 5 with the "myIsr" C function using default instance configuration parameters:

```
Var Hwi = xdc.useModule('ti.sysbios.hal.Hwi');

Hwi.create(5, '&myIsr');
```

Runtime example: The C code required to configure the same interrupt dynamically would be as follows:

```
#include <ti/sysbios/hal/Hwi>

Hwi_create(5, myIsr, NULL, NULL);
```

The NULL, NULL arguments are used when the default instance parameters and generic error handling is satisfactory for creating a Hwi object.

6.2.2 Hwi Instance Configuration Parameters

The following configuration parameters and their default values are defined for each Hwi object. For a more detailed discussion of these parameters and their values see the ti.sysbios.hal.Hwi module in the online documentation. (For information on running online help, see Section 1.5.1, *Using the API Reference Help System*, page 1-7.)

- ❏ The "maskSetting" defines how interrupt nesting is managed by the interrupt dispatcher.

  ```
  MaskingOption maskSetting = MaskingOption_SELF;
  ```

- ❑ The configured "arg" parameter will be passed to the Hwi function when the dispatcher invokes it.

```
UArg arg = 0;
```

- ❑ The "enabledInt" parameter is used to automatically enable or disable an interrupt upon Hwi object creation.

```
Bool enableInt = true;
```

- ❑ The "eventId" accommodates 'C6000 devices that allow dynamic association of a peripheral event to an interrupt number. The default value of -1 leaves the eventId associated with an interrupt number in its normal (reset) state (that is, no re-association is required).

```
Int eventId = -1;
```

- ❑ The "priority" parameter is provided for those architectures that support interrupt priority setting. The default value of -1 informs the Hwi module to set the interrupt priority to a default value appropriate to the device.

```
Int priority = -1;
```

6.2.3 Creating a Hwi Object Using Non-Default Instance Configuration Parameters

Building on the examples given in Section 6.2.1, the following examples show how to associate interrupt number 5 with the "myIsr" C function, passing "10" as the argument to "myIsr" and leaving the interrupt disabled after creation.

Configuration example:

```
var Hwi = xdc.useModule('ti.sysbios.hal.Hwi');

/* initialize hwiParams to default values */
var hwiParams = new Hwi.Params;

hwiParams.arg = 10;          /* Set myIsr5 argument to 10 */
hwiParams.enableInt = false; /* override default setting */

/* Create a Hwi object for interrupt number 5
 * that invokes myIsr5() with argument 10 */
Hwi.create(5, '&myIsr', hwiParams);
```

Runtime example:

```
#include <ti/sysbios/hal/Hwi>

Hwi_Params hwiParams;

/* initialize hwiParams to default values */
Hwi_Params_init(&hwiParams);

hwiParams.arg = 10;
hwiParams.enableInt = FALSE;

Hwi_create(5, myIsr, &hwiParms, NULL);
```

6.2.4 Enabling and Disabling Interrupts

You can enable and disable interrupts globally as well as individually with the following Hwi module APIs:

- `UInt Hwi_enable();`
  Globally enables all interrupts. Returns the previous enabled/disabled state.
- `UInt Hwi_disable();`
  Globally disables all interrupts. Returns the previous enabled/disabled state.
- `Hwi_restore(UInt key);`
  Restores global interrupts to their previous enabled/disabled state. The "key" is the value returned from Hwi_disable() or Hwi_enable().
- The APIs that follow are used for enabling, disabling, and restoring specific interrupts given by "intNum". They have the same semantics as the global Hwi_enable/disable/restore APIs.:
  - `UInt Hwi_enableInterrupt(UInt intNum);`
  - `UInt Hwi_disableInterrupt(UInt intNum);`
  - `Hwi_restoreInterrupt(UInt key);`
- `Hwi_clearInterrupt(UInt intNum);`
  Clears "intNum" from the set of currently pending interrupts.

Disabling hardware interrupts is useful during a critical section of processing.

On the C6000 platform, Hwi_disable() clears the GIE bit in the control status register (CSR). On the C2000 platform, Hwi_disable() sets the INTM bit in the ST1 register.

6.2.5 A Simple Example Hwi Application

The following example creates two Hwi objects. One for interrupt number 5 and another for interrupt number 6. For illustrative purposes, one interrupt is created statically and the other dynamically. An idle function that waits for the interrupts to complete is also added to the Idle function list.

Configuration example:

```
/* Pull in BIOS module required by ALL BIOS applications */
xdc.useModule('ti.sysbios.BIOS');

/* Pull in XDC runtime System module for various APIs used */
xdc.useModule('xdc.runtime.System');

/* Get handle to Hwi module for static configuration */
var Hwi = xdc.useModule('ti.sysbios.hal.Hwi');

/* Initialize hwiParams to default values */
var hwiParams = new Hwi.Params;

/* Set myIsr5 argument */
hwiParams.arg = 10;

/* Keep interrupt 5 disabled until later */
hwiParams.enableInt = false;

/* Create a Hwi object for interrupt number 5
 * that invokes myIsr5() with argument 10 */
Hwi.create(5, '&myIsr5', hwiParams);

/* Add an idle thread 'myIdleFunc' that monitors interrupts. */
var Idle = xdc.useModule(ti.sysbios.knl.Idle);

Idle.addFunc('&myIdleFunc');
```

Runtime example:

```
#include <xdc/std.h>
#include <xdc/runtime/System.h>
#include <ti/sysbios/hal/Hwi>

Bool Hwi5 = FALSE;
Bool Hwi6 = FALSE;
```

```
Main(Void)   {
    Hwi_Params hwiParams;

    /* Initialize hwiParams to default values */
    Hwi_Params_init(&hwiParams);

    /* Set myIsr6 parameters */
    hwiParams.arg = 12;
    hwiParams.enableInt = FALSE;

    /* Create a Hwi object for interrupt number 6
     * that invokes myIsr6() with argument 12 */
    Hwi_create(6, myIsr6, &hwiParms, NULL);

    /* enable both interrupts */
    Hwi_enableInterrupt(5);
    Hwi_enableInterrupt(6);

    /* start BIOS */
    BIOS_start();
}

/* Runs when interrupt 5 occurs */
Void myIsr5(UArg arg)   {
    If (arg == 10) {
        Hwi5 = TRUE;
    }
}

/* Runs when interrupt 6 occurs */
Void myIsr6(UArg arg)   {
    If (arg == 12) {
        Hwi6 = TRUE;
    }
}

/* The Idle thread checks for completion of interrupts 5 & 6
 * and exits when they have both completed. */
Void myIdleFunc()
{
    If (Hwi5 && Hwi6) {
        System_printf("Both interrupts have occurred!");
        System_exit(0);
    }
}
```

6.2.6 The Interrupt Dispatcher

To consolidate code that performs register saving and restoration for each interrupt, DSP/BIOS provides an interrupt dispatcher that automatically performs these actions for an interrupt routine. Use of the Hwi dispatcher allows ISR functions to be written in C.

In addition to preserving the interrupted thread's context, the DSP/BIOS Hwi dispatcher orchestrates the following actions:

- Disables DSP/BIOS Swi and Task scheduling during interrupt processing
- Automatically manages nested interrupts on a per-interrupt basis.
- Invokes any configured "begin" Hwi Hook functions.
- Runs the Hwi function.
- Invokes any configured "end" Hwi Hook functions.
- Invokes Swi and Task schedulers after interrupt processing to perform any Swi and Task operations resulting from actions within the Hwi function.

Note: The *interrupt* keyword or INTERRUPT pragma must not be used to define the C function invoked by the Hwi dispatcher. The Hwi dispatcher contains this functionality, and the use of the C modifier will cause catastrophic results.

Functions that use the *interrupt* keyword or INTERRUPT pragma may not use the Hwi dispatcher and may not call DSP/BIOS APIs.

6.2.7 Registers Saved and Restored by the Interrupt Dispatcher

The registers saved and restored by the dispatcher in preparation for invoking the user's Hwi function conform to the "saved by caller" or "scratch" registers as defined in the register usage conventions section of the C compiler documents. For more information, either about which registers are saved and restored, or about the TMS320 functions conforming to the Texas Instruments C runtime model, see the *Optimizing Compiler User's Guide* for your platform.

6.2.8 Additional Target/Device-Specific Hwi Module Functionality

As described in Section 6.5, the ti.sysbios.hal.Hwi module is implemented using the RTSC proxy-delegate mechanism. All ti.sysbios.hal.Hwi module APIs are forwarded to a target/device-specific Hwi module that implements all of the ti.sysbios.hal.Hwi required APIs. Each of these Hwi module implementations provide additional APIs and functionality unique to the family/device and can be used instead of the ti.sysbios.hal.Hwi module if needed.

For example, the 'C64x+ target-specific Hwi module provides the following APIs in addition to those defined in the ti.sysbios.hal.Hwi module:

- `Hwi_eventMap(UInt intNum, UInt eventId;`
  Remaps a peripheral event number to an interrupt number.
- ```
  Bits16 Hwi_enableIER(Bits16 mask);
  Bits16 Hwi_disableIER(Bits16 mask);
  Bits16 Hwi_restoreIER(Bits16 mask);
  ```

  These three APIs allow enabling, disabling and restoring a set of interrupts defined by a "mask" argument. These APIs provide direct manipulation of the 'C64x+'s internal IER registers.

To gain access to these additional APIs, you use the target/device-specific Hwi module associated with the 'C64x+ target rather than the ti.sysbios.hal.Hwi module.

The following examples are modified versions of portions of the example in Section 6.2.5. The modifications are shown in **bold**.

Configuration example:

```
var Hwi = xdc.useModule('ti.sysbios.family.c64p.Hwi');

/* Initialize hwiParams to default values */
var hwiParams = new Hwi.Params;

/* Set myIsr5 parameters */
hwiParams.arg = 10;
hwiParams.enableInt = false;

/* Create a Hwi object for interrupt number 5
 * that invokes myIsr5() with argument 10 */
Hwi.create(5, '&myIsr5', hwiParams);
```
```

Runtime example:

```
#include <ti/sysbios/family/c64p/Hwi>

Main(Void)   {
    Hwi_Params hwiParams;

    /* Initialize hwiParams to default values */
    Hwi_Params_init(&hwiParams);

    /* Set myIsr6 parameters */
    hwiParams.arg = 12;
    hwiParams.enableInt = FALSE;

    /* Create a Hwi object for interrupt number 6
     * that invokes myIsr6() with argument 12 */
    Hwi_create(6, myIsr6, &hwiParms, NULL);

    /* Enable interrupts 5 & 6 simultaneously using the C64x+
     * Hwi module Hwi_enableIER() API. */
    Hwi_enableIER(0x0060);

. . .
```

6.3 Timer Module

The ti.sysbios.hal.Timer module presents a standard interface for using the timer peripherals. It hides any target/device-specific characteristics of the timer peripherals. It inherits the ti.sysbios.interfaces.ITimer interface.

You can use this module to create a timer (that is, to mark a timer for use) and configure it to call a tickFxn when the timer expires. Use this module only if you do not need to do any custom configuration of the timer peripheral.

This module has a configuration parameter called TimerProxy which is plugged by default with a target/device-specific implementation. For example, the implementation for C64x targets is ti.sysbios.family.c64.Timer.

The timer can be configured as a one-shot or a continuous mode timer. The period can be specified in timer counts or microseconds.

The timer interrupt always uses the Hwi dispatcher. The Timer tickFxn runs in the context of a Hwi thread. The Timer module automatically creates a Hwi instance for the timer interrupt.

The Timer_create() API takes a timerId. The timerId can range from zero to a target/device-specific value determined by the TimerProxy. The timerId is just a logical ID; its relationship to the actual timer peripheral is controlled by the TimerProxy.

If it does not matter to your program which timer is used, in a C program or XDCtools configuration you can specify a timerId of Timer_ANY_TIMER which means "use any available timer". For example, in an XDCtools configuration use:

```
Timer.create(Timer_ANY_TIMER, "&myIsr", timerParams);
```

In a C program, use:

```
Timer_create(Timer_ANY_TIMER, myIsr, &timerParams, NULL);
```

The timerParams includes a number of parameters to configure the timer. For example timerParams.startMode can be set to StartMode_AUTO or StartMode_USER. The StartMode_AUTO setting indicates that statically-created timers will be started in BIOS_start() and dynamically-created timers will be started at create() time. The StartMode_USER indicates that your program starts the timer using Timer_start(). See the example in Section 6.3.1.

You can get the total number of timer peripherals by calling Timer_getNumTimers() at runtime. This includes both used and available timer peripherals. You can query the status of the timers by calling Timer_getStatus().

If you want to use a specific timer peripheral or want to use a custom timer configuration (setting timer output pins, emulation behavior, etc.), you should use the target/device-specific Timer module. For example, ti.sysbios.family.c64.Timer.

The Timer module also allows you to specify the extFreq (external frequency) property for the timer peripheral and provides an API to get the timer frequency at runtime. This external frequency property is supported only on targets where the timer frequency can be set separately from the CPU frequency.

You can use Timer_getFreq() to convert from timer interrupts to real time.

The Timer module provides APIs to start, stop, and modify the timer period at runtime. These APIs have the following side effects.

- Timer_setPeriod() stops the timer before setting the period register. It then restarts the timer.
- Timer_stop() stops the timer and disables the timer interrupt.
- Timer_start() clears counters, clears any pending interrupts, and enables the timer interrupt before starting the timer.

Runtime example: This C example creates a timer with a period of 10 microseconds. It passes an argument of 1 to the myIsr function. It instructs the Timer module to use any available timer peripheral:

```
Timer_Params timerParams;
Timer_Params_init(&timerParams);
timerParams.period = 10;
timerparams.periodType = Timer_PeriodType_MICROSECS;
timerParams.arg = 1;
Timer_create(Timer_ANY_TIMER, myIsr, &timerParams, NULL);
```

Configuration example: This XDCtools example statically creates a timer with the same characteristics as the previous C example. It specifies a timerId of 1:

```
var timer = xdc.useModule('ti.sysbios.hal.Timer');
var timerParams = new Timer.Params();
timerParams.period = 10;
timerParams.periodType = Timer.PeriodType_MICROSECS;
timerParams.arg = 1;
timer.create(1, '&myIsr', timerParams);
```

Runtime example: This C example specifies a frequency for a timer that it creates. The extFreq.hi and extFreq.lo properties set the high and low 32-bit portions of the structure used to represent the frequency in Hz.

```
Timer_Params timerParams;

Timer_Params_init(&timerParams);
timerParams.extFreq.lo = 270000000; /* 27 MHz */
timerParams.extFreq.hi = 0;

...
Timer_create(Timer_ANY_TIMER, myIsr, &timerParams, NULL);
```

Configuration example: This XDCtools configuration example specifies a frequency for a timer that it creates.

```
var Timer = xdc.useModule('ti.sysbios.hal.Timer');
var timerParams = new Timer.Params();
timerParams.extFreq.lo = 270000000;
timerParams.extFreq.hi = 0;
...
Timer.create(1, '&myIsr', timerParams);
```

Runtime example: This C example creates a timer that runs the tickFxn() every 2 milliseconds using any available timer peripheral. It also creates a task that, when certain conditions occur, changes the timer's period from 2 to 4 milliseconds. The tickFxn() itself prints a message that shows the current period of the timer.

```
Timer_Handle timerHandle;

Int main(Void)
{
    Error_Block eb;
    Timer_Params timerParams;

    Timer_Params_init(&timerParams);
    timerParams.period = 2000;    /* 2 ms */
    timerHandle = Timer_create(Timer_ANY_TIMER, tickFxn,
                               &timerParams, &eb);

    if (Error_check(&eb)) {
        System_abort("Timer create failed");
    }

    Task_create(masterTask, NULL, NULL);
}
```

```
Void masterTask(UArg arg0 UArg arg1)
{
    ...
    // Condition detected requiring a change to timer period
    Timer_stop(timerHandle);
    Timer_setPeriodMicroSecs(4000);   /* change 2ms to 4ms */
    Timer_start(timerHandle();
    ...
}

Void tickFxn(UArg arg0 UArg arg1)
{
    System_printf("Current period = %d\n",
           Timer_getPeriod(timerHandle);
}
```

6.3.1 Target/Device-Specific Timer Modules

As described in Section 6.5, the ti.sysbios.hal.Timer module is implemented using the RTSC proxy-delegate mechanism. A separate target/device-specific Timer module is provided for each supported family. For example, the ti.sysbios.timers.timer64.Timer module acts as the timer peripherals manager for the 64P family.

These target/device-specific modules provide additional configuration parameters and APIs that are not supported by the generic ti.sysbios.hal.Timer module.

In the case of the ti.sysbios.timers.timer64.Timer module, the configuration parameters controlInit, globalControlInit, and emuMgtInit are provided to configure various timer properties. This module also exposes a Hwi Params structure as part of its create parameters to allow you to configure the Hwi object associated with the Timer. This module also exposes a Timer_reconfig() API to allow you to reconfigure a statically-created timer.

Configuration example: This XDCtools configuration example specifies timer parameters, including target/device-specific parameters for a timer called myTimer that it creates.

```
var Timer = xdc.useModule('ti.sysbios.timers.timer64.Timer');

var timerParams = new Timer.Params();
timerParams.period = 2000;     //2ms
timerParams.arg = 1;
timerParams.startMode = Timer.StartMode_USER;
timerParams.controlInit.invout = 1;
timerParams.globalControlInit.chained = false;
timerParams.emuMgtInit.free = false;
timerParams.suspSrc = SuspSrc_ARM;

Program.global.myTimer = Timer.create(1, "&myIsr",
    timerParams);
```

Runtime example: This C example uses the myTimer created in the preceding XDCtools configuration example and reconfigures the timer with a different function argument and startMode in the program's main() function before calling BIOS_start().

```
#include <ti/sysbios/timers/timer64/Timer.h>
#include <xdc/cfg/global.h>

Void myIsr(UArg arg)
{
    System_printf("myIsr arg = %d\n", (Int)arg);
    System_exit(0);
}

Int main(Int argc, char* argv[])
{
    Timer_Params timerParams;

    Timer_Params_init(&timerParams);
    timerParams.arg = 2;
    timerparams.startMode = Timer_StartMode_AUTO;
    Timer_reconfig(myTimer, &timerParams, NULL);

    BIOS_start();

    return(0);
}
```

6.4 Cache Module

The cache support provides API functions that perform cache coherency operations at the cache line level or globally. The cache coherency operations are:

- **Invalidate.** Makes valid cache lines invalid and discards the content of the affected cache lines.
- **Writeback.** Writes the contents of cache lines to a lower-level memory, such as the L2 cache or external memory, without discarding the lines in the original cache.
- **Writeback-Invalidation.** Writes the contents of cache lines to lower-level memory, and then discards the contents of the lines in the original cache.

6.4.1 Cache Interface Functions

The cache interface is defined in ti.sysbios.interfaces.ICache. The Cache interface contains the following functions. The implementations for these functions are target/device-specific.

- **Cache_enable();** Enables all caches.
- **Cache_disable();** Disables all caches.
- **Cache_inv(blockPtr, byteCnt, wait);** Invalidates the specified range of memory. When you invalidate a cache line, its contents are discarded and the cache tags the line as "dirty" so that next time that particular address is read, it is obtained from external memory. All lines in the range are invalidated in all caches.
- **Cache_wb(blockPtr, byteCnt, wait);** Writes back the specified range of memory. When you perform a writeback, the contents of the cache lines are written to lower-level memory. All lines within the range are left valid in caches and the data within the range is written back to the source memory.
- **Cache_wbInv(blockPtr, byteCnt, wait);** Writes back and invalidates the specified range of memory. When you perform a writeback, the contents of the cache lines are written to lower-level memory. When you invalidate a cache line, its contents are discarded. All lines within the range are written back to the source memory and then invalidated in all caches.

These Cache APIs operate on an address range beginning with the starting address of blockPtr and extending for the specified byte count. The range of addresses operated on is quantized to whole cache lines in each cache.

The blockPtr points to an address in non-cache memory that may be cached in one or more caches or not at all. If the blockPtr does not correspond to the start of a cache line, the start of that cache line is used.

If the byteCnt is not equal to a whole number of cache lines, the byteCnt is rounded up to the next size that equals a whole number of cache lines.

If the wait parameter is true, then this function waits until the invalidation operation is complete to return. If the wait parameter is false, this function returns immediately. You can use Cache_wait() later to ensure that this operation is complete.

- **Cache_wait();** Waits for the cache wb/wbInv/inv operation to complete. A cache operation is not truly complete until it has worked its way through all buffering and all memory writes have landed in the source memory.

As described in Section 6.5, this module is implemented using the RTSC proxy-delegate mechanism. A separate target/device-specific Cache module is provided for each supported family.

Additional APIs are added to this module for certain target/device-specific implementations. For example, the ti.sysbios.family.c64p.Cache module adds APIs specific to the C64x+ caches. These extensions have functions that also have the prefix "Cache_".

Currently the C64x+, C674x, and ARM caches are supported.

C64x+ specific: The caches on these devices are Level 1 Program (L1P), Level 1 Data (L1D), and Level 2 (L2). See the *TMS320C64x+ DSP Megamodule Reference Guide* (SPRU871) for information about the L1P, L1D, and L2 caches.

6.5 HAL Package Organization

The three DSP/BIOS modules that reside in the ti.sysbios.hal package: Hwi, Timer, and Cache require target/device-specific API implementations to achieve their functionality. In order to provide a common set of APIs for these modules across all supported families/devices, DSP/BIOS uses the RTSC proxy-delegate module mechanism. (See the "RTSC Interface Primer: Lesson 12" for details.)

Each of these three modules serves as a proxy for a corresponding target/device-specific module implementation. In use, all Timer/Hwi/Cache API invocations are forwarded to an appropriate target/device-specific module implementation.

During the configuration step of the application build process, the proxy modules in the ti.sysbios.hal package locate and bind themselves to appropriate delegate module implementations based on the current target and platform specified in the user's config.bld file. The delegate binding process is done internally.

The following tables show the currently supported (as of this document's publication) Timer, Hwi, and Cache delegate modules that may be selected based on an application's target and device. The mapping of target/device to the delegate modules used by Timer, Cache, and Hwi is accessible through a link in the ti.sysbios.hal package online help.

Table 6–1 Proxy to Delegate Mappings

Proxy Module	Delegate Modules
ti.sysbios.hal.Timer	ti.sysbios.hal.TimerNull * ti.sysbios.timers.gptimer.Timer ti.sysbios.timers.timer64.Timer ti.sysbios.family.c64.Timer ti.sysbios.family.c67p.Timer ti.sysbios.family.windows.Timer ti.sysbios.family.m3.Timer
ti.sysbios.hal.Hwi	ti.sysbios.family.c64.Hwi ti.sysbios.family.c64p.Hwi ti.sysbios.family.c67p.Hwi ti.sysbios.family.windows.Hwi ti.sysbios.family.arm9.dm6446.Hwi ti.sysbios.family.arm9.dm510.Hwi ti.sysbios.family.arm9.primus.Hwi ti.sysbios.family.m3.Hwi

Table 6–1 Proxy to Delegate Mappings

Proxy Module	Delegate Modules
ti.sysbios.hal.Cache	ti.sysbios.hal.CacheNull * ti.sysbios.family.c64p.Cache ti.sysbios.family.c67p.Cache ti.sysbios.family.arm9.Cache

* For targets/devices for which a Timer or Cache module has not yet been developed, the hal.TimerNull or hal.CacheNull delegate is used. In TimerNull/CacheNull, the APIs defined in ITimer/ICache are implemented using null functions.

For the proxy-delegate mechanism to work properly, both the proxy and the delegate modules must be implementations of a common RTSC interface specification. The Timer, Hwi, and Cache interface specifications reside in ti.sysbios.interfaces and are ITimer, IHwi, and ICache respectively. These interface specifications define a minimum set of general APIs that, it is believed, will satisfy a vast majority of application requirements. For those applications that may need target/device-specific functionality not defined in these interface specifications, the corresponding Timer, Hwi, and Cache delegate modules contain extensions to the APIs defined in the interface specifications.

To access to these extended API sets, you must directly reference the target/device-specific module in your configuration file and include its corresponding header file in your C source files.

Chapter 7

Instrumentation

This chapter describes modules and other tools that can be used for instrumentation purposes.

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7.1 Overview of Instrumentation

Much of the instrumentation available to DSP/BIOS applications is provided by the XDCtools modules and APIs. See the XDCtools documentation for details about the Assert, Diags, Error, Log, LoggerBuf, and LoggerSys modules.

7.2 Load Module

The ti.sysbios.utils.Load module reports execution times and load information for threads in a system.

DSP/BIOS manages four distinct levels of execution threads: hardware interrupt service routines, software interrupt routines, tasks, and background idle functions. The Load module reports execution time and load on a per-task basis, and also provides information globally for hardware interrupt service routines, software interrupt routines, and idle functions (in the form of the idle task). It can also report an estimate of the global CPU load, which is computed as the percentage of time in the measurement window that was *not* spent in the idle loop. More specifically, the load is computed as follows.

```
global CPU load = 100 * (1 -  ((x * t) / w) )
```

where:

- 'x' is the number of times the idle loop has been executed during the measurement window.
- 't' is the minimum time for a trip around the idle loop, meaning the time it takes to complete the idle loop if no work is being done in it.
- 'w' is the length in time of the measurement window.

Any work done in the idle loop is included in the CPU load. In other words, any time spent in the loop beyond the shortest trip around the idle loop is counted as non-idle time.

The Load module relies on "update" to be called to compute load and execution times from the time when "update" was last called. This is automatically done for every period specified by Load.windowInMs (default = 500 ms) in a ti.sysbios.knl.Idle function when Load.updateInIdle is set to true (the default). The benchmark time window is the length of time between 2 calls to "update".

The execution time is reported in units of xdc.runtime.Timestamp counts, and the load is reported in percentages.

By default, load data is gathered for all threads. You can use the configuration parameters Load.hwiEnabled, Load.swiEnabled, and Load.taskEnabled to select which type(s) of threads are monitored.

7.2.1 Load Module Configuration

The Load module has been setup to provide data with as little configuration as possible. Using the default configuration, load data is gathered and logged for all threads roughly every 500 ms.

The following code configures the Load module to write Load statistics to a LoggerBuf instance.

```
var LoggerBuf = xdc.useModule('xdc.runtime.LoggerBuf');
var Load = xdc.useModule('ti.sysbios.utils.Load');
var Diags = xdc.useModule('xdc.runtime.Diags');

var loggerBuf = LoggerBuf.create();
Load.common$.logger = loggerBuf;
Load.common$.diags_USER4 = Diags.ALWAYS_ON;
```

For information on advanced configuration and caveats of the Load module, see the online reference documentation.

7.2.2 Obtaining Load Statistics

Load statistics recorded by the Load module can be obtained in one of two ways:

- **Load module logger.** If you configure the Load module with a logger and have turned on the diags_USER4, the statistics gathered by the Load module are recorded to the load module's logger instance. You can use the RTA tool to visualize the Load based on these Log records. See Section 7.3 for more information.

  Alternatively, you can configure the logger to print the logs to the console. The global CPU load log prints a percentage. For example:

  ```
  LS_cpuLoad: 10
  ```

  The global Swi and Hwi load logs print two numbers: the time in the thread, and the length of the measurement window. For example:

  ```
  LS_hwiLoad: 13845300,158370213
  LS_swiLoad: 11963546,158370213
  ```

  These evaluate to loads of 8.7% and 7.6%.

  The Task load log uses the same format, with the addition of the Task handle address as the first argument. For example:

  ```
  LS_taskLoad: 0x11802830,56553702,158370213
  ```

  This evaluates to a load of 35.7%.

- **Runtime APIs.** You can also choose to call Load_getTaskLoad(), Load_getGlobalSwiLoad(), Load_getGlobalHwiLoad() or Load_getCPULoad() at any time to obtain the statistics at runtime.

  The Load_getCPULoad() API returns an actual percentage load, whereas Load_getTaskLoad(), Load_getGlobalSwiLoad(), and Load_getGlobalHwiLoad() return a Load_Stat structure. This structure contains two fields, the length of time in the thread, and the length of time in the measurement window. The load percentage can be calculated by dividing these two numbers and multiplying by 100%. However, the Load module also provides a convenience function, Load_calculateLoad(), for this purpose. For example, the following code retrieves the Hwi Load:

  ```
  Load_Stat stat;
  UInt32 hwiLoad;

  Load_getGlobalHwiLoad(&stat);

  hwiLoad = Load_calculateLoad(&stat);
  ```

7.3 Real-Time Analysis Tools in CCS v4.x

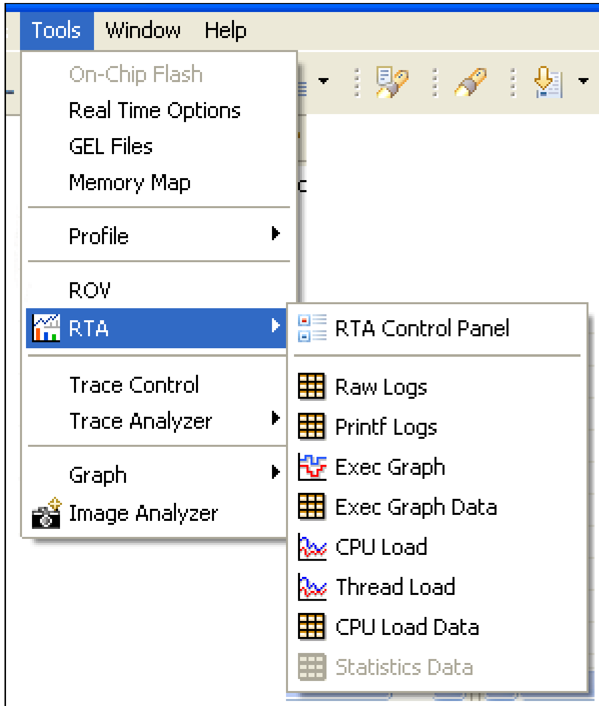
DSP/BIOS 6 supports a number of Real-Time Analysis (RTA) tools that are provided in Code Composer Studio v4.x. These tools provides raw log information as well as execution and load graphs in real-time (while the target is running) or stop mode (while the target is halted).

The subsections that follow briefly introduce the RTA tools.

In order to use RTA tools, your application must be configured to include support for RTA. DSP/BIOS 6 includes an RTA "Agent" module, ti.sysbios.rta.Agent, which retrieves Log data from the target and sends it to the host. See Section 7.4 for details on configuring RTA support.

You may open RTA tools in CCS at any time, typically just before running the target application or while the application is running.

To open the tool, choose **Tools > RTA** from the CCS menu bar. This shows a list of the available graphs and tables provided for real-time analysis.

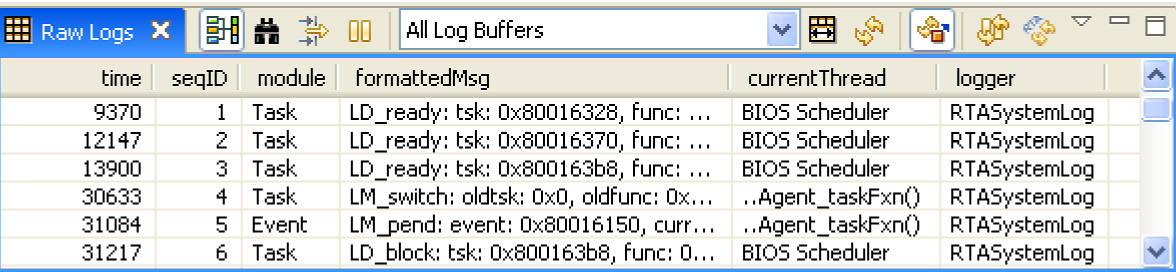


In addition to the RTA tools, the Runtime Object Viewer (ROV) is a stop-mode debugging tool provided by XDCtools. You can use ROV with DSP/BIOS applications to see state information about all the modules in your application. For information, see the RTSC-pedia page on ROV at http://rtsc.eclipse.org/docs-tip/RTSC_Object_Viewer.

7.3.1 Raw Logs

By default, the Raw Logs tool displays complete unformatted log data. The default columns displayed are: time, seqID, module, formattedMsg, currentThread, and logger.

You can open this tool by choosing **Tools > RTA > Raw Logs** from the CCS menu bar.



time	seqID	module	formattedMsg	currentThread	logger
9370	1	Task	LD_ready: tsk: 0x80016328, func: ...	BIOS Scheduler	RTASystemLog
12147	2	Task	LD_ready: tsk: 0x80016370, func: ...	BIOS Scheduler	RTASystemLog
13900	3	Task	LD_ready: tsk: 0x800163b8, func: ...	BIOS Scheduler	RTASystemLog
30633	4	Task	LM_switch: oldtsk: 0x0, oldfunc: 0x...	..Agent_taskFxn()	RTASystemLog
31084	5	Event	LM_pend: event: 0x80016150, curr...	..Agent_taskFxn()	RTASystemLog
31217	6	Task	LD_block: tsk: 0x800163b8, func: 0...	BIOS Scheduler	RTASystemLog

This table displays all the log records that have been sent from the target. This contains all the records used by the RTA tools to populate their graphs and tables. In addition, the following types of logs are also shown:

- Any Log records from other modules
- Any user-defined Logs or Log_print*() calls

This tool contains the following toolbar icons:

Toggle **View With Group** setting on and off. (Shift+G)

Open the **Find** In dialog for searching this log.

Filter the log records to match a pattern by using the Set Filter Expression dialog.

Freeze Data Updates from the target. This is useful when you are using the Find or Filter dialogs. (Shift+F5)

All Log Buffers — Choose the type of log messages you want listed.

Auto Fit Columns sets the column widths to fit their current contents.

Refresh the GUI displays. This button does not collect data from the target.

Stream RTA Data toggles the collection of RTA data at runtime. The default is on if the application is configured to use RTDX. Changing the setting of this toggle affects the setting in all RTA tools.

Toggle Autorefresh Mode is available only when the target is stopped. Toggling this icon on causes the RTA tools to collect stop mode data from the target once per target halt. Changing the setting of this toggle affects the setting in all RTA tools. This mode is on by default.

Refresh RTA Buffers in Stop Mode is available only when the target is stopped, and only when the Autorefresh Mode toggle is off. Clicking this icon causes the RTA tools to collect stop mode data from the target one time.

See Section 7.4.2 and Section 7.4.3 for more about using the , , and icons.

"Groups" in the RTA views refers to synchronizing the views so that moving around in one view causes similar movement to happen automatically in another. For example, if you group the CPU load graph with Raw Logs, then if you click on the CPU Load graph, the Raw Log displays the closest record to where you clicked in the graph.

You can right-click on this tool to choose from a menu of options. In addition to some of the toolbar commands, you can use the following additional commands from the right-click menu:

❏ **Column Settings.** This command opens a dialog that lets you hide or display various columns. You can also change the alignment, font, and display format of a column (for example, decimal, binary, or hex).

❏ **Copy.** This command copies the selected text to the clipboard.

❏ **Enable Auto Scroll.** This command allows the log to scroll automatically as new data is available.

❏ **Data > Export Selected.** This command lets you select a .csv (comma-separated value) file to contain the selected data.

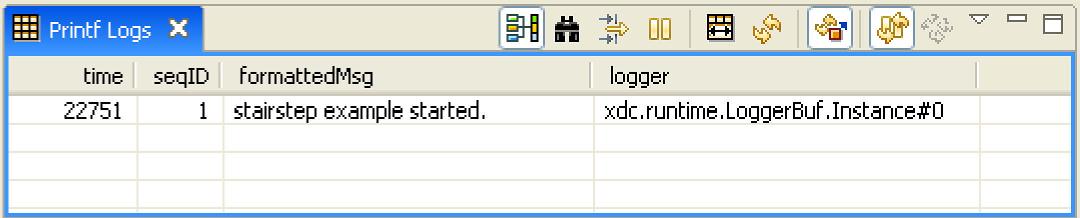
❏ **Data > Export All.** This command lets you select a .csv (comma-separated value) file to contain all the data currently displayed in the log.

❏ **Groups.** This command lets you define groups to contain various types of log messages.

7.3.2 Printf Logs

The Printf Log is a convenient way to view all the user-generated trace and printf logs. By default, the Printf Log tool displays the time, seqID, formattedMsg, and logger.

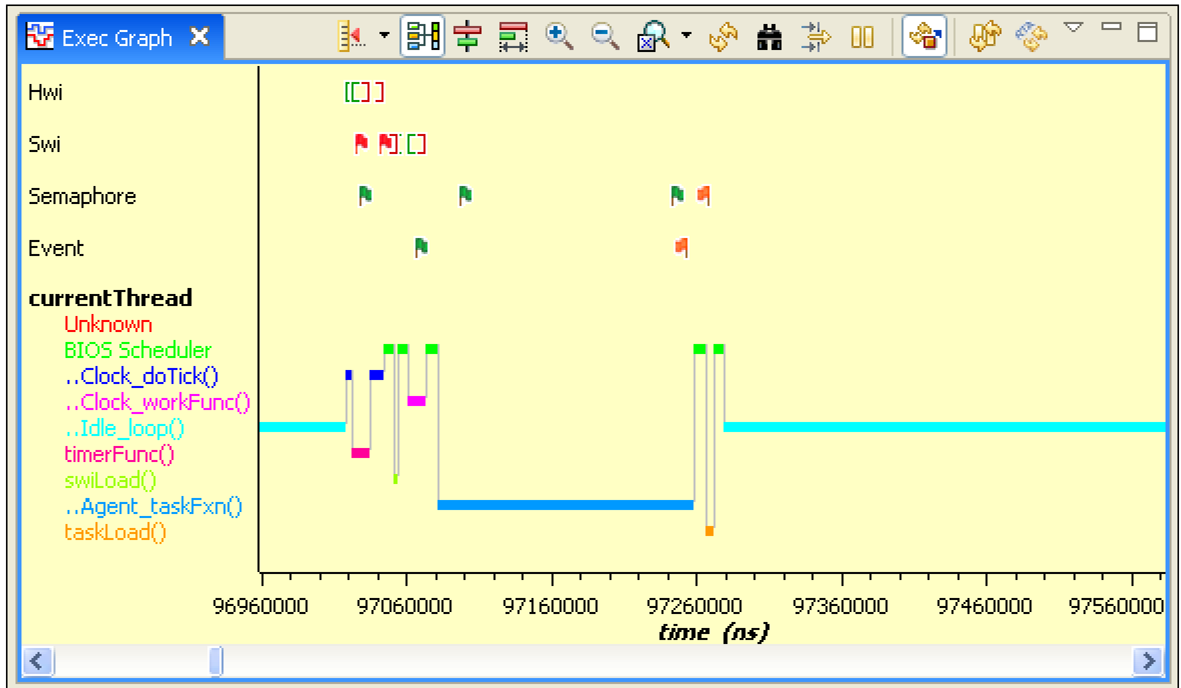
You can open this tool by choosing **Tools > RTA > Printf Logs** from the CCS menu bar.



The toolbar icons and right-click menu for the Printf Logs tool are the same as for the Raw Logs tool (Section 7.3.1).

7.3.3 Exec Graph

The Exec Graph shows which thread is running at a given time. You can open this tool by choosing **Tools > RTA > Exec Graph** from the CCS menus.



In this graph, square brackets “[ ]” indicate the beginning and end of Hwi and Swi threads.

Red flags facing right on the Swi timeline indicate Swi post events.

Green flags on the Semaphore and Event timelines indicate “post” events, and red flags facing left indicate “pend” events.

These icons do not indicate which Hwi, Swi, Semaphore, or Event instance the brackets and flags refer to. For this information, group the Exec Graph with the Raw Logs view (they are grouped by default). Then you can click anywhere on the Exec Graph to jump to the corresponding Raw Log record.

This tool contains the following toolbar icons:

Toggle Measurement Marker Mode selects a measuring mode for time marking. The mode choices are "Freeform" or "Snap to Data". The axis choices are X-Axis, Y-Axis, or Both. When you click on the graph, a marker of the type you have selected is placed. When you drag your mouse around the graph, the time is shown in red.

Toggle **View With Group** setting on and off. (Shift+G)

Align Horizontal Center can be used if you have enabled the View With Group toggle. This icon aligns a group by centering.

Align Horizontal Range can be used if you have enabled the View With Group toggle. This icon aligns a group using a horizontal range.

Click this icon to **Zoom In** on the graph by spreading out the x-axis.

Click this icon to **Zoom Out**.

Choose to **Reset Zoom** level to the default or use the drop-down list to choose a specific zoom level.

Refresh the GUI displays. This button does not collect data from the target.

Open the **Find** In dialog for searching this graph.

Filter the log records to match a pattern by using the Set Filter Expression dialog.

Freeze Data Updates data updates from the target. This is useful when you are using the Find or Filter dialogs. (Shift+F5)

Stream RTA Data toggles the collection of RTA data at runtime. The default is on if the application is configured to use RTDX. Changing the setting of this toggle affects the setting in all RTA tools.

Toggle Autorefresh Mode is available only when the target is stopped. Toggling this icon on causes the RTA tools to collect stop mode data from the target once per target halt. Changing the setting of this toggle affects the setting in all RTA tools. This mode is on by default.

Refresh RTA Buffers in Stop Mode is available only when the target is stopped, and only when the Autorefresh Mode toggle is off. Clicking this icon causes the RTA tools to collect stop mode data from the target one time.

See Section 7.4.2 and Section 7.4.3 for more about using the , , and icons.

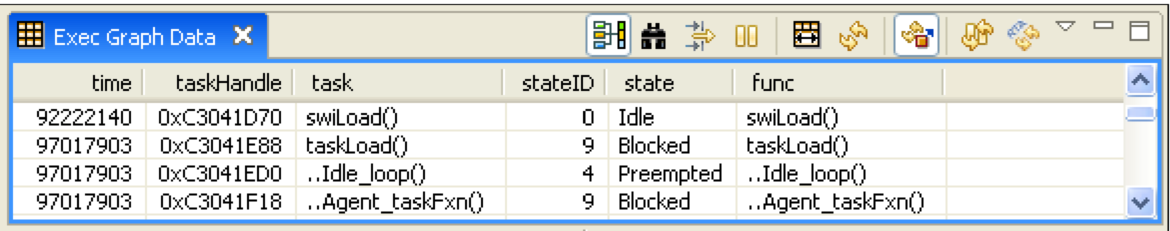
You can right-click on this tool to choose from a menu of options. In addition to some of the toolbar commands, you can use the following additional commands from the right-click menu:

- **Legend.** Toggle this command to hide the graph legend.
- **Horizontal Axis.** Toggle this command to hide the x-axis time markings.
- **Vertical Axis.** Toggle this command to hide the y-axis thread labels.
- **Data > Export All.** This command lets you select a .csv (comma-separated value) file to contain all the data currently displayed in the log.
- **Groups.** This command lets you define groups to contain various types of log messages.
- **Insert Measurement Mark.** Inserts a marker at the location where you right clicked.
- **Remove Measurement Mark.** Lets you select a marker to remove.
- **Remove All Measurement Marks.** Removes all markers you have placed.
- **Display Properties.** Opens a dialog that lets you change the colors, scales, display formats, and labels on the graph.
- **RTA Time Unit.** Choose between displaying units for the x axis in ticks or time (ns).

7.3.4 Exec Graph Data

The Exec Graph Data tool is a convenient way to view all the thread-related logs. By default, the Exec Graph Data tool displays the time, taskHandle, task, stateID, state, and func for each thread-related message.

You can open this tool by choosing **Tools > RTA > Exec Graph Data** from the CCS menu bar.


Exec Graph Data

time	taskHandle	task	stateID	state	func
92222140	0xC3041D70	swiLoad()	0	Idle	swiLoad()
97017903	0xC3041E88	taskLoad()	9	Blocked	taskLoad()
97017903	0xC3041ED0	..Idle_loop()	4	Preempted	..Idle_loop()
97017903	0xC3041F18	..Agent_taskFxn()	9	Blocked	..Agent_taskFxn()

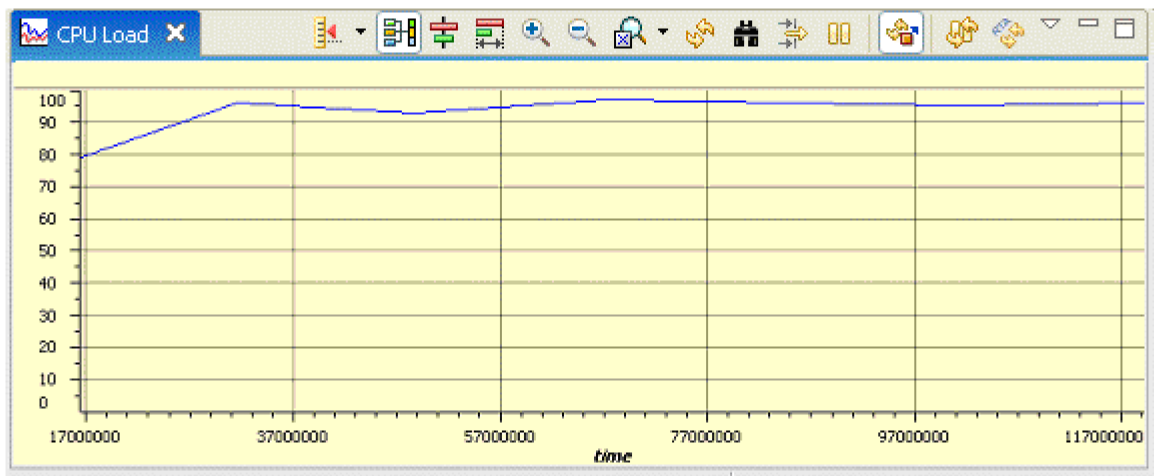
The messages shown in this tool are the raw data used to plot the Exec Graph.

The toolbar icons and right-click menu for the Exec Graph Data tool are the same as for the Raw Logs tool (Section 7.3.1).

7.3.5 CPU Load

The CPU Load tool shows the percentage of time the application is not in the idle loop.

You can open this tool by choosing **Tools > RTA > CPU Load** from the CCS menu bar. See Section 7.2, *Load Module* for details on load statistics.



The CPU Load tool has the same toolbar icons and right-click menu as the Exec Graph tool (Section 7.3.3). However, in addition, the following right-click menu commands are provided:

❑ **Show Grid Lines.** Toggle on or off the x-axis and y-axis grid lines you want to see.

❑ **Display As.** Choose the marker you want to use to display the data. The default is a connected line, but you can choose from various marker styles and sizes.

❑ **Auto Scale.** Scales the load data to fit the range in use. For example, if the range is between 70% and 90%, it zooms in on that range to make changes more visible. When auto scale is turned on, the scale may change as new data arrives.

❑ **Reset Auto Scale.** Resets the scale to better display the current data.

7.3.6 Thread Load

The Thread Load tool shows the percentage of time the application spend in each thread.

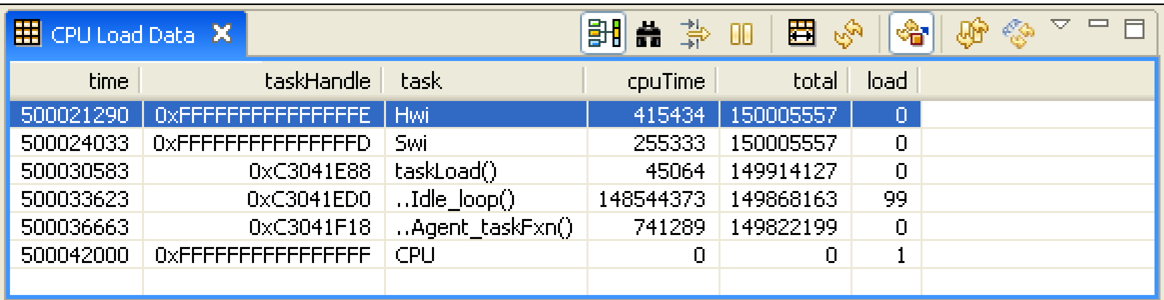
You can open this tool by choosing **Tools > RTA > Thread Load** from the CCS menu bar. See Section 7.2, *Load Module* for details on load statistics.

The toolbar icons and right-click menu for the Thread Load tool are the same as for the Exec Graph tool (Section 7.3.3).

7.3.7 CPU Load Data

The CPU Load Data tool is a convenient way to view CPU load-related logs. By default, the CPU Load Data tool displays the time, taskHandle, task, cpuTime, total, and load for each load-related message.

Open this tool by choosing **Tools > RTA > CPU Load Data** from the CCS menu bar.



time	taskHandle	task	cpuTime	total	load
500021290	0xFFFFFFFFFFFFFFFE	Hwi	415434	150005557	0
500024033	0xFFFFFFFFFFFFFFFD	Swi	255333	150005557	0
500030583	0xC3041E88	taskLoad()	45064	149914127	0
500033623	0xC3041ED0	..Idle_loop()	148544373	149868163	99
500036663	0xC3041F18	..Agent_taskFxn()	741289	149822199	0
500042000	0xFFFFFFFFFFFFFFFF	CPU	0	0	1

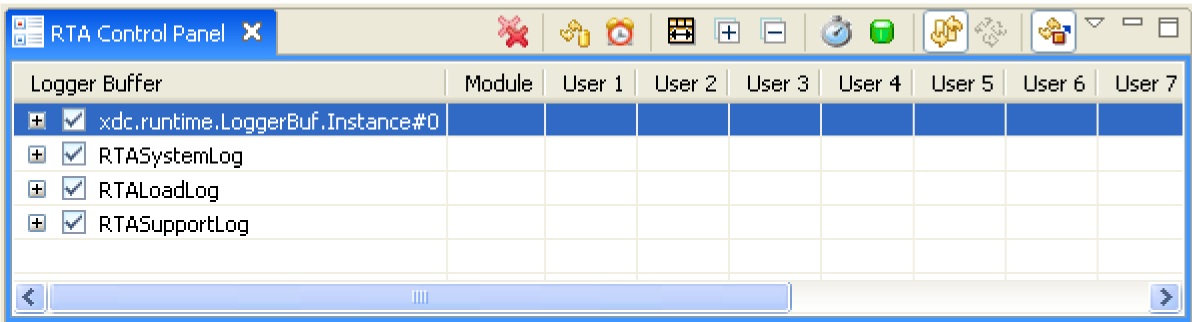
The messages in this tool are raw data used to plot the CPU Load graph.

The toolbar icons and right-click menu for the Load Data tool are the same as for the Raw Logs tool (Section 7.3.1).

7.3.8 RTA Control Panel

The RTA Control Panel provides access to some general RTA settings and gives you control over which Log events are logged on the target.

You can open this panel by choosing **Tools > RTA > RTA Control Panel** from the CCS menu bar.



The RTA Control Panel contains the following toolbar icons:

Close All RTA Views, including this one.

Refresh Runtime Configuration information gets the current runtime settings for this tool from the target application.

RTA Update Rate sets the minimum wait time between attempts for the Task that collects RTA information and sends it to the host. In practice, the time may be longer than what you specify if the Task needs to wait to run because its priority is lower than that of other threads.

Auto Fit Columns sets the column widths to fit their current contents.

Expand All nodes in the Logger Buffer column.

Collapse All nodes in the Logger Buffer column.

Duration for RTA Streaming sets how long data is sent from the target to the host computer. The duration is in minutes. The default is to stream as long as the target application is running.

Disk Usage Quota is the amount of disk space on the host computer available to the RTA tools for temporary data storage. The default is 2 GB. This button will take you to the CCS Preferences dialog to set the size and location of these temporary files.

Toggle Autorefresh Mode is available only when the target is stopped. Toggling this icon on causes the RTA tools to collect stop mode data from the target once per target halt. Changing the setting of this toggle affects the setting in all RTA tools.

Refresh RTA Buffers in Stop Mode is available only when the target is stopped, and only when the Autorefresh Mode toggle is off. Clicking this icon causes the RTA tools to collect stop mode data from the target one time.

Stream RTA Data toggles the collection of RTA data at runtime. The default is on if the application is configured to use RTDX. Changing the setting of this toggle affects the setting in all RTA tools.

See Section 7.4.2 and Section 7.4.3 for more about using the , , and icons.

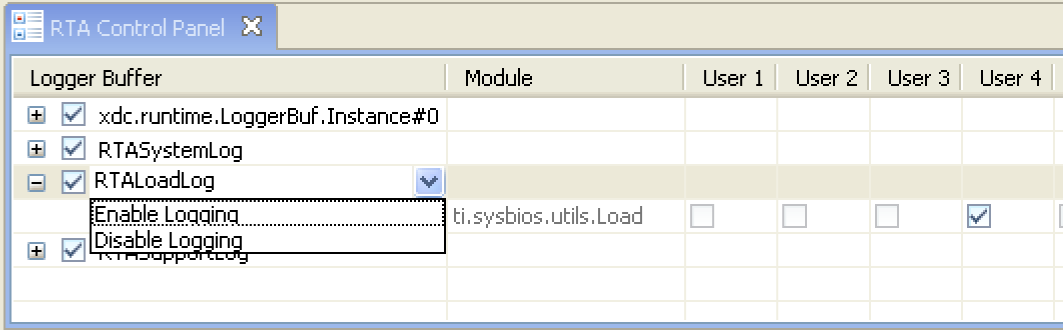
The RTA Control Panel lets you make runtime changes to the types of Log events that are logged on the target. This allows you to make better use of limited buffer sizes and transport bandwidth and to focus on the events that are currently important to you.

The RTA Control Panel provides control over logging in two ways:

- You can enable or disable particular LoggerBuf instances
- You can enable or disable specific Diags levels on a per-module basis.

The RTA Control Panel lists the LoggerBuf instances in the left column. If a name was given to the instance, that name is shown. Otherwise, a LoggerBuf instance is labeled with its address.

Click on a LoggerBuf instance name to see a drop-down menu that allows you to enable or disable that instance. Disabling a LoggerBuf instance means that when the target calls Log_write() or Log_print() to that LoggerBuf, the record will not actually be written into the buffer—any record written to a disabled LoggerBuf is discarded.



Expanding a LoggerBuf instance shows you the list of modules that are logging to that buffer. For each module you can see the current Diags settings for that module (See http://rtsc.eclipse.org/cdoc-tip/xdc/runtime/Diags.html for an explanation of Diags levels and settings). If the checkmark or checkbox is gray, that item is configured as ALWAYS_ON or ALWAYS_OFF.

If a particular Diags level is configured as "RUNTIME_OFF" or "RUNTIME_ON", then you can enable or disable that particular Diags level for a given module. Click on the Diags setting to see a drop-down menu that lets you to turn the level on or off. (You may need to make the columns wider before you can open the drop-down list of settings.)

Note: Modifying log settings requires a data transport. Changing settings in the RTA Control Panel is not possible if your configuration sets the Agent.transport property to Agent.Transport_STOP_MODE_ONLY.

If you know you will never be interested in receiving a particular set of events, you may want to disable them in your application's configuration by setting them to ALWAYS_OFF. (If your configuration uses the Agent module to

automatically configure logging, you can still change individual Diags levels, and your settings will override those of the Agent. See http://rtsc.eclipse.org/docs-tip/Using_xdc.runtime_Logging for information.)

If you used the RTA Agent to configure system logging for your application, you should see three LoggerBuf instances whose labels begin with "RTA":

- **RTASystemLog** is a large buffer that holds all system log records from modules such as Hwi, Swi, Task, Idle, Clock, Event, Semaphore, and Timer. See the documentation for each of these modules for details on the events they log. The RTA tools use User1 and User2 logging for this LoggerBuf.
- **RTALoadLog** is a separate log that holds the Load module records. These records are logged relatively infrequently, but are required to support the CPU and Thread Load graphs. They are sent to a dedicated LoggerBuf instance so that they are not overwritten by other more frequent events. The RTA tools use User4 logging for this LoggerBuf.
- **RTASupportLog** is used internally by RTA. It is used to log a single record when the application starts to provide RTA with the Timestamp frequency so that timestamps can be converted into seconds.

7.4 RTA Agent

This section describes the ti.sysbios.rta.Agent module, which supports the RTA tool in Code Composer Studio 4.x. For information on the RTA tools in CCS 4, see Section 7.3.

The ti.sysbios.rta.Agent module is responsible for transmitting Log records from the target to the host for use by the RTA tool. This is accomplished using a ti.sysbios.knl.Task instance that is periodically awoken to send all the Log records to the host.

The RTA Agent operates on each of the xdc.runtime.LoggerBuf instances in the system in turn. It transmits all available Log records from a given LoggerBuf to the host before servicing the next LoggerBuf instance. In the event that records are being written to a LoggerBuf faster than they are being read, the Agent sends a limited number of records (roughly the size of the LoggerBuf) before moving on to the next LoggerBuf.

The RTA Agent is designed to work with a number of transports, such as TCP/IP, RTDX, or in stop-mode. Configuring the transport is your responsibility, since the transport may be configured for other purposes besides RTA.

7.4.1 Configuring the RTA Agent and RTDX

You can use the following code as a template for a simple configuration of RTA support using RTDX as the transport:

```
/* Bring in and configure the RTA Agent */
var Agent = xdc.useModule('ti.sysbios.rta.Agent');

/* Have the Agent auto-configure RTDX */
Agent.transport = Agent.Transport_RTDX;
```

Alternately, you can set the transport to Transport_USER (if your application has a custom data gathering setup) or Transport_STOP_MODE_ONLY.

Older configuration examples use significantly more statements to configure RTDX. These are no longer needed if you set the Agent.transport property.

In the configuration editor, you can examine the properties of the ti.sysbios.rta.Agent and ti.rtdx.RtdxModule modules. For example, the following statement sets the priority of the Task used by the Agent to collect log information to a higher priority than an example Task called "taskLoadTask".

```
Agent.priority = taskLoadTask.priority + 1;
```

The following statement sets the size of the buffer used to hold log messages before transferring them to the host:

```
Agent.numSystemRecords = 2048;
```

For more examples of statements used to configure the Agent, create a CCS project and use the "RTA Example" template.

By default, the target is expected to be a hardware target with a JTAG connection to the host. If your target is a simulator, your configuration should include the following lines:

```
var RtdxModule = xdc.useModule('ti.rtdx.RtdxModule');
RtdxModule.protocol = RtdxModule.PROTOCOL_SIMULATION;
```

7.4.2 Getting Log Data from a Running Target

If you set the Agent.transport property to Transport_RTDX, you can get RTA information either at runtime or in Stop Mode (see Section 7.4.3).

When you use Transport_RTDX, the RTA Agent creates a Task thread in the target application. That thread gathers all the log records stored in the different LoggerBuf instances on the target.

If the icon is toggled on in the RTA tools, the Agent sends these records to the host over RTDX automatically. This means that in order for records to be collected and sent to the host via the Agent, the target must be running.

When the target halts, the RTA tools show all the records that the RTA Agent has sent thus far. This typically doesn't include the most recent records, though, since those haven't been collected and sent yet. This may be a problem if you need to see the most recent messages for debugging purposes. This problem is the reason for also supporting Stop Mode updates.

7.4.3 Getting Log Data from a Halted Target

When the target is halted, you can get RTA information from the target (in Stop Mode) if you set the Agent.transport property to either Transport_RTDX or Transport_STOP_MODE_ONLY.

If you set the Agent.transport property to Transport_STOP_MODE_ONLY, the Agent's Task thread for gathering log records is not created, and you can use the RTA tools in Stop Mode but not in Run Mode.

When you use a Stop Mode refresh, the RTA tools read the memory locations of the LoggerBufs on the halted target to get all the log records and add them to the RTA tool displays.

The icon toggles whether an auto-refresh of Stop Mode data happens when the target halts. This auto-refresh is on by default. However, reading the target's LoggerBuf buffers via the host can be slow, especially for larger buffer sizes, so you may not always want to use this Auto-Refresh capability.

The RTA tools do not show whether they are still collecting data when the target is halted. You can find out how long it takes to collect the LoggerBuf records for your application by opening the ROV tool, moving to the xdc.runtime.LoggerBuf module, and choosing the Records tab. The data acquisition time for these records in the ROV tool should be the same as the time needed to refresh the RTA tools in Stop Mode.

If the update takes a long time for your application, you can use the icon to manually trigger a refresh when the target halts and you want to see the latest data in the target's LoggerBufs.

7.4.4 Automatic System Logging Configuration

By default, the Agent module automatically configures logging for all the modules needed by the RTA tool. The RTA tool expects all logs from the following modules to be logged to a single LoggerBuf instance with the instance name "RTASystemLog":

- ti.sysbios.knl
  - Clock
  - Idle
  - Swi
  - Task
- ti.sysbios.ipc
  - Event
  - Semaphore
- ti.sysbios.family.*
  - Hwi
  - Timer
- ti.sysbios.utils
  - Load

For all of these modules except Load, the Agent sets diags_USER1 and diags_USER2 to RUNTIME_ON. For the Load module, it sets diags_USER4 to RUNTIME_ON.

To change any of these settings (for example, to set the diags to ALWAYS_ON), set Agent.configureSystemLog to false and perform the configuration manually. To perform the configuration manually, create a LoggerBuf instance and give it the instance name "RTASystemLog". Ensure that all of the above modules log to this "RTASystemLog" LoggerBuf.

7.5 Performance Optimization

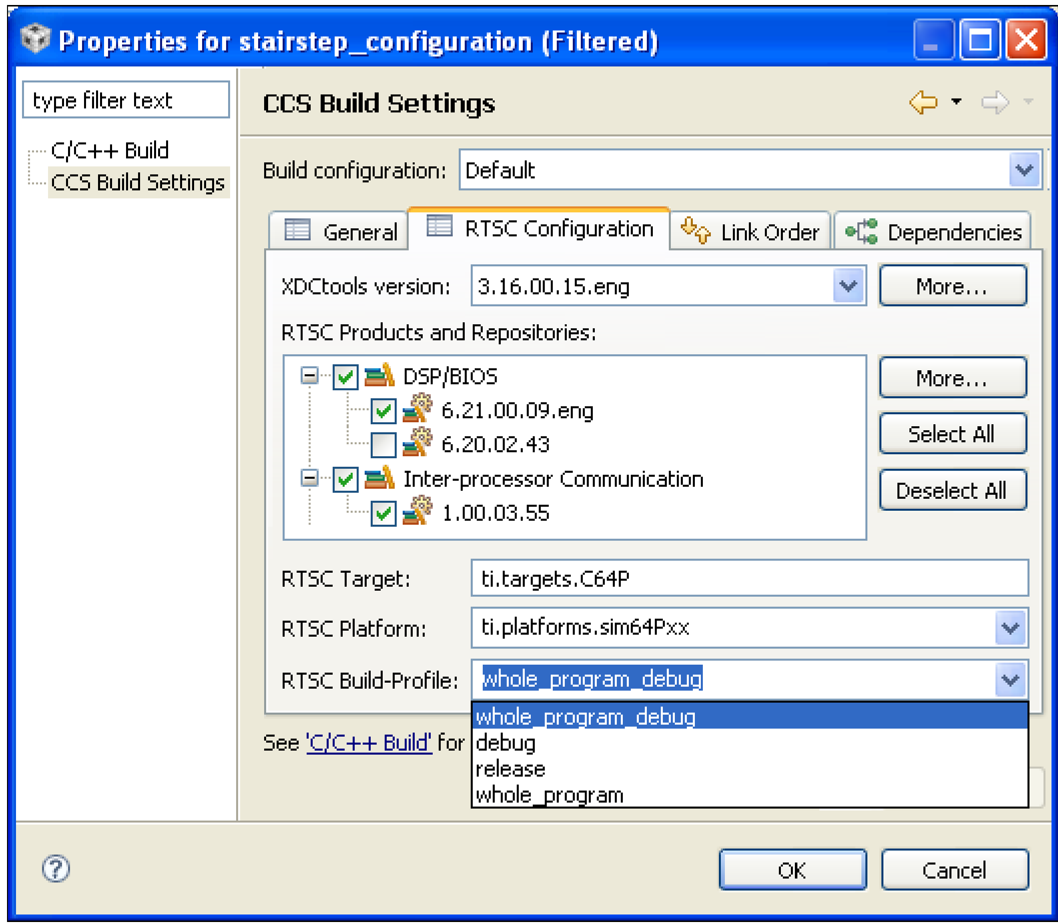
This section provides tips and suggestions for optimizing the performance of a DSP/BIOS-based application. This is accomplished in two ways: by using compiler and linker optimizations, and by optimizing the configuration of DSP/BIOS.

7.5.1 Whole-Program Optimization

Whole-program optimization is a compiler optimization technique that enables the compiler to look across multiple source files when generating object code.

This optimization is central to the promise of RTSC's ability to provide flexibility during configuration without sacrificing system performance. Given an application's configuration, RTSC generates a C file that contains many initialized constants and small code fragments (often "glue" code). Using whole-program optimization, all of these items will typically be removed from the final executable image through classic optimizations such as constant folding and function inlining. Whole-program optimization allows this to occur across independent module boundaries.

Whole-program optimization increases the time to build an application, but improves the application's performance dramatically. To build a configuration project with whole-program optimization, choose "whole_program" or "whole_program_debug" in the RTSC Build-Profile field of the RTSC Configuration tab of the CCS Build Settings dialog.



The "whole_program_debug" profile preserves enough debug information to make it still possible to step through the optimized code in CCS and locate global variables. In DSP/BIOS performance benchmark testing, applications compiled with "whole_program_debug" have been found to have performance that matches that of "whole_program", so it is recommended that you use whole_program_debug.

7.5.2 Configuring Logging

Logging can significantly impact the performance of a system. You can reduce the impact of logging by optimizing the configuration. There are two main ways to optimize the logging used in your application:

- ❑ **No logging.** In DSP/BIOS, logging is not enabled by default. However, if you enable the ti.sysbios.rta.Agent module as described in Section 7.4.1, logging is performed for all DSP/BIOS system modules. To configure your application without logging support, do not enable the RTA Agent, and no logging will occur by default.
- ❑ **Optimizing logging.** If you need some logging enabled in your application, there are some configuration choices you can make to optimize performance. These are described in the following subsections.

7.5.2.1 Diags Settings

There are four diagnostics settings for each diagnostics level: RUNTIME_OFF, RUNTIME_ON, ALWAYS_OFF, and ALWAYS_ON.

The two runtime settings (RUNTIME_OFF and RUNTIME_ON) allow you to enable or disable a particular diagnostics level at runtime. However, a check must be performed to determine whether logging is enabled or disabled every time an event is logged.

If you use ALWAYS_OFF or ALWAYS_ON instead, you will not be able to change the setting at runtime, but the logging call will either be a direct call to log the event (ALWAYS_ON) or will be optimized out of the code altogether (ALWAYS_OFF).

```
var Defaults = xdc.useModule('xdc.runtime.Defaults');
var Diags = xdc.useModule('xdc.runtime.Diags');

/* 'RUNTIME' settings allow you to turn it off or on at runtime,
 * but require a check at runtime. */
Defaults.common$.diags_USER1 = Diags.RUNTIME_ON;
Defaults.common$.diags_USER2 = Diags.RUNTIME_OFF;

/* These settings cannot be changed at runtime, but optimize out
 * the check for better performance. */
Defaults.common$.diags_USER3 = Diags.ALWAYS_OFF;
Defaults.common$.diags_USER4 = Diags.ALWAYS_ON;
```

7.5.2.2 Choosing Diagnostics Levels

DSP/BIOS modules only log to two levels: USER1 and USER2. They follow the convention that USER1 is for basic events and USER2 is for more detail.

To improve performance, you could only turn on USER1, or turn on USER2 for particular modules only.

Refer to each module's documentation to see which events are logged as USER1 and which are logged as USER2.

7.5.2.3 Choosing Modules to Log

To optimize logging, enable logging only for modules that interest you for debugging.

For example, Hwi logging tends to be the most expensive in terms of performance due to the frequency of hardware interrupts. Two Hwi events are logged on every Clock tick when the Clock's timer expires.

7.5.3 Configuring Diagnostics

By default, ASSERTS are enabled for all modules. DSP/BIOS uses asserts to check for common user mistakes such as calling an API with an invalid argument or from an unsupported context. Asserts are useful for catching coding mistakes that may otherwise lead to confusing bugs.

To optimize performance after you have done basic debugging of API calls, your configuration file can disable asserts as follows:

```
var Defaults = xdc.useModule('xdc.runtime.Defaults');
var Diags = xdc.useModule('xdc.runtime.Diags');

/* Disable asserts in all modules. */
Defaults.common$.diags_ASSERT = Diags.ALWAYS_OFF;
```

7.5.4 Choosing a Heap Manager

DSP/BIOS provides three different heap manager implementations: HeapMem, HeapBuf, and HeapMultiBuf. Each of these has various performance trade-offs when allocating and freeing memory.

HeapMem can allocate a block of any size, but is the slowest of the three. HeapBuf can only allocate blocks of a single configured size, but is very quick. HeapMultiBuf manages a pool of HeapBuf instances and balances the advantages of the other two. HeapMultiBuf is quicker than HeapMem, but slower than HeapMem.

See the documentation for each of these modules for a detailed discussion of the trade-offs of each module.

Consider also using different heap implementations for different roles. For example, HeapBuf is ideally suited for allocating a fixed-size object that is frequently created and deleted. If you were creating and deleting many Task instances, you could create a HeapBuf instance just for allocating Tasks.

7.5.5 Hwi Configuration

The hardware interrupt dispatcher provides a number of features by default that add to interrupt latency. If your application does not require some of these features, you can disable them to reduce interrupt latency.

- **dispatcherAutoNestingSupport.** You may disable this feature if you don't need interrupts enabled during the execution of your Hwi functions.
- **dispatcherSwiSupport.** You may disable this feature if no Swi threads will be posted from any Hwi threads.
- **dispatcherTaskSupport.** You may disable this feature if no APIs are called from Hwi threads that would lead to a Task being scheduled. For example, Semaphore_post() would lead to a Task being scheduled.
- **dispatcherIrpTrackingSupport.** This feature supports the Hwi_getIrp() API, which returns an interrupt's most recent return address. You can disable this feature if your application does not use that API.

7.5.6 Stack Checking

By default, the Task module checks to see whether a Task stack has overflowed at each Task switch. To improve Task switching latency, you can disable this feature the Task.checkStackFlag property to false.

Appendix A

DSP/BIOS Emulation on Windows

This appendix describes DSP/BIOS emulation when using the Microsoft Windows operating system.

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A.2 High-Level Description . . . . A−2
A.3 Clock Rate Considerations. . . . . A−4

A.1 Motivation

You can use DSP/BIOS emulation on Windows to model your DSP/BIOS applications on a high-level operating system before moving to simulators or hardware.

When you are developing a software module, such as a codec, a common practice is to first write a "Golden C" version. Once the software module is functioning properly, the Golden C version is used as a baseline for porting the software to specific target platforms.

When developing the Golden C version, it is often preferable to do this work on a High-Level Operating System (HLOS), such as Windows. This allows the use of HLOS tool-chains for code profiling and validation. Providing a DSP/BIOS Emulation layer that runs on Windows makes this effort more efficient. It allows a native DSP/BIOS application to be built and run as a native Windows executable.

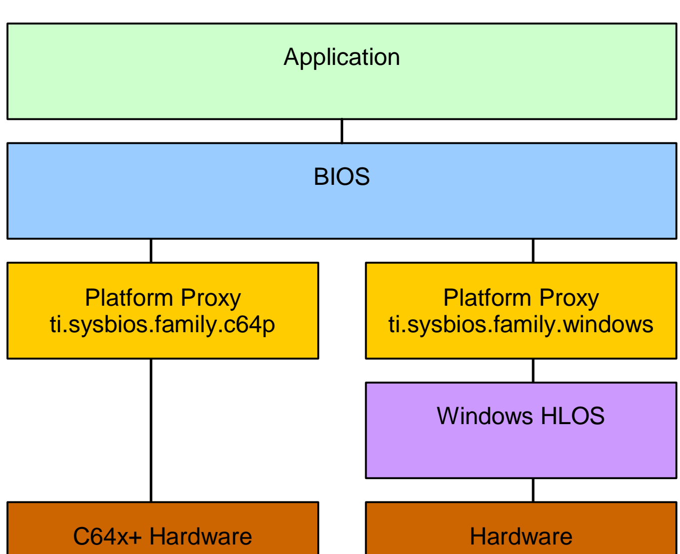
A.2 High-Level Description

DSP/BIOS emulation is supported by implementing the platform proxy modules for Windows. These modules are contained in the ti.sysbios.family.windows package. These proxy modules provide interfaces for the following:

- ❏ hardware interrupts
- ❏ thread context switching
- ❏ general purpose timers
- ❏ system clock tick counter

To implement these interfaces, some hardware functionality is emulated in the proxy modules because Windows does not allow direct access to the hardware.

The following figure shows a block diagram of both a ‘C64x+ implementation and a Windows implementation.



Application code written in C that makes only DSP/BIOS API calls should not require any changes. However, any code written for peripheral control will need to be replaced. Peripherals are not modeled in the emulation package.

The DSP/BIOS Kernel does not require any changes. Through XDCtools configuration, the kernel binds with the appropriate proxy modules relevant to the target platform (that is, for the Windows platform or a hardware platform).

When building the application, XDCtools configuration is used to select the runtime platform. Through configuration options, the application can bind with the appropriate modules that are hardware or emulation specific. This will most likely pertain to peripheral and/or test framework code.

On hardware platforms, peripheral devices typically raise interrupts to the CPU, which then invokes the Hwi dispatcher to service the interrupt. To emulate this behavior, the DSP/BIOS Emulation package simulates an interrupt that preempts the currently running task and invokes the Hwi Dispatcher. This is done asynchronously with respect to DSP/BIOS tasks.

The Windows Emulation package faithfully emulates the DSP/BIOS scheduler behavior. That is to say that task scheduling will occur in the same order on Windows as on hardware. However, interrupts are not real-time. Therefore, interrupt preemption will differ, and this may invoke the scheduler in a different sequence than observed when running on hardware.

Windows Win32 API functions may be invoked along side DSP/BIOS API functions. This should be kept to a minimum in order to encourage code encapsulation and to maximize code reuse between hardware and the Windows platforms.

A.3 Clock Rate Considerations

When running on Windows Emulation, the DSP/BIOS clock is configured to tick much slower. This is necessary because the Windows clock ticks slower than a typical hardware clock. Thus, any code that depends on clock ticks, instead of wall clock duration, should take this into account in the configuration phase.

For example, if Task_sleep(500) is called on a hardware platform where the DSP/BIOS clock ticks every 1 millisecond (resulting in a 500 millisecond sleep period), then it should be normalized for the Windows platform using the following formula:

```
windowsTicks = 500 / (Clock_tickPeriod / 1000)
```

where the Clock_tickPeriod is the DSP/BIOS clock tick period on Windows.

Appendix B

Timing Benchmarks

This appendix describes DSP/BIOS timing benchmark statistics.

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B.1 Timing Benchmarks

This appendix describes the timing benchmarks for DSP/BIOS functions, explaining the meaning of the values as well as how they were obtained, so that designers may better understand their system performance.

The sections that follow explain the meaning of each of the timing benchmarks. The name of each section corresponds to the name of the benchmark in the actual benchmark data table.

The explanations in this appendix are best viewed along side the actual benchmark data. Since the actual benchmark data depends on the target and the memory configuration, and is subject to change, the data is provided in HTML files in the ti.sysbios.benchmarks package (that is, in the BIOS_INSTALL_DIR\packages\ti\sysbios\benchmarks directory).

B.2 Interrupt Latency

The Interrupt Latency benchmark is the maximum number of instructions during which the DSP/BIOS kernel disables maskable interrupts. Interrupts are disabled in order to modify data shared across multiple threads. DSP/BIOS minimizes this time as much as possible to allow the fastest possible interrupt response time.

The interrupt latency of the kernel is measured across the scenario within DSP/BIOS in which maskable interrupts will be disabled for the longest period of time. The measurement provided here is the cycle count measurement for executing that scenario.

B.3 Hwi-Hardware Interrupt Benchmarks

Hwi_enable(). This is the execution time of a Hwi_enable() function call, which is used to globally enable hardware interrupts.

Hwi_disable(). This is the execution time of a Hwi_disable() function call, which is used to globally disable hardware interrupts.

Hwi dispatcher. These are execution times of specified portions of Hwi dispatcher code. This dispatcher handles running C code in response to an interrupt. The benchmarks provide times for the following cases:

- **Interrupt prolog for calling C function.** This is the execution time from when an interrupt occurs until the user's C function is called.
- **Interrupt epilog following C function call.** This is the execution time from when the user's C function completes execution until the Hwi dispatcher has completed its work and exited.

Hardware interrupt to blocked task. This is a measurement of the elapsed time from the start of an ISR that posts a semaphore, to the execution of first instruction in the higher-priority blocked task, as shown in Figure B–1.

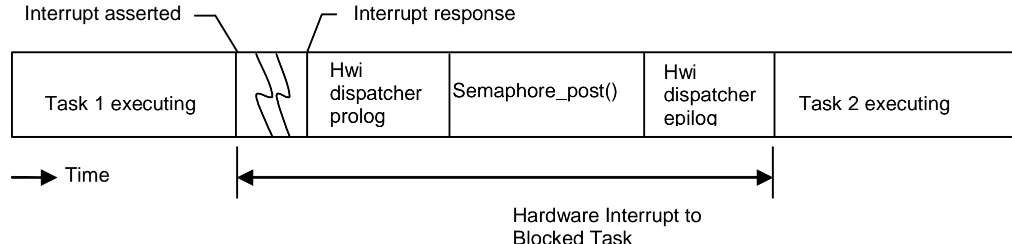

Figure B–1 Hardware Interrupt to Blocked Task

Hardware interrupt to software interrupt. This is a measurement of the elapsed time from the start of an ISR that posts a software interrupt, to the execution of the first instruction in the higher-priority posted software interrupt.

This duration is shown in Figure B–2. Swi 2, which is posted from the ISR, has a higher priority than Swi 1, so Swi 1 is preempted. The context switch for Swi 2 is performed within the Swi executive invoked by the Hwi dispatcher, and this time is included within the measurement. In this case, the registers saved/restored by the Hwi dispatcher correspond to that of "C" caller saved registers.

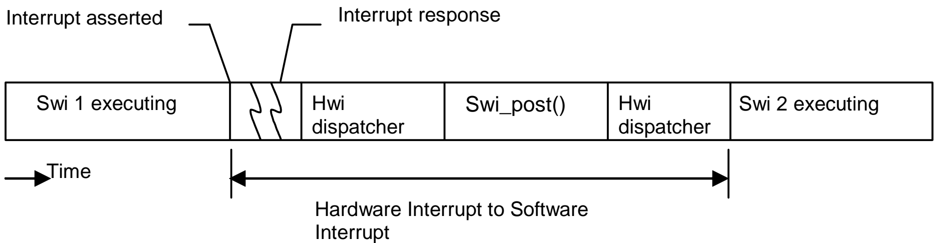

Figure B–2 Hardware Interrupt to Software Interrupt

B.4 Swi-Software Interrupt Benchmarks

Swi_enable(). This is the execution time of a Swi_enable() function call, which is used to enable software interrupts.

Swi_disable(). This is the execution time of a Swi_disable() function call, which is used to disable software interrupts.

Swi_post(). This is the execution time of a Swi_post() function call, which is used to post a software interrupt. Benchmark data is provided for the following cases of Swi_post():

- **Post software interrupt again.** This case corresponds to a call to Swi_post() of a Swi that has already been posted but hasn't started running as it was posted by a higher-priority Swi. Figure B–3 shows this case. Higher-priority Swi1 posts lower-priority Swi2 twice. The cycle count being measured corresponds to that of second post of Swi2.

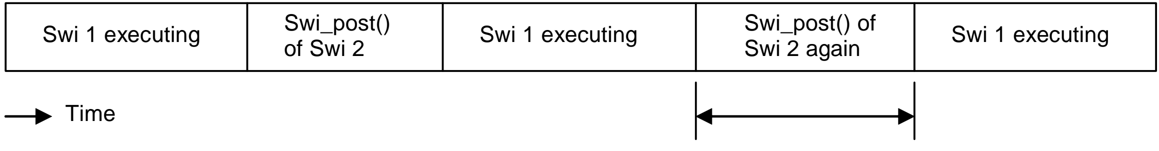

Figure B–3 Post of Software Interrupt Again

- **Post software interrupt, no context switch.** This is a measurement of a Swi_post() function call, when the posted software interrupt is of lower priority then currently running Swi. Figure B–4 shows this case.

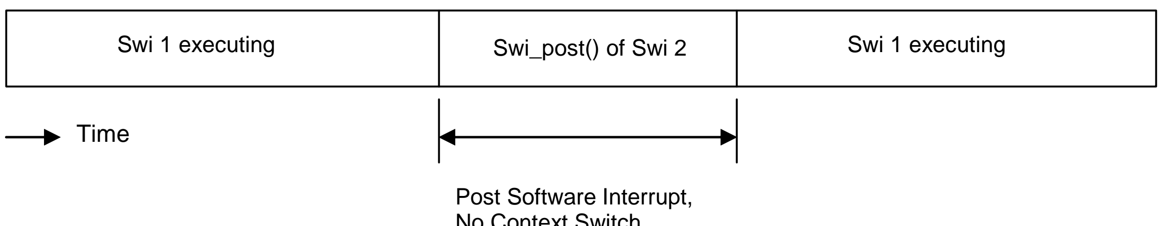

Figure B–4 Post Software Interrupt without Context Switch

- **Post software interrupt, context switch.** This is a measurement of the elapsed time between a call to Swi_post() (which causes preemption of the current Swi) and the execution of the first instruction in the higher-priority software interrupt, as shown in Figure B–5. The context switch to Swi2 is performed within the Swi executive, and this time is included within the measurement.

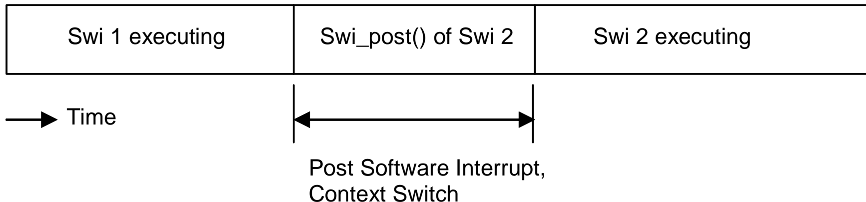

Figure B–5 Post Software Interrupt with Context Switch

B.5 Task Benchmarks

Task_enable(). This is the execution time of a Task_enable() function call, which is used to enable DSP/BIOS task scheduler.

Task_disable(). This is the execution time of a Task_disable() function call, which is used to disable DSP/BIOS task scheduler.

Task_create(). This is the execution time of a Task_create() function call, which is used to create a task ready for execution. Benchmark data is provided for the following cases of Task_create():

- **Create a task, no context switch.** The executing task creates and readies another task of lower or equal priority, which results in no context switch. See Figure B–6.

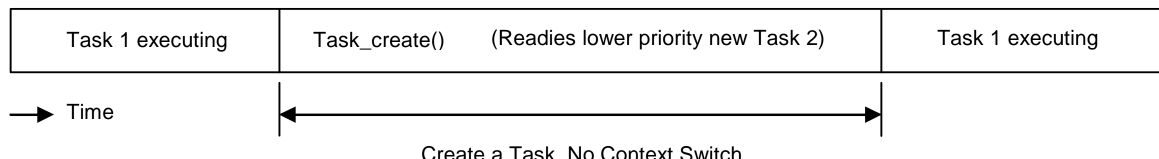

Figure B–6 Create a New Task without Context Switch

- ❑ **Create a task, context switch.** The executing task creates another task of higher priority, resulting in a context switch. See Figure B–7.

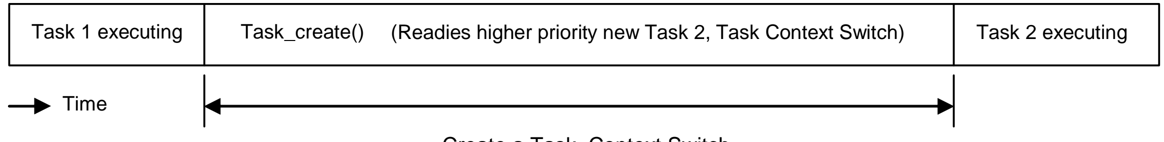

Figure B–7 Create a New Task with Context Switch

Note: The benchmarks for Task_create() assume that memory allocated for a Task object is available in the first free list and that no other task holds the lock to that memory. Additionally the stack has been pre-allocated and is being passed as a parameter.

Task_delete(). This is the execution time of a Task_delete() function call, which is used to delete a task. The Task handle created by Task_create() is passed to the Task_delete() API.

Task_setpri(). This is the execution time of a Task_setpri() function call, which is used to set a task's execution priority. Benchmark data is provided for the following cases of Task_setpri():

- ❑ **Set a task priority, no context switch.** This case measures the execution time of the Task_setpri() API called from a task Task1 as in Figure B–8 if the following conditions are all true:
  - ■ Task_setpri() sets the priority of a lower-priority task that is in ready state.
  - ■ The argument to Task_setpri() is less then the priority of current running task.

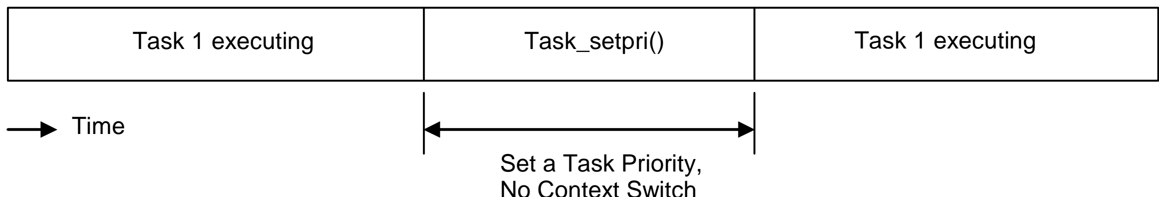

Figure B–8 Set a Task's Priority without a Context Switch

❑ **Lower the current task's own priority, context switch.** This case measures execution time of Task_setpri() API when it is called to lower the priority of currently running task. The call to Task_setpri() would result in context switch to next higher-priority ready task. Figure B–9 shows this case.

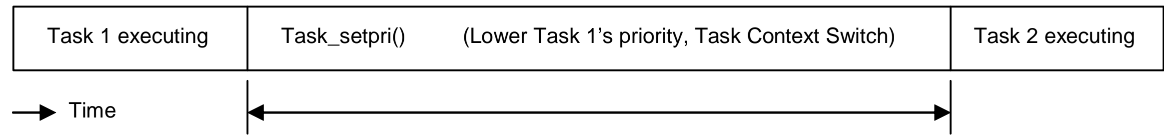

Figure B–9 Lower the Current Task's Priority, Context Switch

❑ **Raise a ready task's priority, context switch.** This case measures execution time of Task_setpri() API called from a task Task1 if the following conditions are all true:

- Task_setpri() sets the priority of a lower-priority task that is in ready state.
- The argument to Task_setpri() is greater then the priority of current running task.

The execution time measurement includes the context switch time as shown in Figure B–10.

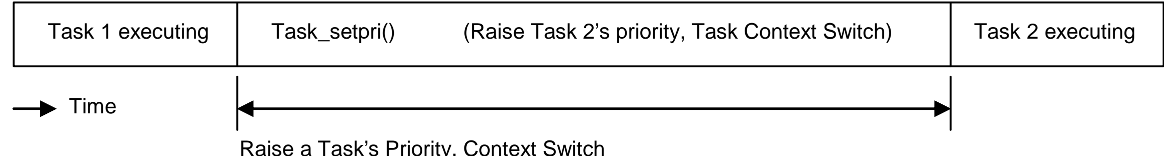

Figure B–10 Raise a Ready Task's Priority, Context Switch

❑ **Task_yield().** This is a measurement of the elapsed time between a function call to Task_yield() (which causes preemption of the current task) and the execution of the first instruction in the next ready task of equal priority, as shown in Figure B–11.

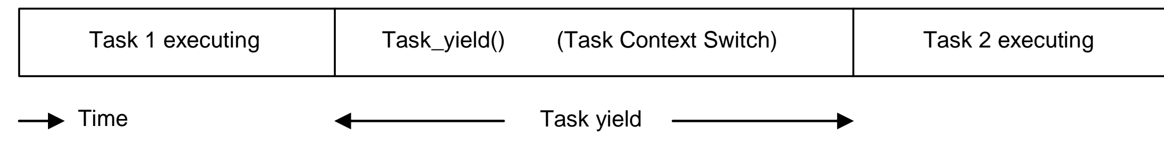

Figure B–11 Task Yield

B.6 Semaphore Benchmarks

Semaphore benchmarks measure the time interval between issuing a Semaphore_post() or Semaphore_pend() function call and the resumption of task execution, both with and without a context switch.

Semaphore_post(). This is the execution time of a Semaphore_post() function call. Benchmark data is provided for the following cases of Semaphore_post():

- **Post a semaphore, no waiting task.** In this case, the Semaphore_post() function call does not cause a context switch as no other task is waiting for the semaphore. This is shown in Figure B–12.

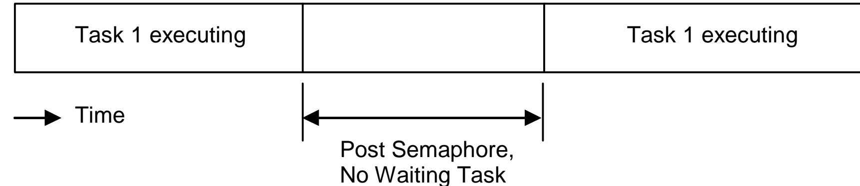

Figure B–12 Post Semaphore, No Waiting Task

- **Post a semaphore, no context switch.** This is a measurement of a Semaphore_post() function call, when a lower-priority task is pending on the semaphore. In this case, Semaphore_post() readies the lower-priority task waiting for the semaphore and resumes execution of the original task, as shown in Figure B–13.

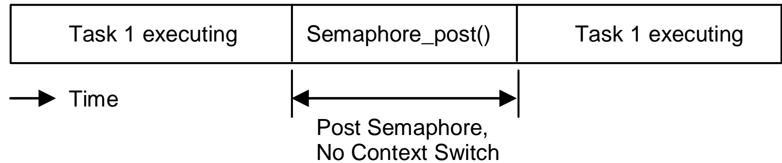

Figure B–13 Post Semaphore, No Context Switch

- **Post a semaphore, context switch.** This is a measurement of the elapsed time between a function call to Semaphore_post() (which readies a higher-priority task pending on the semaphore causing a context switch to higher-priority task) and the execution of the first instruction in the higher-priority task, as shown in Figure B–14.

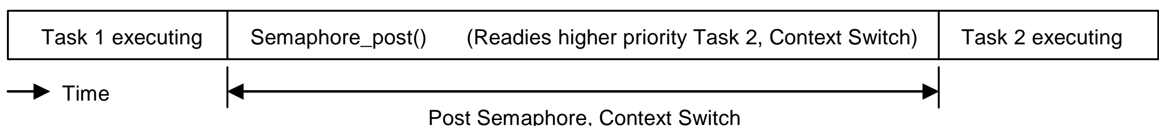

Figure B–14 Post Semaphore with Task Switch

Semaphore_pend(). This is the execution time of a Semaphore_pend() function call, which is used to acquire a semaphore. Benchmark data is provided for the following cases of Semaphore_pend():

- **Pend on a semaphore, no context switch.** This is a measurement of a Semaphore_pend() function call without a context switch (as the semaphore is available.) See Figure B–15.

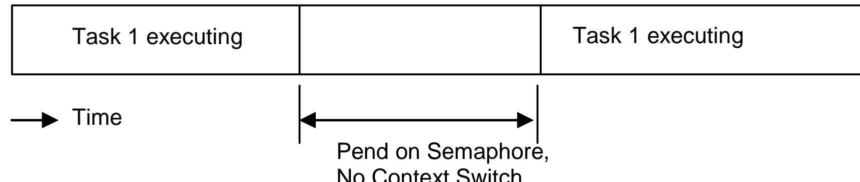

Figure B–15 Pend on Semaphore, No Context Switch

- **Pend on a semaphore, context switch.** This is a measurement of the elapsed time between a function call to Semaphore_pend() (which causes preemption of the current task) and the execution of first instruction in next higher-priority ready task. See Figure B–16.

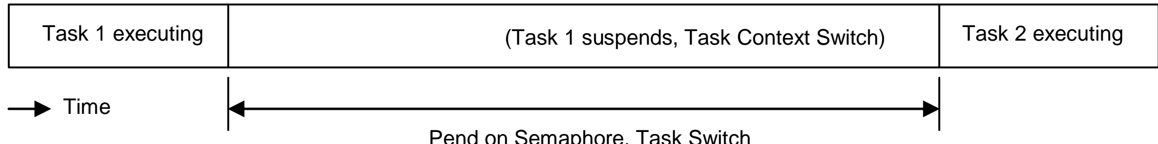

Figure B–16 Pend on Semaphore with Task Switch

Appendix C

Size Benchmarks

This appendix describes DSP/BIOS size benchmark statistics.

Topic	Page
C.1 Overview	C−2
C.2 Comparison to DSP/BIOS 5	C−3
C.3 Default Configuration Sizes	C−4
C.4 Static Module Application Sizes	C−4
C.5 Dynamic Module Application Sizes	C−9
C.6 Timing Application Size	C−9

C.1 Overview

This appendix contains information on the size impact of using DSP/BIOS modules in an application.

Tradeoffs between different DSP/BIOS 6 modules and their impact on system memory can be complex, because applying a module usually requires support from other modules.

Also, even if one module's code is linked in by another module, it does not necessarily link in the entire module, but typically only the functions referenced by the application—an optimization that keeps the overall size impact of the DSP/BIOS 6 kernel to a minimum.

Because of the complexity of these tradeoffs, it is important to understand that this appendix does not provide an analytical model of estimating DSP/BIOS 6 overhead, but rather gives sizing information for a number of DSP/BIOS configurations.

The size benchmarks are a series of applications that are built on top of one another. Moving down Table C–1, each application includes all of the configuration settings and API calls in the previous applications. Applications lower on the table generally require the modules in the applications above them (The Clock module, for example, requires the Hwi module), so this progression allows for measuring the size impact of a module by subtracting the sizes of all of the other modules it depends upon. (The data in the table, however, is provided in absolute numbers.)

The actual size benchmark data is included in the DSP/BIOS 6 installation in the ti.sysbios.benchmarks package (that is, in the BIOS_INSTALL_DIR\packages\ti\sysbios\benchmarks directory). There is a separate HTML file for each target. For example, the ‘C64x sizing information can be found in the c6400Sizing.html file.

For each benchmark application, the table provides four pieces of sizing information, all in 8-bit bytes.

- **Code Size** is the total size of all of the code in the final executable.
- **Initialized Data Size** is the total size of all constants (the size of the .const section).
- **Uninitialized Data Size** is the total size of all variables.
- **C-Initialization Size** is the total size of C-initialization records.

The following sections should be read alongside the actual sizing information as a reference.

C.2 Comparison to DSP/BIOS 5

Where possible, DSP/BIOS 6 size benchmarks have been designed to match the DSP/BIOS 5 benchmarks so that the results can be compared directly. The following table shows which data to compare.

Table C–1 Comparison of Benchmark Applications

DSP/BIOS 5	DSP/BIOS 6
Default configuration	Default configuration
Base configuration	Basic configuration
HWI application	Hwi application
CLK application	Clock application
CLK Object application	Clock Object application
SWI application	Swi application
SWI Object application	Swi Object application
PRD application	None[1]
PRD Object application	None[1]
TSK application	Task application
TSK Object application	Task Object application
SEM application	Semaphore application
SEM Object application	Semaphore Object application
MEM application	Memory application
Dynamic TSK application	Dynamic Task application
Dynamic SEM application	Dynamic Semaphore application
RTA application	None[2]
None[3]	Timing Application

[1] DSP/BIOS 6 does not have a PRD module. Instead, the DSP/BIOS 6 Clock module supports the functionality of both the DSP/BIOS 5 CLK and PRD modules.

[2] The RTA application is not yet implemented for DSP/BIOS 6.

[3] The new benchmark is the application used to generate the timing benchmarks for DSP/BIOS 6 (see Appendix B). This application leverages all of the key components of the operating system in a meaningful way. It does not utilize any of the size-reducing measures employed in the base configuration of the size benchmarks.

C.3 Default Configuration Sizes

There are two minimal configurations provided as base size benchmarks:

- **Default Configuration.** This is the true "default" configuration of DSP/BIOS. The configuration script simply includes the BIOS module as follows:

  ```
  xdc.useModule('ti.sysbios.BIOS');
  ```

  This shows the size of an empty application with everything left at its default value; no attempts have been made here to minimize the application size.

- **Basic Configuration.** This configuration strips the application of all unneeded features and is essentially the smallest possible DSP/BIOS application. Appendix D details tactics used to reduce the memory footprint of this configuration. This is the configuration that the size benchmarks will be built off of.

C.4 Static Module Application Sizes

This section is the focus of the size benchmarks. Each application builds on top of the applications above it in Table C–1.

For each module there are generally two benchmarks. For example, there is the "Clock application" benchmark and the "Clock Object application" benchmark.

The first of the two benchmarks (Clock application) does three things:

1) In the configuration script, it includes the module.
2) In the configuration script, it creates a static instance of the module.
3) In the C code, it makes a call to one of the module's APIs.

The second benchmark (the "object" application) creates a second static instance in the configuration script. This demonstrates the size impact of creating an instance of that object. For example, if the Clock application requires x bytes of initialized data, and the Clock Object application requires y bytes of initialized data, then the impact of one Clock instance is (y - x) bytes of data.

The code snippets for each application apply to all targets, except where noted.

C.4.1 Hwi Application

The Hwi Application configuration script creates a Hwi instance, and the C code calls the Hwi_plug() API.

Configuration Script Addition

```
// Use target/device-specific Hwi module.
var Hwi = xdc.useModule('ti.sysbios.family.c64.Hwi');
var hwi5 = Program.global.hwi5 =
      Hwi.create(5, '&oneArgFxn');
```

C Code Addition

```
Hwi_plug(7, (Hwi_PlugFuncPtr)main);
```

C.4.2 Clock Application

The Clock Application enables the Clock module, creates a Clock instance, and pulls in the modules necessary to call the Timestamp_get32() API in the C code.

Configuration Script Addition

```
var BIOS = xdc.useModule('ti.sysbios.BIOS');
BIOS.clockEnabled = true;

var Clock = xdc.useModule('ti.sysbios.knl.Clock');
Clock.create("&oneArgFxn", 5,
      {startFlag:true,arg:10});

xdc.useModule('xdc.runtime.Timestamp');
```

C Code Addition

```
Timestamp_get32();
```

C.4.3 Clock Object Application

The Clock Object Application statically creates an additional Clock instance to illustrate the size impact of each Clock instance.

Configuration Script Addition

```
Clock.create("&oneArgFxn", 5,
      {startFlag:true,arg:10});
```

C.4.4 Swi Application

The Swi Application enables the Swi module and creates a static Swi instance in the configuration script. It calls the Swi_post() API in the C code.

Configuration Script Addition

```
var BIOS = xdc.useModule('ti.sysbios.BIOS');
BIOS.swiEnabled = true;

var Swi = xdc.useModule('ti.sysbios.knl.Swi');
Program.global.swi0 = Swi.create('&twoArgsFxn');
```

C Code Addition

```
Swi_post(swi0);
```

C.4.5 Swi Object Application

The Swi Object Application creates an additional Swi instance to illustrate the size impact of each new Swi instance.

Configuration Script Addition

```
Program.global.swi1 = Swi.create('&twoArgsFxn');
```

C.4.6 Task Application

The Task Application configuration script enables Tasks and creates a Task instance. It also configures the stack sizes to match the sizes in the DSP/BIOS 5 benchmarks (for comparison).

In the C code, the Task application makes a call to the Task_yield() API.

Configuration Script Addition

```
var BIOS = xdc.useModule('ti.sysbios.BIOS');
BIOS.taskEnabled = true;

var Task = xdc.useModule('ti.sysbios.knl.Task');
Program.global.tsk0 = Task.create("&twoArgsFxn");

Task.idleTaskStackSize = 0x200;
Program.global.tsk0.stackSize = 0x200;
```

C Code Addition

```
Task_yield();
```

C.4.7 Task Object Application

The Task Object Application creates an additional Task instance to illustrate the size impact of each new Task instance.

Configuration Script Addition

```
Program.global.tsk1 = Task.create("&twoArgsFxn");
Program.global.tsk1.stackSize = 0x200;
```

C.4.8 Semaphore Application

The Semaphore Application configuration script creates a Semaphore instance and disables support for Events in the Semaphore for an equitable comparison with the DSP/BIOS 5 SEM module.

In the C code, the Semaphore application makes a call to the Semaphore_post() and Semaphore_pend() APIs.

Configuration Script Addition

```
var Sem = xdc.useModule('ti.sysbios.ipc.Semaphore');
Sem.supportsEvents = false;
Program.global.sem0 = Sem.create(0);
```

C Code Addition

```
Semaphore_post(sem0);
Semaphore_pend(sem0, BIOS_WAIT_FOREVER);
```

C.4.9 Semaphore Object Application

The Semaphore Object Application configuration script creates an additional Semaphore instance to illustrate the size impact of each new Semaphore instance.

Configuration Script Addition

```
Program.global.sem1 = Sem.create(0);
```

C.4.10 Memory Application

The Memory Application configuration script configures the default heap used for memory allocations. It creates a HeapMem instance to manage a 4 KB heap, places the heap into its own section in memory, then assigns the HeapMem instance as the default heap to use for Memory.

In the C code, the Memory application makes calls to the Memory_alloc() and Memory_free() APIs. It allocates a block from the default heap by passing NULL as the first parameter to Memory_alloc(), then frees the block back to the default heap by again passing NULL as the first parameter to Memory_free().

Configuration Script Addition

```
var mem = xdc.useModule('xdc.runtime.Memory');

var HeapMem =
      xdc.useModule('ti.sysbios.heaps.HeapMem');
var heap0 = HeapMem.create();
heap0.sectionName = "myHeap";
Program.sectMap["myHeap"] =
      Program.platform.dataMemory;
heap0.size = 0x1000;

mem.defaultHeapInstance = heap0;
```

C Code Addition

```
Ptr *buf;
buf = Memory_alloc(NULL, 128, 0, NULL);
Memory_free(NULL, buf, 128);
```

C.5 Dynamic Module Application Sizes

The following application demonstrate the size effects of creating object dynamically (in the C code).

C.5.1 Dynamic Task Application

The Dynamic Task Application demonstrates the size impact of dynamically (in the C code) creating and deleting a Task instance. This application comes after the Memory application because it must use the Memory module to allocate space for the new Task instance.

C Code Addition

```
Task_Handle task;
task = Task_create((Task_FuncPtr)main, NULL, NULL);
Task_delete(&task);
```

C.5.2 Dynamic Semaphore Application

The Dynamic Semaphore Application demonstrates the size impact of dynamically (in the C code) creating and deleting a Semaphore instance. This application comes after the Memory application because it must use the Memory module to allocate space for the new Semaphore instance.

C Code Addition

```
Semaphore_Handle sem;
sem = Semaphore_create(1, NULL, NULL);
Semaphore_delete(&sem);
```

C.6 Timing Application Size

The timing application is the application used to generate the timing benchmarks for DSP/BIOS 6 (see Appendix B). This application leverages all of the key components of the operating system in a meaningful way, and does not utilize any of the size-reducing measures employed in the base configuration of the size benchmarks. Therefore, this is the largest application provided as a benchmark.

Appendix D

Minimizing the Application Footprint

This appendix describes how to minimize the size of a DSP/BIOS application.

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D.4 Basic Size Benchmark Configuration Script . . . . D−6

D.1 Overview

This section provides tips and suggestions for minimizing the memory requirements of a DSP/BIOS-based application. This is accomplished by disabling features of the operating system that are enabled by default and by reducing the size of certain buffers in the system.

All of the tips described here are applied to the base configuration for the size benchmarks. The final section of this chapter presents the configuration script used for the base size benchmark.

The actual size benchmark data is included in the DSP/BIOS 6 installation in the ti.sysbios.benchmarks package (that is, in the BIOS_INSTALL_DIR\packages\ti\sysbios\benchmarks directory). There is a separate HTML file for each target. For example, the ‘C64x sizing information can be found in the c6400Sizing.html file.

The following sections simply describe different configuration options and their effect on reducing the application size. For further details on the impact of these settings, refer to the documentation for the relevant modules.

Because the code and data sections are often placed in separate memory segments, it may be more important to just reduce either code size data size. Therefore the suggestions are divided based on whether they reduce code or data size. In general, it is easier to reduce data size than code size.

D.2 Reducing Data Size

D.2.1 Removing the malloc Heap

Calls to malloc are satisfied by a separate heap, whose size is configurable. The following code minimizes the size of this heap. (Some targets do not support a heap size of 0, so this command sets it to 1.)

```
Program.heap = 0x1;
```

The Program variable is automatically available to all scripts. It defines the "root" of the configuration object model. It comes from the xdc.cfg.Program module, and is implicitly initialized as follows:

```
var Program = xdc.useModule('xdc.cfg.Program');
```

D.2.2 Reducing Space for Arguments to main()

A special section in memory is created to store any arguments to the main() function of the application. The size of this section is configurable, and can be reduced depending on the application's needs.

```
Program.argSize = 0x4;
```

D.2.3 Reducing Size of System Stack

The size of the System stack, which is used as the stack for interrupt service routines, is configurable, and can be reduced depending on the application's needs.

```
Program.stack = 0x400;
```

D.2.4 Disabling Named Modules

The space used to store module name strings can be reclaimed with the following configuration setting:

```
var Defaults = xdc.useModule('xdc.runtime.Defaults');
Defaults.common$.namedModule = false;
```

D.2.5 Leaving Text Strings Off the Target

By default, all of the text strings in the system, such as module and instance names and error strings, are loaded into the target's memory. These strings can be left out of the application using the following settings.

```
var Text = xdc.useModule('xdc.runtime.Text');
Text.isLoaded = false;
```

D.2.6 Disabling the Module Function Table

Modules that inherit from an interface (such as GateHwi, which inherits from IGate) by default have a generated function table that is used in supporting abstract handles for instances. For example, an API takes a handle to an IGate as one of its parameters. Because the type of the gate is abstract, it must use a function table to access the module functions for that gate.

If the instances of one of these modules are never used in an abstract way, however, then the function table for the module is unnecessary and can be removed. For example, if none of the GateHwi instances in a

system are ever cast to IGate instances, then the GateHwi function table can be disabled as follows.

```
var GateHwi = xdc.useModule('ti.sysbios.gates.GateHwi');
GateHwi.common$.fxntab = false;
```

D.3 Reducing Code Size

D.3.1 Disabling Logging

Logging can be disabled with the following configuration settings:

```
var Defaults = xdc.useModule('xdc.runtime.Defaults');
var Diags = xdc.useModule('xdc.runtimg.Diags');
Defaults.common$.diags_ASSERT = Diags.ALWAYS_OFF;
```

D.3.2 Setting Memory Policies

The Memory module supports different “memory policies” for creating and deleting objects. If all of the objects in an application can be statically created in the configuration script, then all of the code associated with dynamically creating instances of modules can be left out of the application. This is referred to as a static memory policy.

```
var Defaults = xdc.useModule('xdc.runtime.Defaults');
var Types = xdc.useModule('xdc.runtime.Types');
Defaults.common$.memoryPolicy = Types.STATIC_POLICY;
```

D.3.3 Disabling Core Features

Some of the core features of DSP/BIOS can be enabled or disabled as needed. These include the Swi, Clock, and Task modules.

```
var BIOS = xdc.useModule('ti.sysbios.BIOS');
BIOS.swiEnabled = false;
BIOS.clockEnabled = false;
BIOS.taskEnabled = false;
```

D.3.4 Eliminating printf()

There is no way to explicitly remove printf from the application. However, the printf code and related data structures are not included if the application is free of references to System_printf(). This requires two things:

- ❏ The application code cannot contain any calls to System_printf().
- ❏ The following configuration settings need to be made to DSP/BIOS:

```
var System = xdc.useModule('xdc.runtime.System');
var SysMin = xdc.useModule('xdc.runtime.SysMin');
SysMin.bufSize = 0;
SysMin.flushAtExit = false;
System.SupportProxy = SysMin;

//Remove Error_raiseHook, which brings System_printf
var Error = xdc.useModule('xdc.runtime.Error');
Error.raiseHook = null;
```

See the module documentation for details. Essentially, these settings will eliminate all references to the printf code.

D.3.5 Disabling RTS Thread Protection

If an application does not require the RTS library to be thread safe, it can specify to not use any Gate module in the RTS library. This can prevent the application from bringing in another type of Gate module.

```
var BIOS = xdc.useModule('ti.sysbios.BIOS');
BIOS.rtsGateType = BIOS.NoLocking;
```

D.4 Basic Size Benchmark Configuration Script

The basic size benchmark configuration script puts together all of these concepts to create an application that is close to the smallest possible size of a DSP/BIOS application.

The values chosen for Program.stack and Program.argSize are chosen to match the settings used in generating the DSP/BIOS 5 benchmarks in order to support a fair comparison of the two systems.

This configuration script works on any target.

```
var Defaults = xdc.useModule('xdc.runtime.Defaults');
var System = xdc.useModule('xdc.runtime.System');
var SysMin = xdc.useModule('xdc.runtime.SysMin');
var Error = xdc.useModule('xdc.runtime.Error');
var Text = xdc.useModule('xdc.runtime.Text');
var Types = xdc.useModule('xdc.runtime.Types');
var Diags = xdc.useModule('xdc.runtime.Diags');
var BIOS = xdc.useModule('ti.sysbios.BIOS');
var GateHwi = xdc.useModule('ti.sysbios.gates.GateHwi');
var HeapStd = xdc.useModule('xdc.runtime.HeapStd');
var Memory = xdc.useModule('xdc.runtime.Memory');

//Assumption: app needs SysMin at a minimum,
//but may not use printf, so buf can be zero.
SysMin.bufSize = 0;
SysMin.flushAtExit = false;
System.SupportProxy = SysMin;

//Get rid of Error_raiseHook which brings in
System_printf
Error.raiseHook = null;

//Heap used by malloc is set to zero length.
Program.heap = 0x1;

//arg and stack size made same as BIOS 5.00
Program.argSize = 0x4;
Program.stack = 0x400;

//Logger disabled for benchmarking
Defaults.common$.logger = null;
```

```
//Set isLoaded for Text module
Text.isLoaded = false;

//Set STATIC_POLICY
Defaults.common$.memoryPolicy = Types.STATIC_POLICY;
Defaults.common$.diags_ASSERT = Diags.ALWAYS_OFF;
Defaults.common$.namedModule = false;

BIOS.swiEnabled = false;
BIOS.clockEnabled = false;
BIOS.taskEnabled = false;
BIOS.rtsGateType = BIOS.NoLocking;

//App not using abstract GateHwi instances
GateHwi.common$.fxntab = false;
HeapStd.common$.fxntab = false;
```

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