



Documentation

***X2C v6.3.2018
Free Edition***

August 14, 2020

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Part I

Installation

1 Software versions

Following software versions were tested for full X2C functionality:

Software	Version
<i>Required:</i>	
Scilab (www.scilab.org)	5.5.2
<i>Optional (for standalone operation):</i>	
Java Runtime Environment	Java SE 8 / ojdkbuild 13 JRE
<i>Optional (for documentation):</i>	
MiKTeX (www.miktex.org)	2.9
Doxygen (www.doxygen.org)	1.8.10
Graphviz (www.graphviz.org)	2.38
<i>Optional (for programming):</i>	
Texas Instruments Code Composer Studio	9.x
Texas Instruments Code Generation Tools	c2000_16.9.5.LTS / arm_16.9.4.LTS
Keil μ Vision	5.x
Microchip MPLAB X IDE	5.xx
Microchip Compiler XC16	1.xx

Different versions of these programs may work but without warranty.

2 Setup with *Scilab/Xcos* support

2.1 Installation

1. Open *Scilab/Xcos* and with the *File Browser* navigate to `<X2C_ROOT>\System\Scilab\Scripts`. Right click on **setup.sce** and click *Execute in Scilab*.
2. Restart *Scilab/Xcos*
3. The setup command creates a X2C configuration file which will automatically load X2C libraries and palettes at startup of *Scilab/Xcos*.

2.2 Uninstallation

1. Open *Scilab/Xcos* and execute the command `initX2C(%f)` in the *Scilab/Xcos* console.
2. Restart *Scilab/Xcos*
3. Once above command was executed, the X2C configuration file is deleted and *Scilab/Xcos* will not load any X2C libraries or palettes anymore.

For the unlikely event that Scilab freezes at startup and remains in a deadlock state, the deinstallation can be done manually by deleting the file **scilab.ini** located in the Scilab home directory (for Windows typically `C:\Users\<your user name>\AppData\Roaming\Scilab\scilab-5.x.x`).

3 Setup of Java for standalone operation

In X2C standalone operation, this means only X2C Communicator and Scope are to be used, installation and setup of Scilab is not necessary. However, a Java runtime environment is required.

The recommended Java software is OpenJDK. The ojdkbuild project provides, inter alia, Microsoft Windows Installer (MSI) files by using the source code of OpenJDK.

Following setup steps are required to setup ojdkbuild for X2C :

1. Download the appropriate MSI installer from the website (the file name starts with 'java-13-openjdk-jre')
2. Run the installer
3. When the installer reaches the 'Custom Setup' step, be sure the following additional options are enabled/selected:
 - (a) Click on the small 'plus' symbol next to the 'OpenJDK JRE' icon to show the list of available options

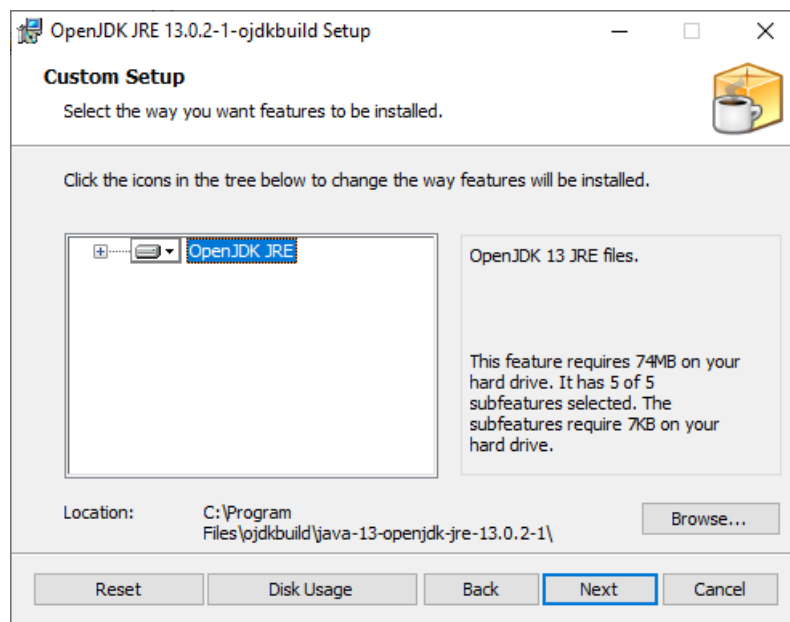


Figure 1: Setup Options

- (b) Ensure these options are enabled:
 - Windows Registry
 - PATH Variable
 - JAVA_HOME Variable
 - JAR Files Association

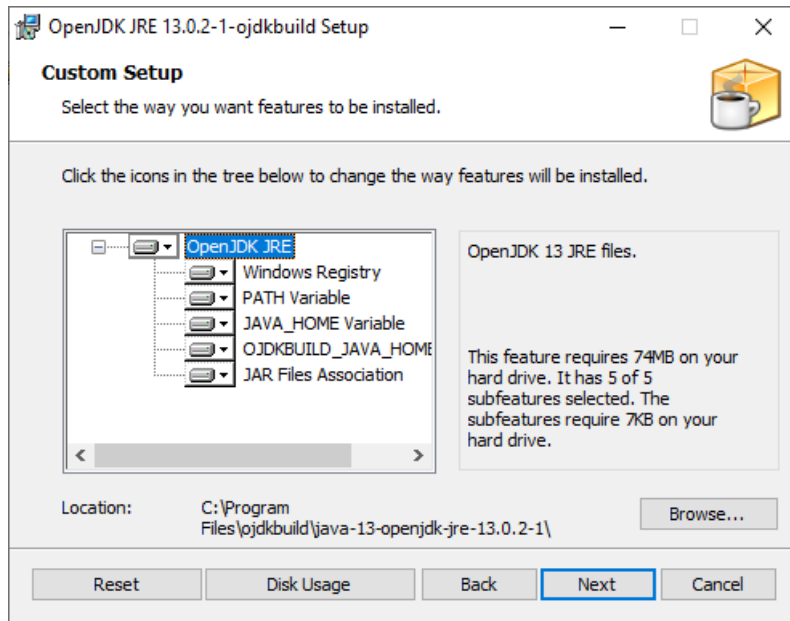


Figure 2: Selected Setup Options

4. Wait for the installer to complete

You may check the successful Java setup by running the X2C Communicator. A double click on the 'Communicator.jar' file in the <X2C ROOT>\System\Java directory should open the Communicator application.

4 Configuration of *Code Composer Studio*

4.1 Install the TI v16.9.5 compiler

It is necessary to use the compiler version TI v16.9.5 in *Code Composer Studio* in combination with *X2C*. Navigate to **Project** → **Properties** click **General** and in the **Advanced settings** area see what compiler versions are available. It is necessary to use the compiler version **TI v16.9.5**. If this version is not selectable go to **Help** → **Install new Software** and in the **Work with** drop down menu choose **Code Generation Tools Update**. In the section **TI Compiler Updates** find *C2800 Compiler Tools Version 16.9.5* and mark it as seen in Figure 3. Click **Next** and install the update. Now go back to the Project Properties and change the compiler.

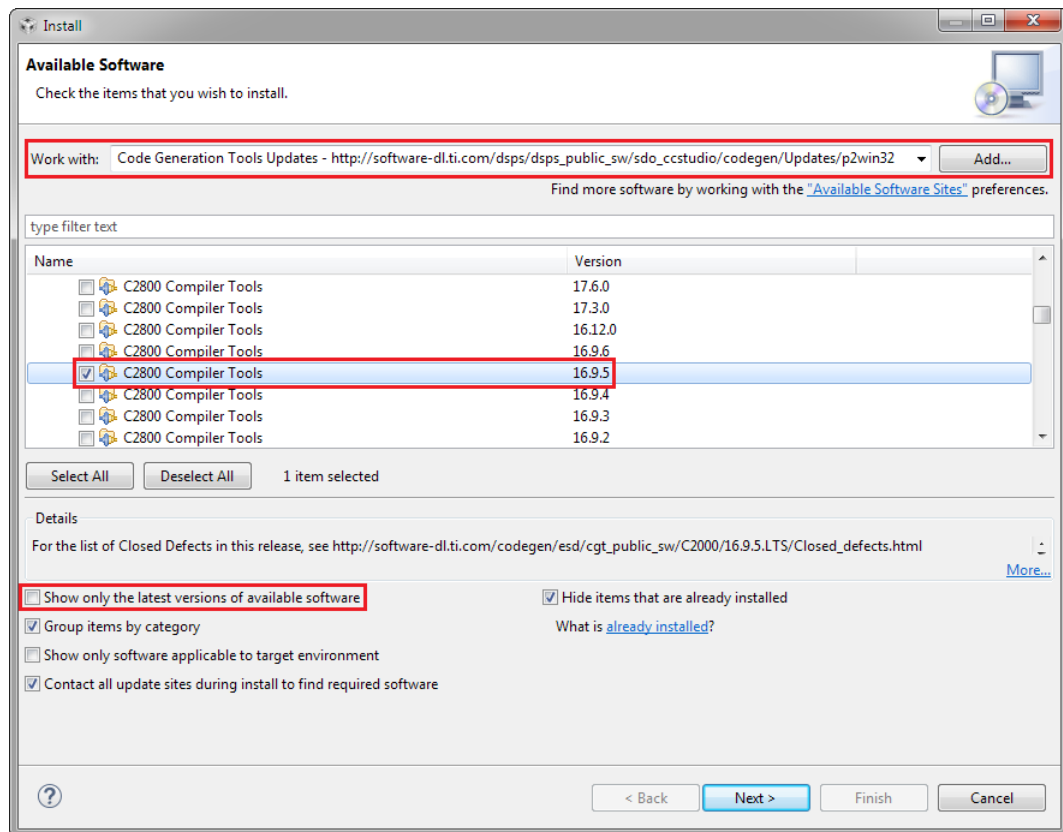


Figure 3: *Code Composer Studio* Compiler Download

4.2 *Texas Instruments* target processor types

4.2.1 Supported processors families

Currently the following *Texas Instruments* processor families are supported by X2C .

- TI C28x 32-Bit CPU
- TI TM4C12x 32-Bit CPU (ARM Cortex-M4 core)

4.2.2 Change target processor in *Code Composer Studio*

In the following section file names may vary with different processor types.

1. Import the *Blinky* demo application in *Code Composer Studio* (see Section 17 for more information).
2. Change the *Predefined symbols* (see Section 4.3) suitable for the used processor type.
3. With the OS file browser navigate to the *controlSUITE* subdirectory \device_support and search for your processor type (e.g. C:\ti\controlSUITE\device_support\f2806x\v130\F2806x_headers).
4. Copy the folders *cmd*, *include* and *source* into the project directory <PROJECT_DIRECTORY>\TexasInstruments and replace the existing folders from the processor used in the *Blinkdy* demo application.
5. In *Code Composer Studio* open the **F28xxx_Device.h** file in the folder <PROJECT_DIRECTORY>\TexasInstruments\include. In the section *User To Select*

Target Device search for your processor and change the 0 to TARGET. An example is shown in Figure 4.

```
57 #define DSP28_28067P 0
58 #define DSP28_28067UP 0
59 #define DSP28_28067PZ 0
60 #define DSP28_28067UPZ 0
61
62 #define DSP28_28068P 0
63 #define DSP28_28068UP 0
64 #define DSP28_28068PZ 0
65 #define DSP28_28068UPZ 0
66
67 #define DSP28_28069P 0
68 #define DSP28_28069UP 0
69 #define DSP28_28069PZ 0
70 #define DSP28_28069UPZ TARGET
```

Figure 4: Change processor type in the *device.h* file

6. In *Code Composer Studio* open the files *Hardware.h* and *X2cDataTypes.h* and adapt the file names in the *include* directives for the *F28xxx_Device.h* file.

4.3 Change predefined Symbols

The X2C project uses predefined symbols to give the preprocessor information before compiling the project. Navigate to **Project** → **Properties** open **Build** → **C2000 Compiler** → **Predefined Symbols**.

Currently three different processor families can be chosen

- `__GENERIC_TI_C28X__` for *Texas Instruments* Processors
- `__GENERIC_ARM_ARMV7__` for *ARM* Processors
- `__GENERIC_MICROCHIP_DSPIC__` for *Microchip* Processors

The definition

- `__CUSTOM_DATATYPE_DEFINITIONS__`

is needed to avoid compiler warnings caused by multiple *typedefs*.

In addition the definition

- `SCOPE_SIZE=8000`

like seen in Figure 5 needs to be made. The value of *Scope Size* is changeable and depends on the intended application and the used target processor. In the *Blinky* demo applications these values are already defined.

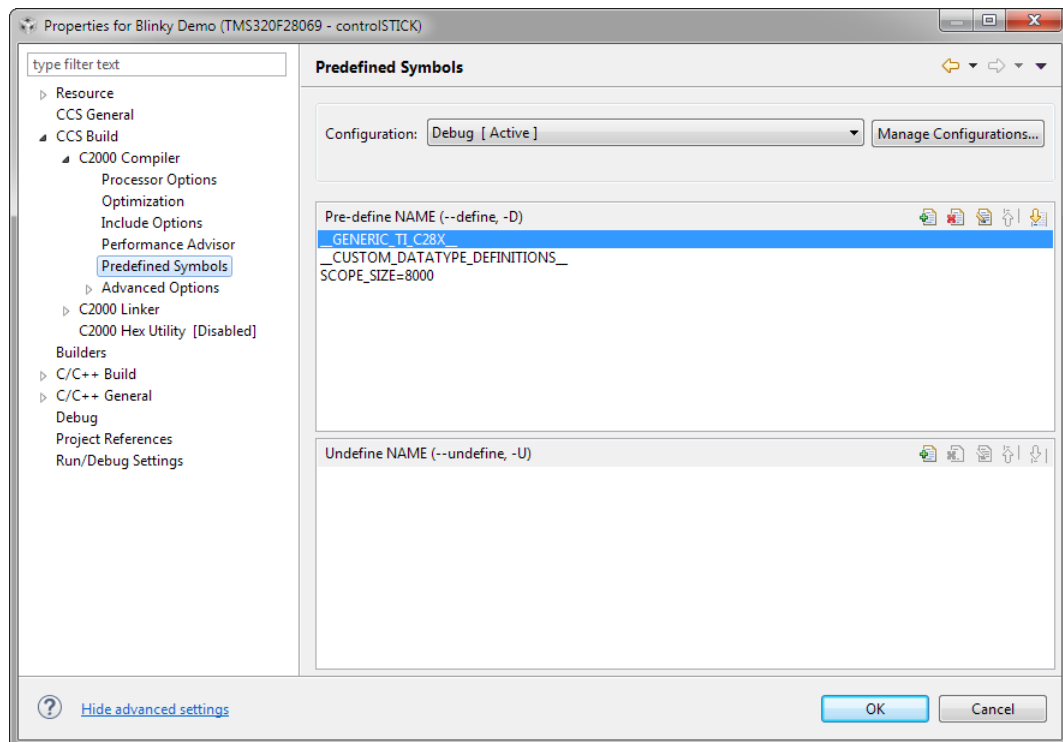


Figure 5: Predefined symbols for generic processor type in *Code Composer Studio*

5 Configuration of *MPLAB X*

5.1 Install the XC16 compiler

When working with *MPLAB X* the compiler to build the project has to be installed manually. Which compiler is needed depends on the used processor type. In the demo application *Blinky* the *xc 16 v1.21* compiler from the *Microchip* web page (http://www.microchip.com/pagehandler/en_us/devtools/mplabxc/) can be used.

5.2 *Microchip* target processor types

5.2.1 Supported processors families

Currently the following *Microchip* processor families are supported by *X2C*.

- dsPIC 16-Bit CPU

5.2.2 Change target processor in *MPLAB X*

Right click on the **Project** → **Properties**. In the *Configuration* area *Devices* can be picked in the drop down menu. Click **OK** to save the changes.

5.3 Change predefined Symbols

The *X2C* project uses *predefined Symbols* to give the preprocessor information before compiling the project. In the the sample project these symbols are already defined. Right click on the **Projectname** → **Properties** → **XC16 Global Options** → **xc16-gcc** to eventually change them. In the section *Define C macros* a list of defines is available as seen in Figure 6. Depending on the used target processor three different processor families can be chosen

- `__GENERIC_TI_C28X__` for *Texas Instruments* Processors
- `__GENERIC_ARM_ARMV7__` for *ARM* Processors
- `__GENERIC_MICROCHIP_DSPIC__` for *Microchip* Processors

In addition the definition

- `SCOPE_SIZE=5000`

like seen in Figure 6 needs to be made. The value of *Scope Size* is changeable and depends on the intended application and the used target processor. In the *Blinky* demo applications these values are already defined.

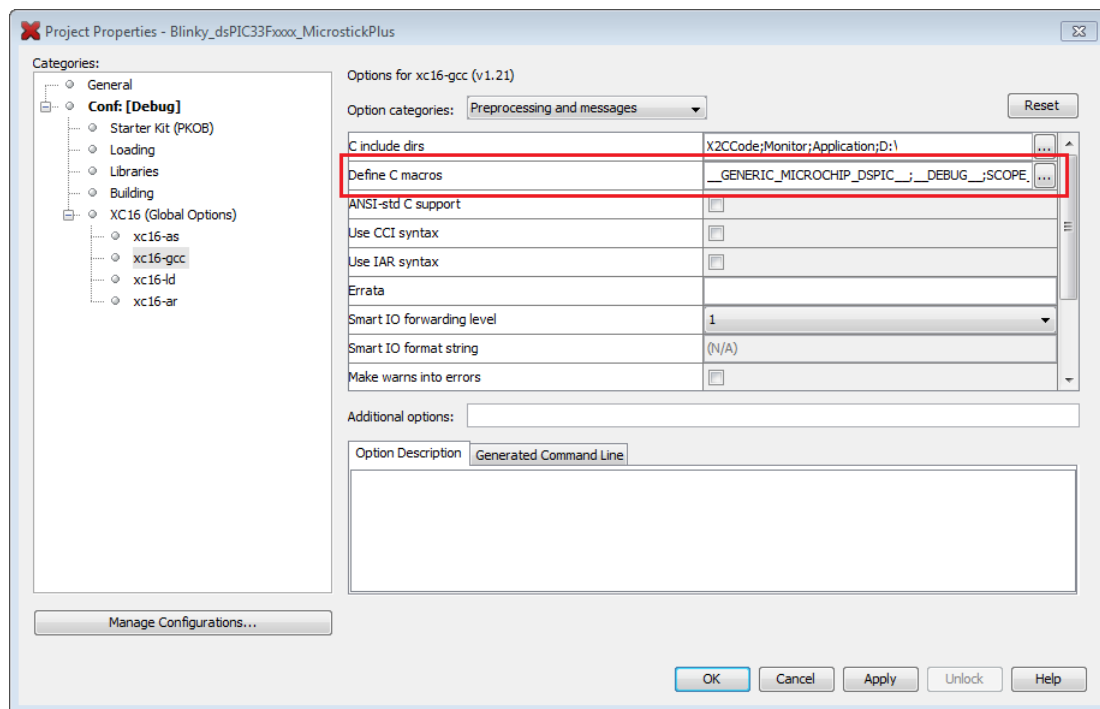


Figure 6: Predefined Symbols in *MPLAB X*

Part II

General

6 Introduction to X2C

6.1 Boolean data representation

Boolean data is based on the header *stdbool.h* introduced in C99 in the C Standard Library for the C programming language.

Bool	
Implementation type	Boolean
Format	C99
Minimum value	0 (false)
Maximum value	1 (true)

6.2 Fixed point data representation

6.2.1 Standard signals

Standard signals are symmetrically scaled about zero and their scaling range is $]-1...1[$. In a case of an overflow the signal will be limited to 1 (or -1 respectively). For example a subtraction of a signal with value 0.5 from a signal with value -0.7 will lead to a signal with value -1.

Depending on the chosen implementation the values are handled in one of the following formats:

FiP8	
Implementation type	8-bit fixed point
Format	Q7
Minimum value	-0.992 187 500
Maximum value	0.992 187 500
Resolution	0.007 812 500

FiP16	
Implementation type	16-bit fixed point
Format	Q15
Minimum value	-0.999 969 482 421 875
Maximum value	0.999 969 482 421 875
Resolution	0.000 030 517 578 125

FiP32	
Implementation type	32-bit fixed point
Format	Q31
Minimum value	−0.999 999 999 534 339
Maximum value	0.999 999 999 534 339
Resolution	0.000 000 000 465 661

6.2.2 Unlimited/Unbalanced signals

The scaling of unlimited/unbalanced signals is $[-1...1]$. While the standard signals omit one value to achieve a symmetrical value range, the unlimited (or also called unbalanced) signals utilize the full value range which leads to a slightly unbalanced value range. As the name implies unlimited signals won't be limited. In fact unlimited signals utilize wrapping/overflow functions of the DSP. For example a subtraction of a signal with value 0.5 from a signal with value -0.7 will lead to a signal with value 0.8.

So the primary use of the unlimited signal is as angular signal where $(-1...1)$ corresponds to $(-\pi... \pi)$.

Depending on the chosen implementation the values are handled in one of the following formats:

FiP8	
Implementation type	8-bit fixed point
Format	Q7
Minimum value	−1.000 000 000
Maximum value	0.992 187 500
Resolution	0.007 812 500

FiP16	
Implementation type	16-bit fixed point
Format	Q15
Minimum value	−1.000 000 000 000 000
Maximum value	0.999 969 482 421 875
Resolution	0.000 030 517 578 125

FiP32	
Implementation type	32-bit fixed point
Format	Q31
Minimum value	−1.000 000 000 000 000
Maximum value	0.999 999 999 534 339
Resolution	0.000 000 000 465 661

6.3 Floating point data representation

6.3.1 Standard signals

The standard signals in floating point format are not restricted, the full value range according to the IEEE 754 standard is available.

Float32	
Implementation type	32-bit floating point
Format	IEEE 754
Minimum value	$-3.4028234663852885981170418348452e + 38$
Maximum value	$3.4028234663852885981170418348452e + 38$
Resolution	$\pm 1.1754943508222875079687365372222e - 38$ (normalized)

Float64	
Implementation type	64-bit floating point
Format	IEEE 754
Minimum value	$-1.797693134862315708145274237317e + 308$
Maximum value	$1.797693134862315708145274237317e + 308$
Resolution	$\pm 2.2250738585072013830902327173324e - 308$ (normalized)

6.3.2 Unlimited/Unbalanced signals

Contrary to their names the unlimited/unbalanced signals in floating point format are limited to $[-\pi, +\pi]$. All other properties are similar to the unlimited signals in fixed point format.

Float32	
Implementation type	32-bit floating point
Format	IEEE 754
Minimum value	$-3.1415926535897932384626433832795$
Maximum value	$3.1415926535897932384626433832795$
Resolution	$\pm 1.1754943508222875079687365372222e - 38$ (normalized)

Float64	
Implementation type	64-bit floating point
Format	IEEE 754
Minimum value	$-3.1415926535897932384626433832795$
Maximum value	$3.1415926535897932384626433832795$
Resolution	$\pm 2.2250738585072013830902327173324e - 308$ (normalized)

6.4 Restrictions

6.4.1 Algebraic loops

Algebraic loops as depicted in Figure 7a are not possible due to an execution order problem. Therefore a block is required which breaks the loop at a specific position. This can be achieved by inserting a block with no direct feedthrough functionality, e.g. [Block: LoopBreaker](#) from the *General*-library or [Block: Delay](#) from the *Control*-library (see Figure 7b).

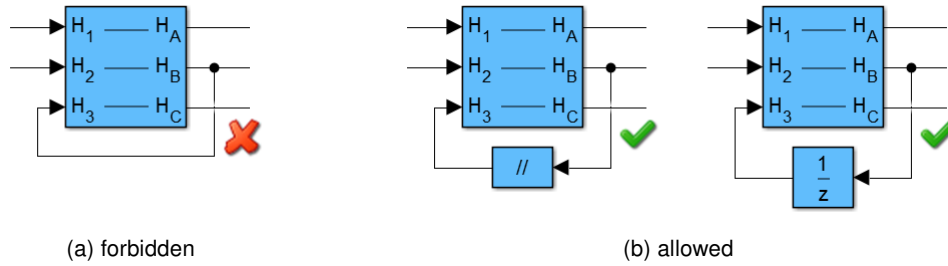


Figure 7: Algebraic loops

6.4.2 Connection of blocks with different implementations

Though blocks with different implementations are allowed (and computed correctly) in the same model, connections of ports with different datatypes are not permitted. The conversion blocks [24](#), [24](#) and [24](#) can be used to resolve datatype incompatibilities.

7 Basic structure of the C Code

When setting up a new project with X2C code generation it is necessary to configure the hardware on the target system. The following section provides basic information how the *Blinky* demo applications are structured. With this understanding one should be able to adapt hardware configuration for further projects.

In the following the *Blinky* demo application in combination with the *TI Piccolo F28069 ControlSTICK* and the *TMS320F28069* Processor is used for demonstration.

Info: The *.c files listed below need to be updated in case of changes in the *Scilab/Xcos* model configuration.

7.1 Main.c

- **initInterruptVector()** defined in *Hardware.c* configures the target specific interrupts.
- **initSerial()** defined in *Hardware.c* initializes the serial interface.
- **initHardware()** defined in *Hardware.c* here the peripheral devices such as *Watchdog*, *GPIO Ports*, *ADCs*, *Timers* and others are defined.
- **X2C_init()** defined in *X2C.c* calls the initialization functions of the X2C blocks.
- The **while(1)** loop is mainly used for the serial communication.
- The **mainTask()** function is the key structure of the project. Here the connection between *Outputs* and *Inports* are defined and the *X2C_Update()* function (defined in *X2C.c*) is called. The basic structure of the *mainTask()* is
 1. Assign Inports
 2. Call *X2C_Update()*
 3. Update Outports

The *mainTask()* function is usually called by an *Interrupt Service Routine (Isr)* which can be triggered by multiple sources.

Example: In the *Blinky Demo Application* after each *ADC* conversion cycle the *ADCIsr* calls the *mainTask()* function.

- **KICK_DOG** resets the *Watchdog* timer periodically. During operation this timer continuously counts a certain time span (configured in *Hardware.c*). If the application has an unexpected failure *KICK_DOG* can not be called and the *Watchdog* timer exceeds its limit and therefore the target reboots. If the operation executes as expected the *Watchdog* timer is within the limit and can be reseted by *KICK_DOG* without any further actions.

7.2 Hardware.c

In this file all connections and peripheral device settings should be made.

- In **initHardware()** all peripheral function should be initialized.
 - Watchdog timer
 - GPIO Ports
 - Interrupt initialization
 - ADC, Timer, PWM and all the other peripheral devices
- **initSerial()** initializes the serial interface on the target. The settings made here should match with the setting made in the *Communicator* described in Section 11.

8 Testing

8.1 JUnit tests

To minimize the risk of software bugs most parts of X2C are tested. The Java core of X2C is tested with JUnit tests.

8.2 CUnit tests

Much care is also taken of testing the C-code of the blocks. These so called CUnit tests are conducted directly on the target. In Figure 8 the test setting can be seen.

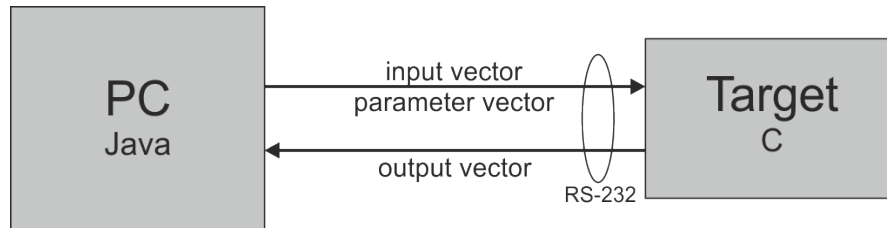


Figure 8: CUnit test setting

In the test environment on the PC a input vector and a parameter vector, if necessary, are defined and sent to the target via serial interface. On the target the update function of the block under test is executed. The resulting output vector is transferred back to the PC where it is compared with a reference output vector. If the difference between the actual and the reference output vector is below a specified limit the test is marked as passed. Otherwise an error is reported.

Basically, the generation of the test vectors are done with one or a combination of these methods:

Equivalence class testing To reduce the number of test items they are grouped into classes with same behavior. Only one member of each equivalence class is used as entry for the test vector. Two simple equivalence classes could be positive and negative numbers.

Boundary testing The entries for the test vectors are chosen in such a way that they lie below and above critical boundaries. For example, typical values for a FiP16 implementation would be -32768, -32767, -1, 0, 1, 32767.

Back-to-back testing For complex blocks this method is used. The vectors are generated by simulating a block or model with the same functionality in Matlab/Simulink or Scilab/Xcos.

Several different targets are used for testing. The test reports can be found in the library documentation *Library.source.pdf* in the directory `<X2C_ROOT>\Library`.

9 Coding Conventions

9.1 Language

The native language of X2C is English. Hence all documentation, file names, variables, comments in source files, etc. should be in English.

9.2 General naming conventions

- Unless otherwise stated, all names should use the camel case notation. A definition of camel case can be found on <http://en.wikipedia.org/wiki/CamelCase>. The type of camel case (upper or lower) depends on the type of name, see sections below.

Examples: `ThisIsUpperCamelCasing.java`, `showLowerCamelCaseExample()`

- Non-ASCII characters should be avoided. Also the space character should not be used.
- Due to a character limitation in Scilab, names with more than 27 characters should be avoided.
- Names should not start with a number.
- [Hungarian notation](#) should not be used.

9.3 Naming of files

In general files should have a meaningful name. If abbreviations are used, easy understandable ones should be used. Upper camel case is recommended.

Examples: `Hardware.c`, `SystemControl.c`, `GlobalDefines.h`

9.4 Naming of functions and methods

Function and method names should contain a verb to describe the action of the function. The verb is placed first and is in lower case and subsequent nouns start with a capital letter (lower camel case).

Examples: `readADC()`, `setPWM()`

9.5 Naming of macros

Macros should be written in capital letters. Macro names which contain multiple words should use an underscore as separator (screaming [snake case](#)).

Examples: `DISABLE_PWM`, `NO_ERROR`

9.6 Naming of variables

Based on the proposed convention from Sun Microsystems following guidelines should be considered:

Variables are in mixed case with a lowercase first letter. Internal words start with capital letters. Variable names should be short yet meaningful. The choice of a variable name should be mnemonic- that is, designed to indicate to the casual observer the intent of its use. One-character variable names should be avoided except for temporary "throwaway" variables. Common names for temporary variables are i, j, k, m, and n for integers; c, d, and e for characters.

Examples: `int16 i`; `float32 myWidth`;

9.7 Naming of model parameters

Parameter and variable names in Matlab or Scilab should follow lower [snake case](#) notation. This means the first word can either start with a lower or upper case letter, all subsequent words have to start with a lower case letter, and the words are separated by underscores.

Examples: `i_ref`, `n_max`, `k_T`, `U_dc_max`

9.8 Naming of X2C blocks

Block and Subsystem/Superblock names in Matlab or Scilab should follow upper camel case notation. Exceptions are words with abbreviations, then a underscore character as separator is allowed to increase readability.

Examples: `CurrentController`, `OffsetAngle`, `AnIn1`, `DigOut1`, `I_Phase1`

9.9 Source and header files

Every *.c source file should have a corresponding *.h header file. A minimalistic header with prototype definitions is sufficient.

Due to MISRA rule 8.1 (see [MISRA-C 2004 compliance](#)) it is required to have prototypes for every function, including static ones. To avoid conflicts between global and static function prototypes when including header files, the following rule shall apply:

- Global function prototypes should be located in its header file
- Static function prototypes should be located at the beginning of its source file

9.10 Global definitions

Definition of macros which are used in more than one source file should be placed in `GlobalDefines.h`. Macros only used in one file should be defined in the source file in which they are used.

Globally needed variables should be defined in `GlobalDefines.c` and declared in `GlobalDefines.h`. This way all global variables are at one place and can be referenced from every file which has the `GlobalDefines.h` header file included.

Example:

Listing 1: `GlobalDefines.c`

```
1  #include "GlobalDefines.h"
2
3  /******
4  /* Global Variables
5  /******
6  uint16 errorstate = NO_ERROR;          /* Error Message */
7  uint32 modulestate = NO_ERROR;        /* Module Status */
8  FIStates FIState = RESET_STATE;      /* State of frequency inverter */
```

Listing 2: `GlobalDefines.h`

```
1  #ifndef GLOBALDEFINES_H
2      #define GLOBALDEFINES_H
3
4      #include "Target.h"
5      #include "X2C.h"
6
7      /******
8      /* Global Variables
9      /******
10     extern uint16 errorstate;          /* Error Message */
11     extern uint32 modulestate;        /* Module Status */
12     extern FIStates FIState;          /* State of frequency inverter */
13
14 #endif
```

9.11 Template files

For an easy orientation standard file names should be used in X2C projects:

- `Main.c`: Frame program main file.
- `Hardware.c`: Hardware configuration and initialization.
- `GlobalDefines.*`: Files with globally needed definitions and variables.
- `SystemControl.c`: File with startup sequence of power electronics and error handling.
- `InterruptControl.c`: Interrupt handling, especially interrupt vector table and interrupt service routines.
- `InputControl.c`: Handling of analog and digital inputs.
- `OutputControl.c`: Handling of analog and digital outputs.
- `CANControl.c`: Configuration, initialization and functions of a CAN interface.

Of course, if files contain a lot of code it is recommended to split the file into several ones to maintain comprehensibility.

Example: Splitting of `InputsControl.c` in `AnalogInputControl.c`, `DigitalInputControl.c` and `HallSensorControl.c`

9.12 Include order of header files

To avoid conflicts and missing dependencies header files should be included in following order:

1. System headers
2. Application headers
3. Header of current source file

Example:

Listing 3: Main.c

```
1 #include "VersionInfo.h"
2 #include "GlobalDefines.h"
3 #include "Hardware.h"
4 #include "SystemControl.h"
5 #include "InputControl.h"
6 #include "OutputControl.h"
7 #include "Main.h"
```

9.13 Hardware registers

To maintain comprehensibility and to allow interchangeability of source files hardware (DSP) registers should be accessed via macros.

Example:

```
#define SET_LED      (GPBSET = 0x00000004)

/* some code */
SET_LED;
/* some more code */
```

instead of

```
/* some code */
GPBSET = 0x00000004;
/* some more code */
```

10 MISRA-C 2004 compliance

The rules of the Motor Industry Software Reliability Association [MISRA](#) should be followed as much as possible. Some major rules are:

- **MISRA-C:2004 2.2/R:** Source code shall only use `/* ... */` style comments.
- **MISRA-C:2004 19.4/R:** C macros shall only expand to a braced initialiser, a constant, a string literal, a parenthesised expression, a type qualifier, a storage class specifier, or a do-while-zero construct.
- **MISRA-C:2004 8.12/R:** When an array is declared with external linkage, its size shall be stated explicitly or defined implicitly by initialisation.
- **MISRA-C:2004 18.4/R:** Unions shall not be used.
- **MISRA-C:2004 16.3/R:** Identifiers shall be given for all of the parameters in a function prototype declaration.
- **MISRA-C:2004 19.15/R:** Precautions shall be taken in order to prevent the contents of a header file being included twice.
- **MISRA-C:2004 19.1/A:** `#include` statements in a file should only be preceded by other preprocessor directives or comments.
- **MISRA-C:2004 8.1/R:** Functions shall have prototype declarations and the prototype shall be visible at both the function definition and call.

10.1 Applied rules

```
1  /* Enable MISRA-C:2004 checking (all rules) */
2  --check_misra="all"
3
4  /* Rule violation handling */
5  --misra_advisory="warning"
6  --misra_required="warning"
7
8  /* Exceptions */
9  --check_misra="-1.1" /* (MISRA-C:2004 1.1/R) Ensure strict ANSI C mode (-ps)
10     is enabled */
11 --check_misra="-12.7" /* (MISRA-C:2004 12.7/R) Bitwise operators shall not be
12     applied to operands whose underlying type is signed */
13 --check_misra="-19.7" /* (MISRA-C:2004 19.7/A) A function should be used in
14     preference to a function-like macro */
15 --check_misra="-5.7" /* (MISRA-C:2004 5.7/A) No identifier name should be
16     reused */
```

Listing 4: MISRA.opt

Part III

Utilities

11 Communicator

The *Communicator* is the interface between the target system and the model in *Scilab/Xcos*. It is used to generate the C code files out of the model. Furthermore it is used to transfer data between the computer and the target. When started the *Communicator* is connected with the model via *RMI* interface and via serial interface with the target (DSP).

11.1 *Scilab/Xcos Communicator* start

As described in Section 16 the *Communicator* is started out of an open *Scilab/Xcos* model with the buttons *start Communicator*. The button *Transform model and push to Communicator* loads the model file (.xml) into the *Communicator*. Changes in the model structure can be made and pushed to the *Communicator* by double clicking on the button *Transform model and push to Communicator*.

11.2 Standalone *Communicator* start

If there are no intended changes in the model structure it is possible to start the *Communicator* without *Scilab/Xcos*. In <X2C_ROOT>\System\Java double click on **Communicator.jar**. In the open *Communicator* go to **Model** → **Load Model** and browse to your project directory. In the *X2CCode* folder choose the model (.xml) file and open it. In the *Status* tab check the *Log* area if the model has been loaded successfully.

11.3 Basic functions of the *Communicator*

The *Communicator* is structured into the menu bar (1) the toolbar (2) and four main tabs (3).

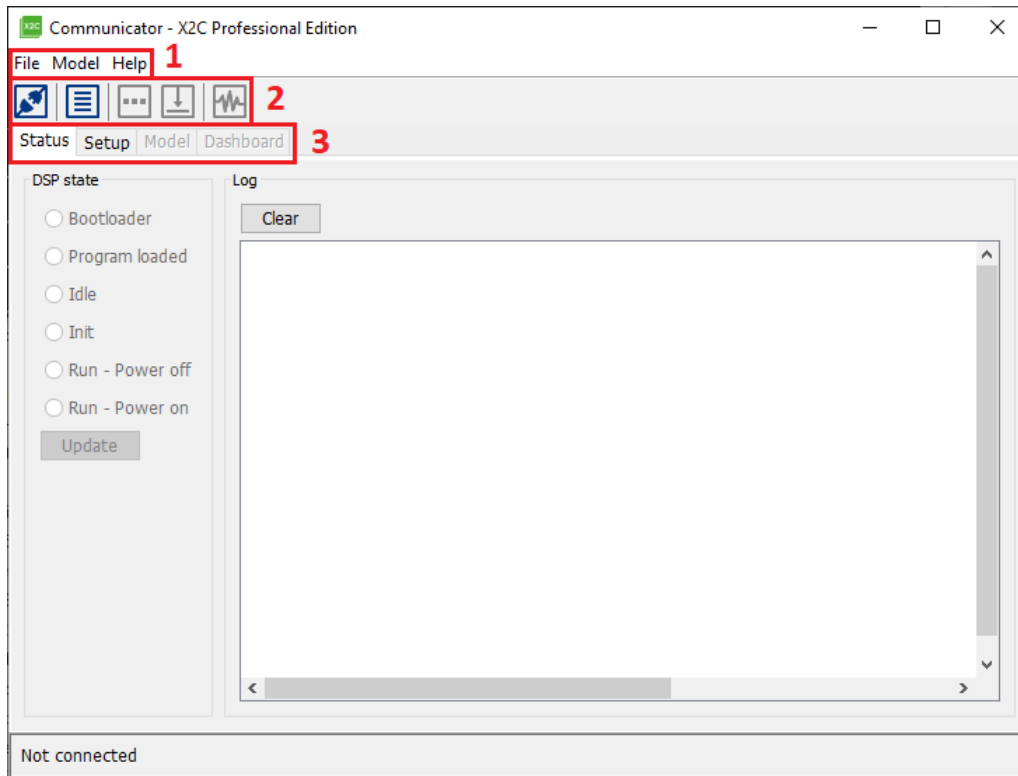


Figure 9: Basic structure of the *Communicator*

1. Menu bar

- In the **File** menu the settings can be modified, loaded and saved.
- In the **Model** menu a new *.xml* file can be loaded and saved.

2. Toolbar

- With the button **Connect to Target** the *Communicator* can be connected respectively disconnected from the target.
- **Create Code** generates the *X2C* C code files out of the *X2C* model. Changes in the *Model* tab like *Sample time* require new code creation.
- **Create RTOS Code** was moved to *Settings*. See [11.4](#) for details.
- In the **Download settings** the *Binary* and *MAP* files can be selected. These files are usually generated during the build process and are used by the *Communicator* for the following purposes:
 - (a) The binary is required to download an application to the target system. This feature is not available in the free edition.
 - (b) The MAP file is optional and is required only to view global variables in the *X2C Scope*. See [12](#) for details.
- The **Download application to target** function is only available in the Professional edition of *X2C*. This function provides application download functionality without any use of external programming devices.
- The **Scope** button starts an oscilloscope like environment for plotting signals and variables of the running target. For more information see [Section 12](#).

3. Tabs

- In the **Status** tab there are two main areas as seen in [Figure 10](#). In *DSP state* the current status of the connected target is shown. The following states are possible:

- The **Bootloader** state indicates that no valid/working application is present on the target system. Bootloader and Application download are available in the Professional edition only.
- The **Program loaded** state indicates an application is present and running.
- In the **Idle** state only the communication between target and computer is active. All controller functions are inactive furthermore the *Outports* values are static.
- The **Init** state calls the initialization functions of all *X2C* blocks. In this state all signals and variables are reset to their initial values.
- **Run - Power off** means the application is running normally but the power supply of the power electronics (e.g. frequency converter) is off.
- In **Run - Power on** the system is fully active.

Info: In the *Blinky* demo application the last four states cannot be changed because they are only useful for engine control applications.

The *Log* area shows status updates and error messages and can be cleared with the *Clear* button.

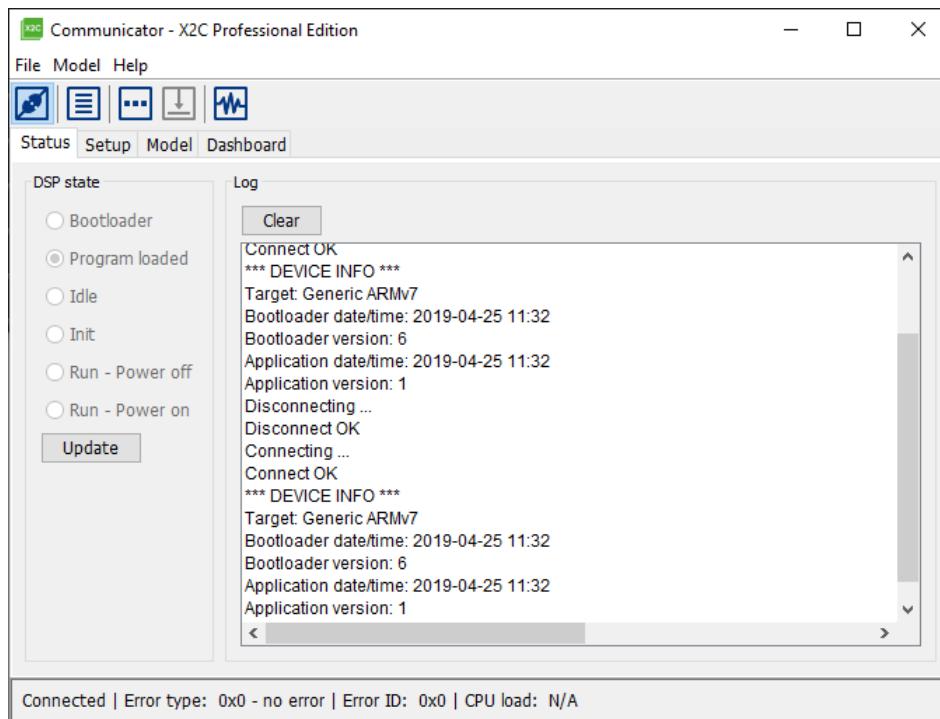


Figure 10: *Communicator* status

- The **Setup** tab is for the interface configuration. To change the settings the *Communicator* needs to be disconnected from the target. There are a few ways to connect with the target. One can choose between *Serial*, *USB* and *PCAN* interface. The setting made here need to be compatible with the target configurations. In the *Protocol* area the *LNet Node ID* can be set. By default this value is set to 1. Since the *Communicator* can be used with more than one target each target is defined with an unique *LNet Node ID*.

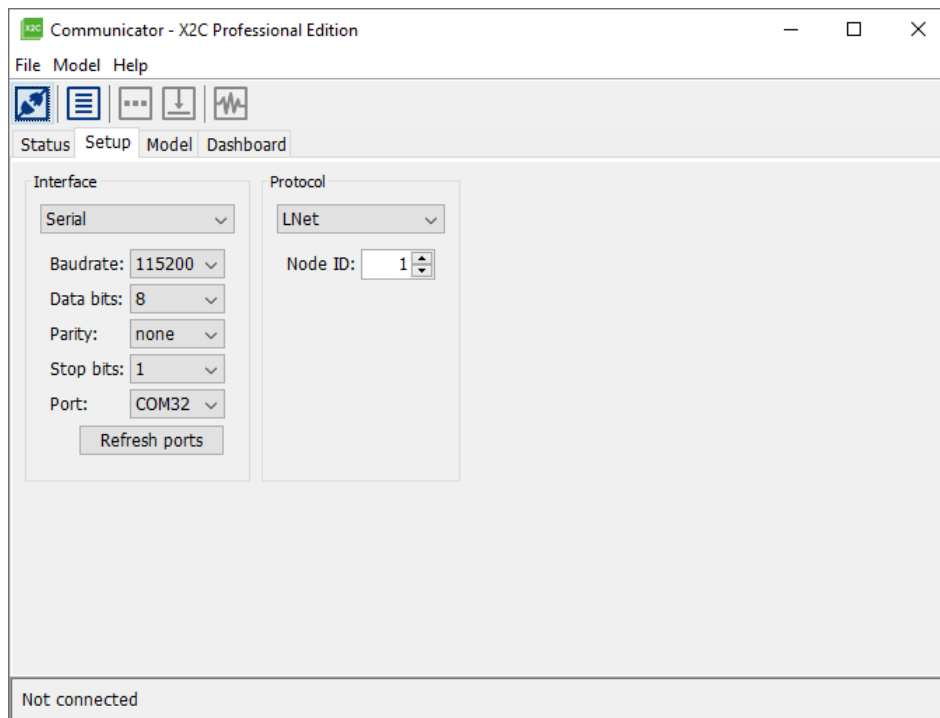


Figure 11: *Communicator* setup

- In the **Model** tab the *Model structure* area provides a list of the used blocks in the *Scilab/Xcos* model. Jump to Section 11.5 to see how variables can be changed through the *Model structure* settings.
The *Model properties* settings need to be made before code generation.
 - The *Sample time* can be changed in the *Scilab/Xcos* model by changing the values in the *CLOCK* block. After double clicking on *transform model and push to Communicator* the sample time in the *Communicator* is updated. After clicking on *Analyze* the sample in the *Communicator* is updated.
Note: Changes of the sample time made in the model need to be compatible with the defined sample time on the target.
 - *Use Scope* was moved to *Settings*. See 11.4 for details.
 - *Use Parameter ID for block data transfer* was moved to *Settings*. See 11.4 for details.

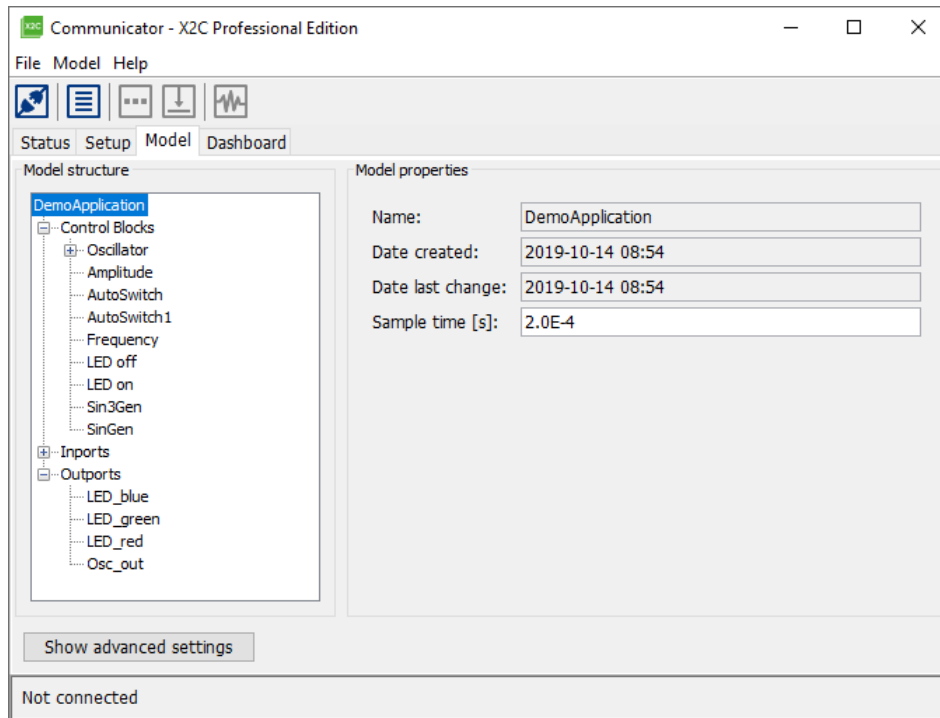


Figure 12: *Communicator Model*

11.4 Settings

The Settings can be found in the *File* menu. The Settings view is divided into 4 tabs.

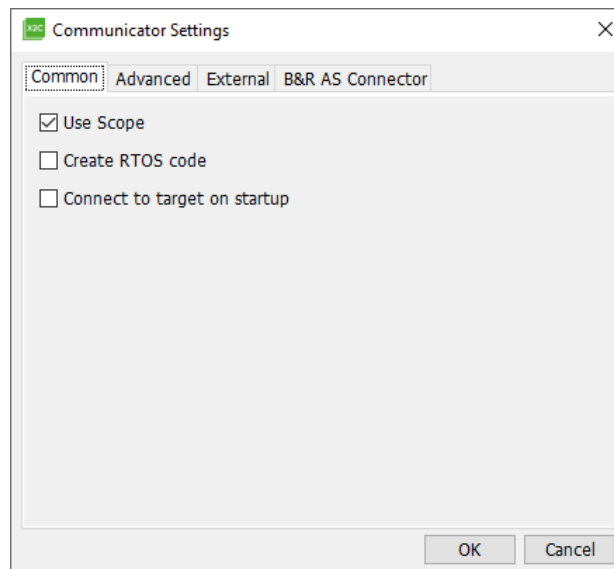


Figure 13: *Communicator Settings*

Common

- **Use Scope** [enabled]

Use Scope defines if the scope application (see Section 12) can be used when connected with the target. When disabled the target processor is relieved due to less communication effort.

- **Create RTOS code** [disabled]
Generates code which is optimized for real time operations.
- **Connect to target on startup** [enabled]
Tries to connect to the target when the Communicator starts. If this option is enabled, the previously used communication setup is being used.

Advanced

- **Create Signals code** [disabled]
Creates a file containing lists with internal X2C signals. These signals are Inports, Outports and Block Outports.
- **Create & compile HotInt code** [disabled]
Generates HotInt specific files. After successful generation, the HotInt project (Microsoft® Visual Studio) is being compiled. The latest version being found is used for compilation. Supported Visual Studio versions:
 - Visual Studio 2013
 - Visual Studio 2012
- **Enable Code For Speed Optimizer** [disabled]
Allows the usage of the Code For Speed Optimizer. Refer to [14](#) for details.

External

Allows to select executables which are executed

- before code generation (Pre-Generate)
- after code generation (Post-Generate)

B&R AS Connector

This tab allows to configure the X2C Connector for *B&R® Automation Studio®* . Refer to [21](#) for details.

11.5 Change parameters on the target with the *Communicator*

If all connection are set up properly there are two ways of changing the parameter values on the running target.

1. In the *Communicator* click on **Model**. In the Model structure area all the Block properties are listed and can be changed by double clicking on them.
2. In the *Scilab/Xcos* model double click on the blocks and change the values.

12 Scope

The *Scope* application is a very useful device for monitoring signals and variables on the running target. It allows an easy observation in an oscilloscope like environment. The *Scope* is structured into four main areas as seen in Figure 14.

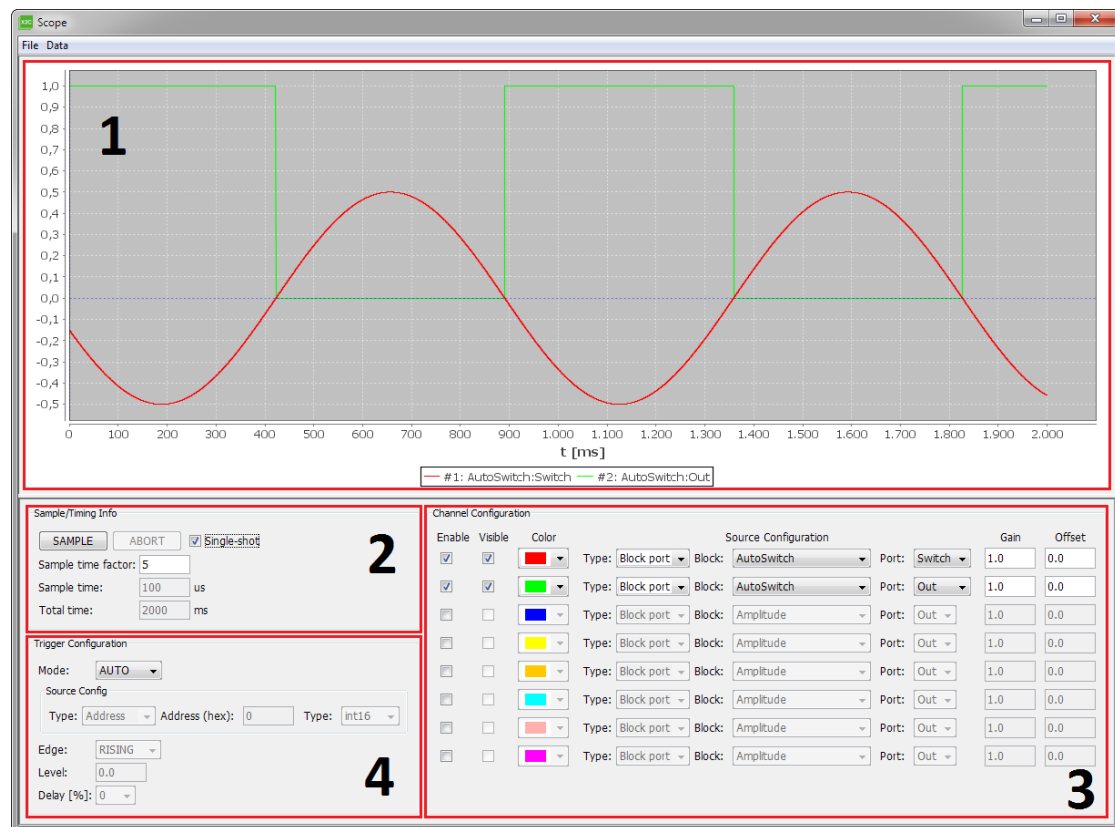


Figure 14: Communicator Scope

1. The **Plot area** shows the selected values at a time based abscissa (x-coordinate) in milliseconds and scaled from -1.0 to 1.0 at the ordinate (y-coordinate). Furthermore there is a legend at the bottom of the plot area showing the color of each channel.
2. In the **Sample/Timing Info** section options of the time axis can be made. The oscilloscope is started with the button *SAMPLE*. When the option *Single-shot* is marked only one time period (see *Total time*) is shown in the plot area. When unmarked the plot area continuously plots the received values from the target. Due to time delay in data transfer it is possible that there are missing values between two plot cycles. The plot process can be stopped with the button *ABORT*.
With the option *Sample time factor* the time axis can be scaled. Factor 1 means every value (Time between two values is *Sample Time*) is plotted in the plot area. As example factor 5 means every fifth value is used, therefore a longer time span can be plotted at the time axis.
3. The **Channel Configuration** configures which signal is shown at the plot area. There are eight channels that can be plotted simultaneously. Mark *Enable* to configure one channel. In the *Type* menu *Address*, *Block Port* and *I/O port* can be chosen. *I/O ports* are the links between the target peripheries and the *X2C* model. The *Block Port* are

signals used in the *X2C* model.

When fixed point data representation is selected all signal are scaled to values between -1.0 and 1.0 , therefore one might use the option *Gain* or *Offset* to plot the signal in real scale.

4. The **Trigger Configuration** is divided in the options *NORMAL* and *AUTO*. When option *AUTO* is chosen no specific trigger is set. In this configuration signal values are continuously transfer and plotted. This can lead to moving graphs especially when periodic signals are observed.

Choose *NORMAL* to set up a trigger.

- (a) In *Source Config* choose a signal which should work as trigger source.
- (b) With *Edge* the trigger only checks rising respectively falling edges of the source signal.
- (c) The *Level* and *Delay* options move the trigger point in vertical and time direction.

Example: Trigger the harmonic sine wave u from a *SinGen* block.

As trigger source the signal itself is used. When the trigger is delayed in time a vertical marker indicates the position. The effect of the settings *Level* with a value of 0.2 and *Edge* for *FALLING* can be seen in Figure 15.

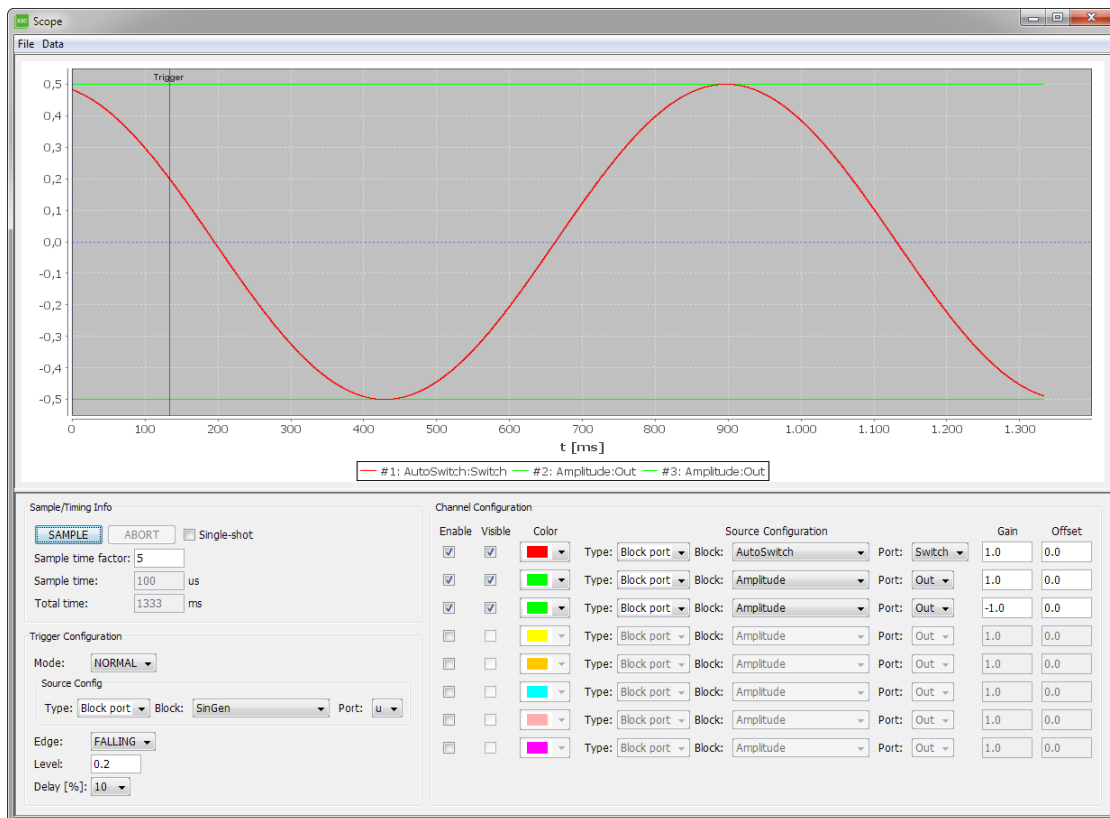


Figure 15: Scope Trigger using Example

13 Block Generator

The Block Generator is used to create new blocks, load and/or edit previously saved blocks. The following, essential parameters define the block function:

13.1 Block properties

Name

Each block within a library must have a unique name.

Library type

The library type selection is done via the 'Change configuration' button.

An internal library block will be stored within the X2C structure where only the library name is required. The internal library name can be selected via a dropdown menu.

When the block is saved, the files will be automatically saved into the correct directories.

An external (or project specific) block is stored within its project structure and requires the user to enter a library name and pre-namespace identifier. Both, the library name & pre-namespace, is entered via text fields.

When the block is saved, a window will appear, which allows to select the project directory for this project specific block (only directory selection is possible) The Block Generator tries to save the files in the following structure (directories will be created automatically if they don't exist):

<selected directory>\Library\<library name>\

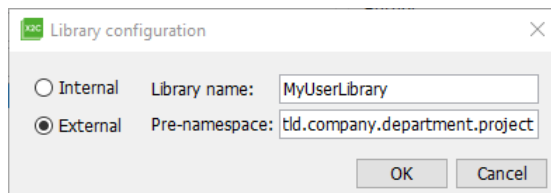


Figure 16: *Block Generator* External library settings

Identifier

Every block needs a unique identifier (ID) across all libraries to ensure proper functionality if a project uses blocks from different libraries. *ID* should be a value < 4000 for internal blocks and a value ≥ 4000 for external blocks.

Additional \LaTeX information file

In case of having a \LaTeX file with additional block information the name of the file can be set.

Mask In- & Outports

Every block can have several inports & outports. Each in-/outport must have a unique name.

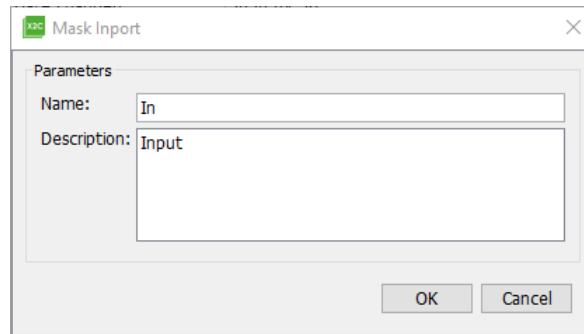


Figure 17: *Block Generator Mask Inport*

Mask Parameters

Every block can have several mask parameters. Each mask parameter must have a unique name. *Prompt* will be displayed next to the value input of this parameter. *Data type* decides between an input field for type *Double* or a dropdown menu for type *ComboBox*.

In case of type *Double* you can select the *Default value* for this parameter.

Type *ComboBox* lets you add/remove items which can be selected by the user if this parameter value should be changed. The default value is defined by selecting one out of the entries.

Visible makes this parameter visible, *Changeable* en- or disables this parameter.

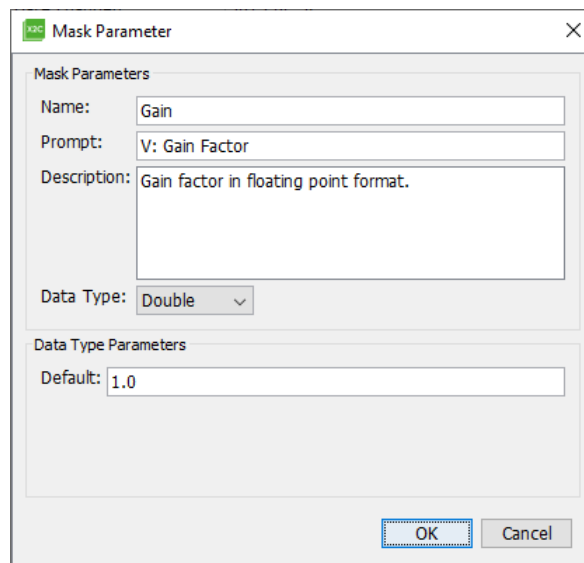


Figure 18: *Block Generator Mask Parameter*

Visualizations

Visualizations are used to represent the block within a model. *Command* contains the language specific commands to represent the block.

13.2 Implementation properties

Every block must have at least 1 Implementation. Each Implementation has its Init-, Update-, Save- and Load functions (C) and Conversion functions (Java/Python/JavaScript).

Name

Each implementation must have a unique name within a block. The Implementation name is used for C- & Java code file name.

Identifier

Every Implementation needs an unique identifier (ID) within its block. This ID can have values in the range from 0 to 15.

Controller In- & Outports

The Controller In- & Outport names can be selected but not edited. The names are defined by the block's Mask In- & Outports. Only the data type must be selected for each In-/Outport.

Controller Parameter

Each Controller Parameter must have an unique name within its Implementation. The data type and default value can be selected. Also the ability to download/upload the parameter can be defined by using *Load & Save Enable* checkbox.

The *Array* option allows the Parameter to contain a data array instead of a scalar value. Two array configurations are possible:

- **Modifyable**
Enabled by setting the *Array* checkbox and *Array size*. This type of array has a fixed size and is located in volatile memory. Due to volatile nature the data can be up- and downloaded.
- **Fixed**
Enabled by setting both, the *Array* and *Array in flash memory* checkboxes. The size of this type of array is not fixed because it is generated on Model generation. It is located in non-volatile memory and therefore cannot be up- and downloaded.

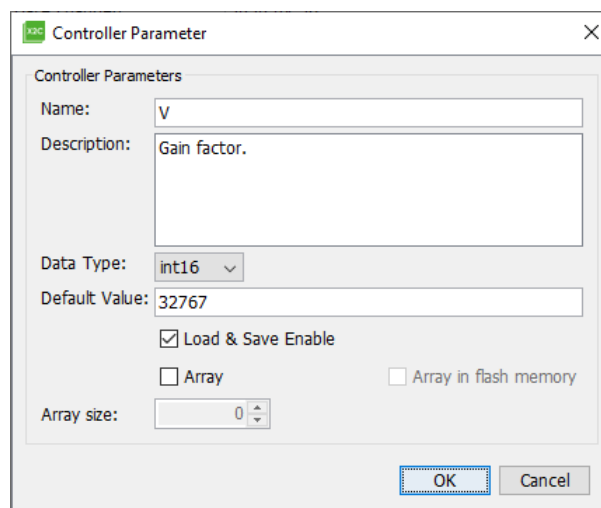


Figure 19: *Block Generator* Controller Parameter

Conversion function type

The Conversion function type can be selected by using the dropdown menu. If *Java*, *Python* or *JavaScript* is selected, the Block Generator will generate a conversion function template file for this block which needs to be manually filled with block-specific conversion calculations, otherwise no conversion function file will be created.

13.2.1 Advanced Implementation Settings

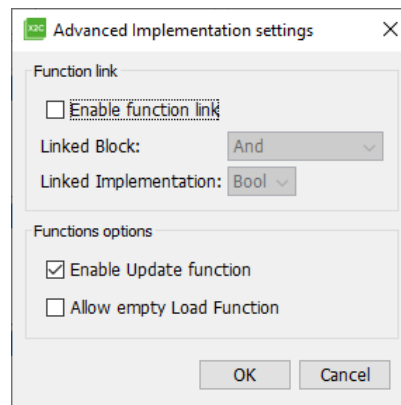


Figure 20: *Block Generator* Advanced Implementation Settings

Function Link

If this option is enabled, the *Init*-, *Update*-, *Load*- and *Save* Block functions are used from an other Block Implementation. A Block within the same *X2C* library may be selected as link source.

Update Function

This option is enabled by default. If disabled, the Implementation does not have a (cyclic) Update function.

Allow empty Load function

Forces the Block Generator to create a *Load* function even if the Implementation doesn't contain any transmittable parameters. The user customizable part of the *Load* function may be used to change the *Load* functions' default behaviour.

13.3 Save or load a block

Saving & loading is done via the *File* menu in the menu bar.

Saving

If the selected block is member of an internal library, the Block Generator automatically uses the correct library root directory.

In case of an external library block type, the user is prompted a directory selection window, in which the project directory can be selected. The library root directory is now located in:

<user directory selection>\<Library>\<library name>.

Each library is organized in this structure:

- Controller: Directory with the C-code source files (*.c, *.h).
- Conversion: Directory with the Java, Python or JavaScript conversion files.
- Doc: Directory with files needed for the (auto-generated) documentation.
- Scilab: This directory contains the *Scilab/Xcos* library files as well as the interfaces functions and the files need for simulation in *Scilab/Xcos* .
- XML: Configuration files (*.xml) contain all block parameters and are located in this directory.

Part IV

Add-Ons

14 Code For Speed Optimizer (CFSO)

The CFSO allows the optimization of the X2C Update function(s) to decrease the execution time. TO achieve this, the CFSO, if activated, replaces the X2C Block function calls by the X2C Block Update code itself to remove the overhead of C function calls. The optimizer collects the required information from the Block-Implementation C source code. It can be enabled in the Advanced *Communicator* settings tab.

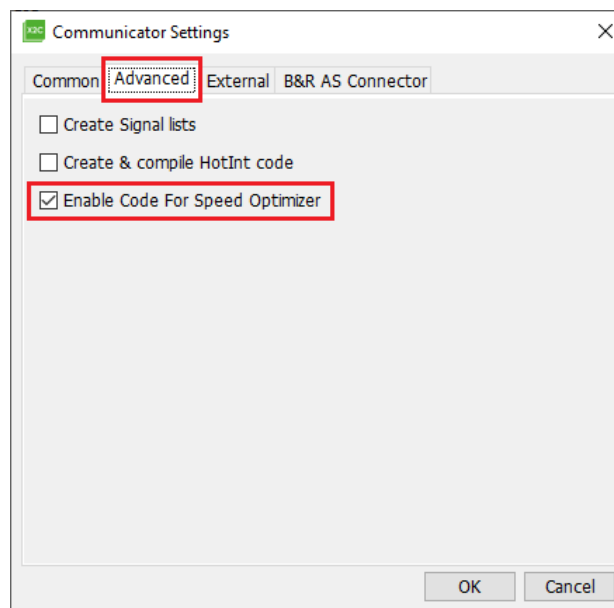


Figure 21: CFSO in Advanced *Communicator* settings

This feature is only available in editions **Plus** and **Professional**.

14.1 Data Collection

The CFSO collects the data from the C source for each Block-Implementation type. If the source is not available, the Implementation is tagged to use the usual Update function call instead and the next Implementation type is processed. Otherwise the following Implementation specific elements are extracted from the C source:

- Preprocessor code
- Includes
- Define names
- Update function code

During data extraction, every occurrence of the Implementation Pointer variable is replaced by a placeholder. The data collection procedure is repeated for every Implementation type in the Model. In the further course the X2C Code Generator will replace the placeholder by the current Block variable.

14.1.1 Implementations using a function link

This kind of Implementation shares the Update function code with an other Implementation. In this case the Preprocessor code, Includes and Define names from both Implementations are merged. The Update function code is retrieved from the linked Implementation.

14.2 Code Generation

Once all the Implementation information is collected, the *X2C* Code Generator replaces every Update function call, except for the Implementations of which the sources are not available. Following elements are added at the beginning of the generated *X2C* C file:

- An informational line beyond the header to inform the user that the CFSO is active
- All collected Implementation C Includes

For each Update function the following content is added in the following order:

1. Preprocessor code
2. Implementation Update function
3. Undefine C macros (`#undef`) for all possible defined C macros

The placeholders, which were set during the data collection procedure, are replaced by the appropriate Block Implementation variable. In case of an Implementation with unavailable C source, the usual Update function call is used. A comment is added above the relevant Update function call for information.

15 Dashboard

The Dashboard allows the user to view and modify selected elements. Each element features various, configurable properties for a user friendly representation of each data value. The elements can be uploaded or downloaded - depending on the respective type.

A download can be done for each individual, editable entry by changing its value or for all editable values by using the 'Download Editable Values' button.

The upload procedure is started by the 'Start Update' button and uploads ALL uploadable values at a defined interval.

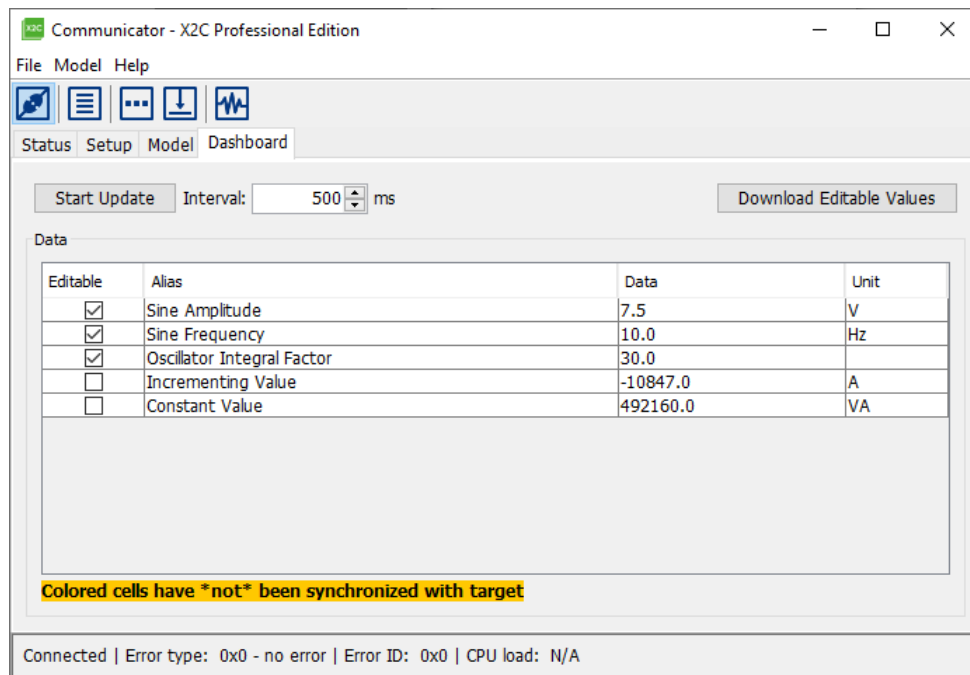


Figure 22: Communicator Dashboard View

This feature is only available in editions **Plus** and **Professional**.

15.1 Configuration File

The Dashboard configuration is stored in a properties file. Currently there is no GUI support to setup a Dashboard configuration. Instead, the user has to setup the file.

Configuration file templates are available to make the configuration process easier. These templates can be found in directory /Templates/Dashboard.

A Dashboard configuration can be loaded or cleared via the Communicator menus. Two options are available to either load a new configuration or clear the current configuration.

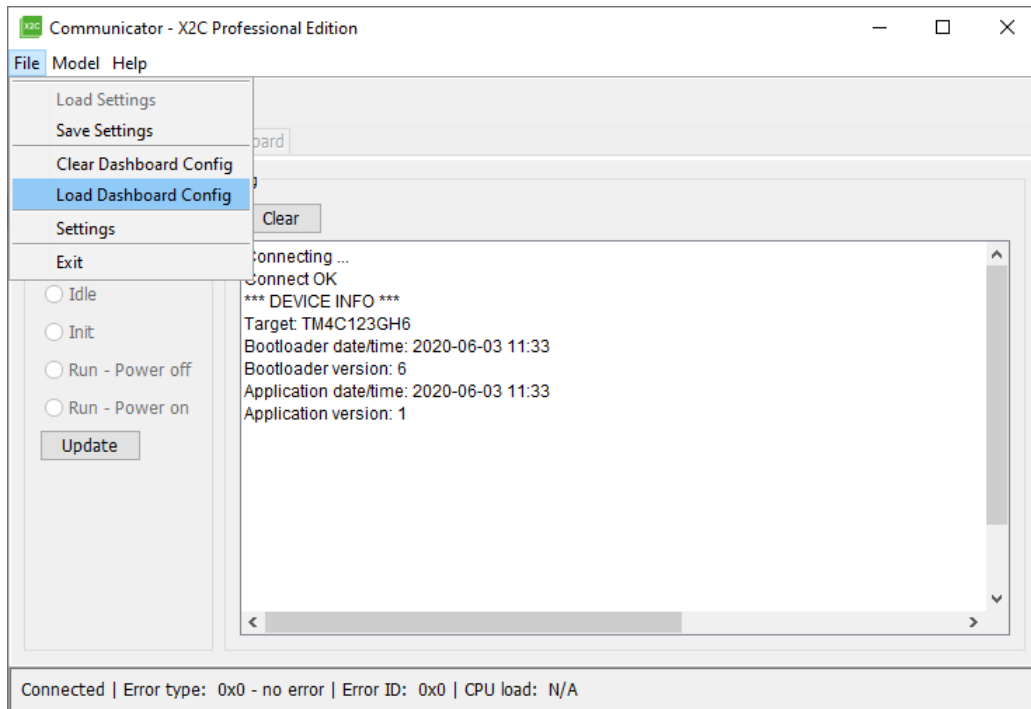


Figure 23: Communicator Dashboard configuration

These elements are usually contained in a configuration file:

Property

A property is defined by a key and value. The syntax is
KEY=VALUE

Example:

MODEL=MyModel.xml

Comment

The hash symbol # introduces a comment line. Every line starting with a hash symbol is ignored by the configuration file parser. Example:

This line is a comment

15.2 Common properties

Each Dashboard element does have common properties independent of its type.

Alias name

If this property is set, the alias name will be displayed instead of the element name. Otherwise the element name is shown.

Property name: ALIAS

Example:

ALIAS=Show this text instead

Offset & Gain

Applies Offset and Gain factors. This allows, for example, the transformation between physical unit and raw value. If one or both values are not set, the appropriate default value is used. The default for GAIN is 1.0, the default for OFFSET is 0.0.

Property name: OFFSET, GAIN

Example:

OFFSET=0.5

GAIN=2.0

ATTENTION:

The Offset and Gain calculation depends on the transfer direction (UPLOAD or DOWNLOAD).

DOWNLOAD (data is transferred from Dashboard to the target):

$$TargetValue = DashboardValue * GAIN + OFFSET$$

UPLOAD (data is transferred from the target to the Dashboard):

$$DashboardValue = (TargetValue - OFFSET) / GAIN$$

Unit

Defines a physical unit. If this property is not set, no unit will be used.

Property name: UNIT

Example:

UNIT=MyUnitName

15.3 Element types

15.3.1 Block-Parameter

Allows to define an X2C Block and one of its Mask Parameters to be downloaded to the target. Following additional properties have to be set to identify the selected X2C Block:

- BLOCK
X2C Block name
- PARAMETER
Mask Parameter name of X2C Block
- MIN
Defines the lower limit for the value
If this value is not defined or empty, no lower limit is active.
- MAX
Defines the upper limit for the value
If this value is not defined or empty, no upper limit is active.
- VALUE
Sets the initial Dashboard value
If this value is not defined, the current Mask Parameter from the Block is used

This element type can currently be used for **download only**.

A complete example for a Block-Parameter element. This first 5 properties are Block-Parameter-type specific, the rest are common properties.

```
BLOCK=MyConstant  
PARAMETER=Value  
VALUE=5.0  
MIN=1.0  
MAX=12.0  
ALIAS=Voltage  
UNIT=V  
GAIN=300.0  
OFFSET=10.0
```

15.3.2 Variables

Allows to define a global symbol (variable) to be uploaded from the target and displayed in the Dashboard. Following additional properties have to be set:

- VARIABLE
Variable name
- TYPE
Data type of the variable

The data type can be one out of the following values:

int8, uint8, int16, uint16, int32, uint32, int64, uint64

The Boolean type is currently not supported. This element type can currently be used for **upload only**.

ATTENTION:

This feature requires a MAP file to be loaded in the Communicator because the target memory addresses for each global variable is extracted from the MAP file generated by the vendors' toolchain. If no MAP file is loaded, the variables will be displayed in the Dashboard View but the 'Start Update' button will remain inactive. If one or more invalid variable names are encountered in the Dashboard configuration file, an error message is shown in the Communicator log for every invalid variable name. Trying to use the 'Start Update' button will result in an error message showing the first invalid variable name.

A complete example for a Variable element. The first 2 properties are Variable-type specific, the rest are common properties.

```
VARIABLE=MyGlobalVar  
TYPE=int16  
ALIAS=Current  
UNIT=A  
GAIN=100.0  
OFFSET=0.0
```

15.4 Model Override

This property allows the Communicator to replace the currently loaded X2C Model or load a new Model at all. The property is optional and can be omitted if not used but must be defined at the beginning of the Dashboard configuration file if used. The value can be a filename or a fully qualified file name containing the complete path.

Property name: MODEL

Example:

MODEL=MyModelFile.xml

MODEL=C:\MyProject\Dashboard.txt

The Communicator log window displays a message if loading the Model from the configuration file was successful.

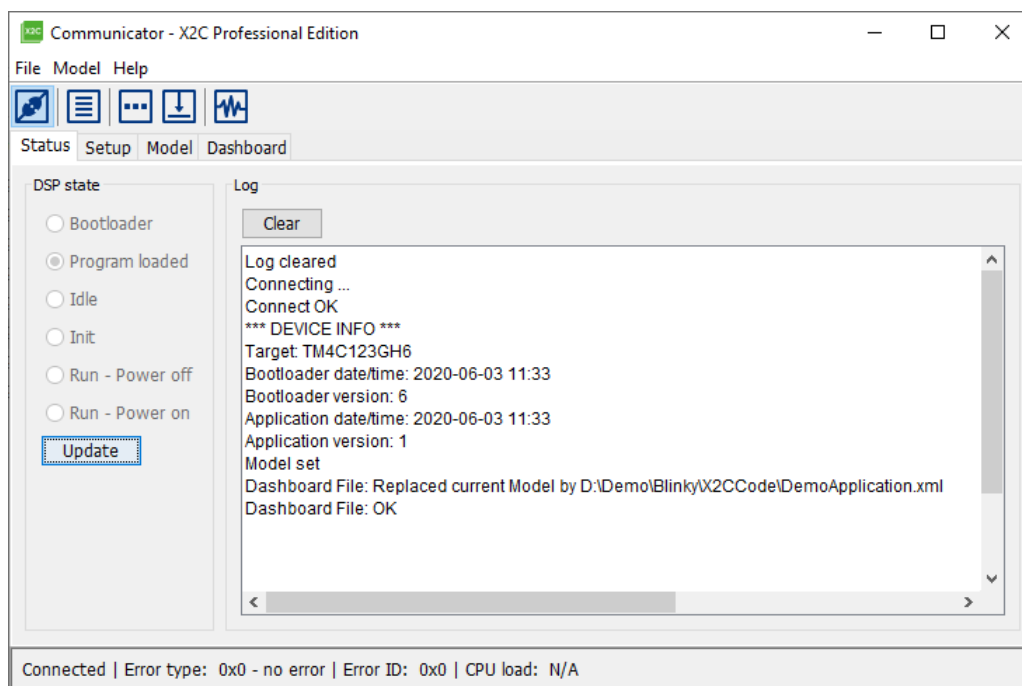


Figure 24: Communicator Dashboard Model log entry

Part V

How-To

16 X2C code generation with *Scilab/Xcos*

The following section describes *X2C* code generation of a *Scilab/Xcos* model based on the *Blinky* demo application.

1. Open *Scilab/Xcos* and in the file browser navigate to your project directory (e.g. <X2C_ROOT>\DemoApplication\Blinky_TI_TMS320F28069_controlSTICK\X2CCode).
2. Double click on **DemoApplication.zcos**. The example project contains a few blocks used to demonstrate the basic function of X2C (see Figure 25). The *Inport* and *Outport* blocks define the interface between the generated X2C code and the peripheral functions (e.g. ADC or GPIO Pins) on the target. For details about each block function read *X2Copen.Doc.pdf* in the documentation folder of the X2C directory.

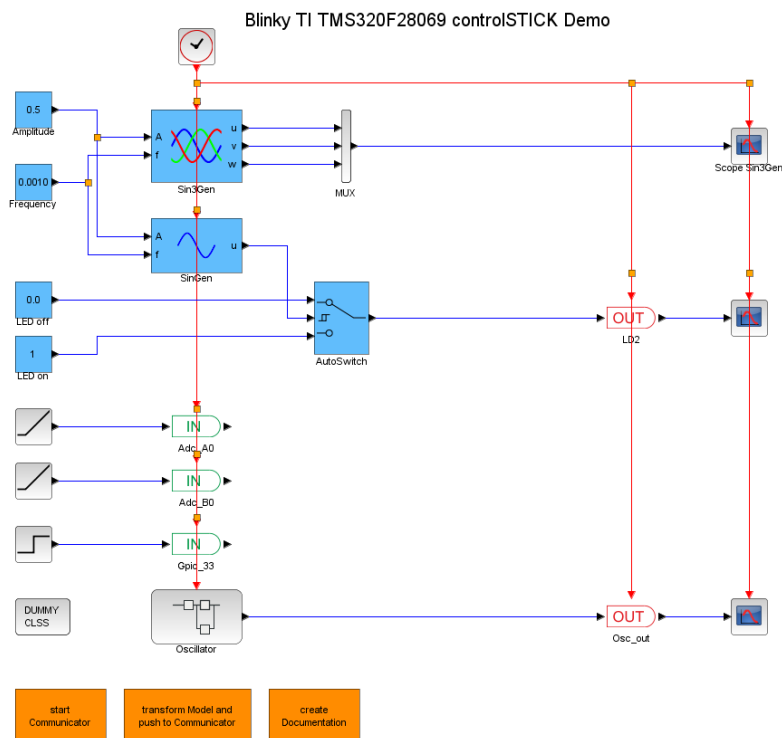


Figure 25: *Blinky* demo application in *Scilab/Xcos*

3. Double click on **start Communicator** (for more information about the *Communicator* see Section 11). Some details of the current actions of the *Communicator* are shown in the *Log* area of the *Communicator* window and the *Scilab/Xcos* command line:

```
1 Starting Communicator
2 done
3 Successfully connected to Communicator
```

4. Double click on **Transform model and push to Communicator** and check the pop-up window for the end of the transformation process.

5. Click **Create Code** in the *Communicator*. Now the files *X2C.h* and *X2C.c* are generated in the <PROJECT_ROOT>\X2CCode directory and the Log screen should contain the lines:

```
1  [...]
2  Model updated
3  Model XML file write: OK
4  Create code successful.
```

6. The *C* code for the *X2C* application has been created. Depending on the used target start the programming tool (e.g. *Code Composer Studio* , *Keil μ Vision* or *MPLAB X*) and import the *Blinky* demo application project as described in Section 17, or 18 respectively. Follow the instructions on how to configure and download the application to the target.

17 Loading and building the demo application Blinky in *Code Composer Studio*

The demo application *Blinky* is intended to be used with a *TI F28069 Piccolo controlSTICK*.

1. Connect the *TI F28069 Piccolo controlSTICK* to the computer.
2. Open *Code Composer Studio* (choose workspace directory as you like). Now click **Project** → **Import Existing CCS Eclipse Project**. Browse to the location of the *Blinky* project (<X2C_ROOT>\DemoApplication\Blinky_TI_TMS320F28069_controlSTICK). Click **Finish** to import the project.
3. In the *Code Composer Studio* file structure of the *Blinky* demo project there are two virtual folders *Blocks* and *Core*, which should be linked directly to the X2C directory. To ensure this go to **Project** → **Properties** drop down **Resource** and click **Linked Resources**. Double click on folder **X2C_ROOT** and set the correct link to your X2C installation directory (<X2C_ROOT>). After hitting **OK** two times there should not be any warning signs (like shown in Figure 26) at the icons for the linked files in the *Blocks* and *Core* folders.

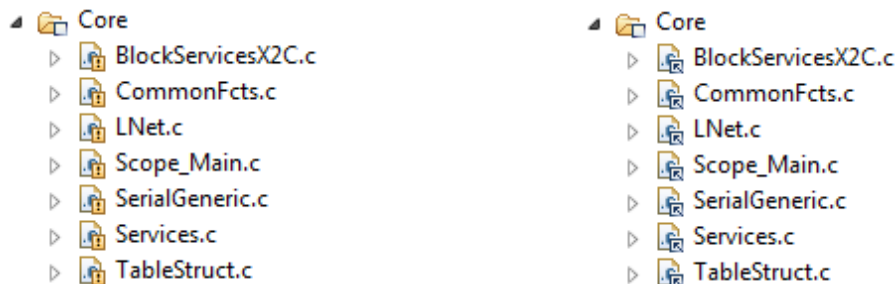


Figure 26: *Code Composer Studio* invalid (left) and valid (right) X2C root directory

4. The generated code from X2C is located in the folder <X2C_ROOT>\DemoApplication\Blinky_TI_TMS320F28069_controlSTICK\X2CCode. To check if code generation went fine go to the X2CCode folder and open *X2C.c*. Make sure time and date of code generation is plausible.
5. Build the project in *Code Composer Studio* by clicking **Project** → **Build all** or by clicking on the **Hammer** symbol as seen in Figure 27 at the top of the screen. Check for errors while building in the console at the bottom of the screen.

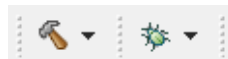


Figure 27: *Code Composer Studio* build and debug buttons

6. If your target is connected to the computer click **Run** → **Debug** or click on the *Bug* symbol as seen in Figure 27 at the top. The program is now transferred to the target and can be started with the **green arrow** button at the top.
7. After starting the program the on-board LED of the *TI F28069 Piccolo controlSTICK* should be blinking!

18 Loading and building the demo application Blinky in MPLAB X

The demo application *Blinky* is build for the combination of the *Microstick II* with the *dsPIC33FJ128MC802* processor and the *MicrostickPlus* developer board (for details see www.microstick.com).

Info: To download a new application only the *Microstick II* needs to be connected with the computer.

1. Connect the *Microstick II* with the computer.
2. Open *MPLAB X* and click **File** → **Open Project**. Browse to the location of the *Blinky* demo application in the *X2C* directory <X2C_ROOT>\DemoApplication\... \Blinky_Microchip_dsPIC33Fxxxx_MicrostickPlus. Click **Open Project**.
3. In the case the demo application is copied/moved to a different location, the include paths have to be adapted. To ensure the compiler uses the correct path variables right click on the **Projectname** → **Properties** → **XC16 Global Options** → **xc16-gcc**. In the drop down menu **Option categories** choose **Preprocessing and messages**. Click on the dots beside **C include dirs**. There are relative paths to the needed include files listed as seen in Figure 28. Correct the links by double clicking on the path variables.
Info: Only the links to the *Library* and *Controller* path need to be updated.

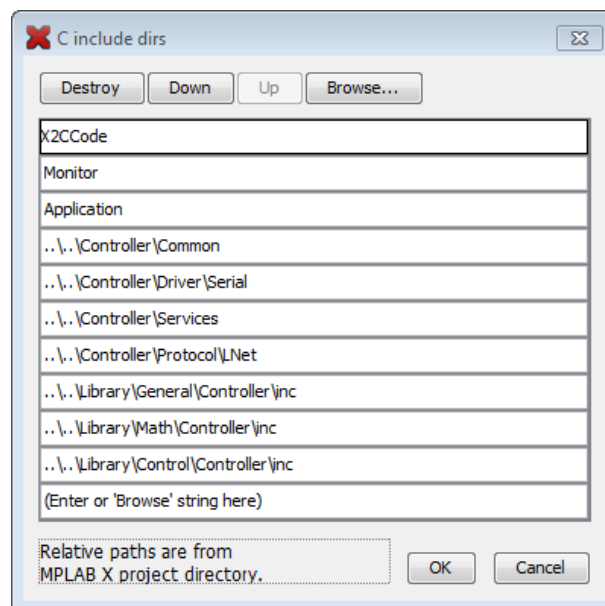


Figure 28: Default path variables for the include files

4. Go to **Run** → **Clean and Build Main Project** or click the *hammer with brush* button as seen in Figure 29. After building there should be a message BUILD SUCCESSFUL in the message area at the bottom of the screen.



Figure 29: MPLAB X Clean and Build Main Project button

5. If the build process was successful go to **Run** → **Run Main Project** or click the *Green*

Arrow button as seen in Figure 29. If there is a message similar to *MICROSTICK not Found* try to select the *Starter Kits (PKOB)* item which represents your board.

6. After starting the program the LED (RB12) on the *MicrostickPlus Board* should be blinking!

19 Loading and building the demo application Blinky in Keil μ Vision

The demo application *Blinky* is intended to be used with the *ST STM32F051R8 Discovery* or the *ST STM32F072RB Nucleo* kit.

1. Connect the ST development kit with the computer. You may have to install the ST-Link USB driver (available on www.stm.com) to get the board recognized by your operating system.
2. Open *Keil μ Vision* and click **Project** → **Open Project**. Browse to the location of the *Blinky* project (either <X2C_ROOT>\DemoApplication\Blinky_ST_STM32F051R8_Discovery or <X2C_ROOT>\DemoApplication\Blinky_ST_STM32F072RB_Nucleo). Click **Open** to import the project.
3. In the *Keil μ Vision* file structure of the *Blinky* demo project are two virtual folders *Blocks* and *Core*, which are linked relatively to the *X2C* directory. If the *Blinky* demo project is copied/moved to a different location, the include paths as seen in Figure 30 have to be adapted.

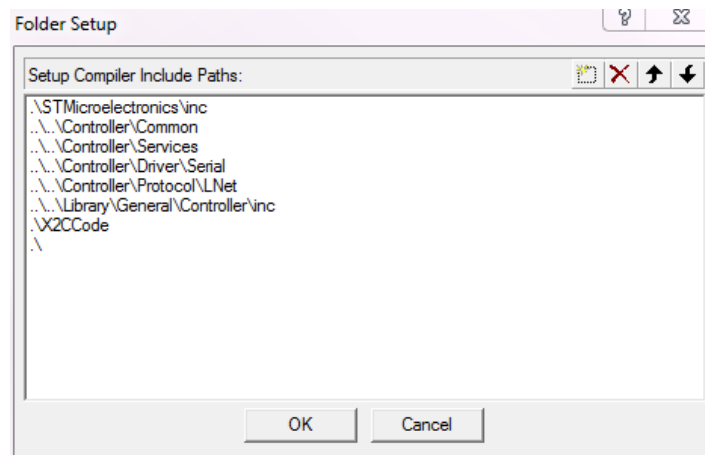


Figure 30: Keil μ Vision include paths setting

To open shown window go to **Project** → **Options for target 'Blinky Demo'** change to tab **C/C++** and click ... next to the include paths text field.

4. The generated code from *X2C* is located in the *X2CCode* folder (eg. <X2C_ROOT>\DemoApplication\Blinky_ST_STM32F072RB_Nucleo\X2CCode). To check if code generation went fine go to the *X2CCode* folder and open *X2C.c*. Make sure time and date of code generation are plausible.
5. Build the project in *Code Composer Studio* by clicking **Project** → **Build target** or by clicking on the *Build* symbol as seen in Figure 31 at the top left of the *Keil μ Vision* screen. Check for errors while building in the console at the bottom of the screen.



Figure 31: Keil μ Vision build and load buttons

6. If your target is connected to the computer click **Flash** → **Download** or click on the *Download* symbol as seen in Figure 31 at the top left of the *Keil μ Vision* screen. The program is now transferred to the target and is automatically started.

7. After starting the program the green on-board LED of the ST development kit should be blinking!
8. To use *X2C Communicator* and *Scope* the computer has to be connected via serial interface to the development kit. Early versions of the *ST STM32F051R8 Discovery* kit do not support virtual COM port over USB. In this case a TTL-level compatible RS-232 adapter has to be connected to pin PA9 - TxD, PA10 - RxD and GND.

20 The creation of an external project-specific X2C block

The creation of an external project-specific X2C block is summarized in three steps by the subsequent three subsections.

20.1 The creation of the basic structure

The first step in the creation of an external project-specific X2C block is the creation of its basic structure using *X2C Block Generator* previously described in Section 13. *X2C Block Generator* can be initiated by executing the `BlockGenerator.jar` file located in `<X2CRoot>\System\Java\`. Once executed, *X2C Block Generator* opens up in the form of the GUI shown in Figure 32 whose options are described hereafter.

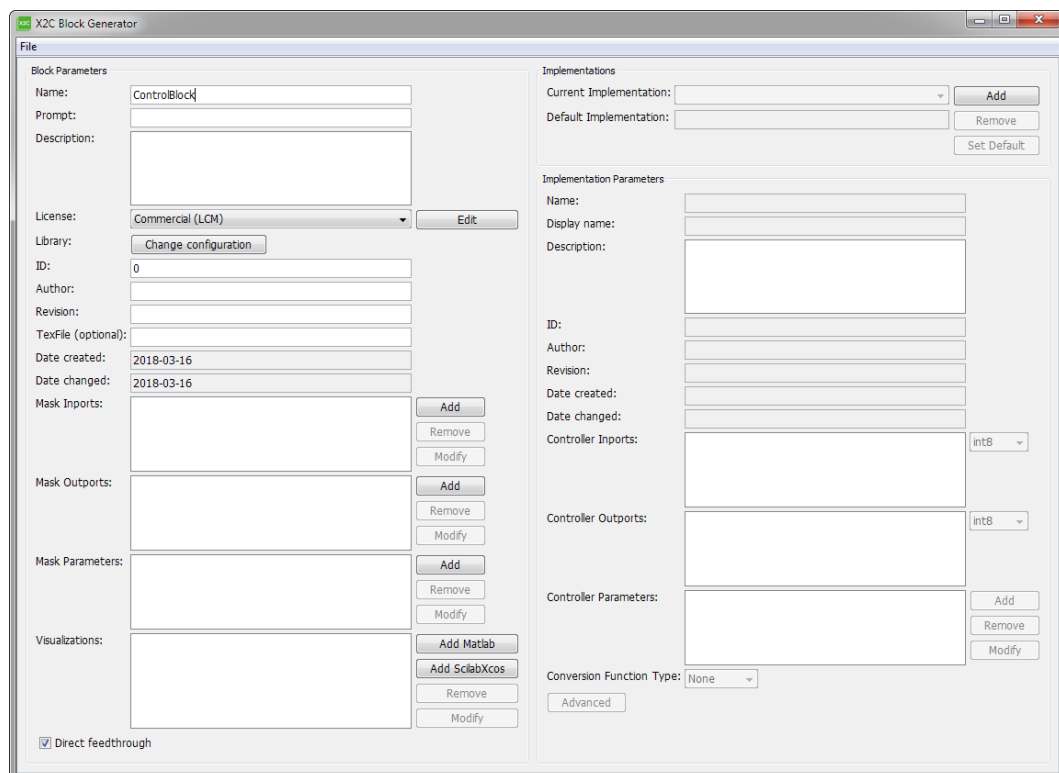


Figure 32: The initial appearance of the *X2C Block Generator* GUI

Block Parameters

- **Name** of the block needs to be uniquely specified for the unambiguous identification of the block in the library and the MATLAB Simulink or Scilab Xcos model.
- **Prompt** is displayed in the help of the block in Scilab Xcos.
- **Description** of the block is displayed in the dialog window of the block in both MATLAB Simulink and Scilab Xcos and should describe the purpose of the block.
- **License** can be selected from the drop-down menu that contains various options or it can be manually defined by clicking on the **Edit** push-button.
- **Library** needs to be specified by clicking on the **Change Configuration** push-button that opens up the *Library Configuration* window in which the **External** radio-button should be selected. By doing so, the **Library Name** and **Pre-Namespace** text-fields become available. It is mandatory to save the library in the `<ProjectRoot>` folder (i.e. the folder that contains the `X2CCode` folder).

- **Library Name** should be uniquely specified.
- **Pre-Namespace** is used for Java conversion functions and can be arbitrarily selected. For example the library name can be entered here as well.
- **ID** needs to be an unique integer number between 4000 and 8191, including those two limits.
- **Author** of the block should be specified.
- **Revision** should be specified to enable the distinction between different software versions of the block.
- **T_EX File** containing a description of the block in the L^AT_EX format that can be optionally created for the documentation of the block. When writing display math, it is advisable not to use environments provided by the `amsmath` package. Instead, `displaymath`, `equation`, `array`, and `eqnarray` should be used for consistent rendering of display equations by J^AT_EX in the generated `.html` file. The name of the `.tex` file should differ from the name of the block. (Internal convention is `<BlockName>_Info.tex`).
- **Date Created** is automatically specified upon the creation of the block.
- **Date Changed** is automatically specified every time the block is changed.
- **Mask Inports** are user interfaces that need to be defined for all inputs of the block by clicking on the **Add** push-button that opens up the *Mask Inport* window in which the **Name** and **Description** text-fields under the **Parameters** section become available. Every mask inport can also be removed or edited by clicking on the **Remove** or **Modify** push-button, respectively.

– Parameters

- * **Name** is displayed in the documentation of the block.
- * **Description** is displayed in the documentation of the block.
- **Mask Outputs** are user interfaces that need to be defined for all outputs of the block by clicking on the **Add** push-button that opens up the *Mask Output* window in which the **Name** and **Description** text-fields under the **Parameters** section become available. Every mask output can also be removed or edited by clicking on the **Remove** or **Modify** push-button, respectively.

– Parameters

- * **Name** is displayed in the documentation of the block.
- * **Description** is displayed in the documentation of the block.
- **Mask Parameters** are user interfaces that need to be defined for all parameters of the block by clicking on the **Add** push-button that opens up the *Mask Parameter* window in which the **Name**, **Prompt**, and **Description** text-fields together with the **Data Type** drop-down menu under the **Parameters** section become available. Every mask parameter can also be removed or edited by clicking on the **Remove** or **Modify** push-button, respectively.

– Parameters

- * **Name** is displayed in the documentation of the block.
- * **Prompt** is displayed in the dialog window of the block in both MATLAB Simulink and Scilab Xcos.
- * **Description** is displayed in the documentation of the block and the dialog window of the block in both MATLAB Simulink and Scilab Xcos.

- * **Data Type** can be selected from the drop-down menu to be either **Double** or **ComboBox** as well as **Visible** and/or **Changeable** by the available check-boxes.
- **Data Type Parameters**
 - * **Default** value of the parameter needs to be specified in the case of **Data Type: Double**.
 - * **Add** or **Remove** push-buttons become available for adding items in the case of **Data Type: ComboBox**.
- **Visualizations** of the block can be separately defined for MATLAB Simulink by clicking on the **Add Matlab** push-button as well as for Scilab Xcos by clicking on the **Add ScilabXcos** push-button.
 - **Visualization Parameters** for MATLAB Simulink
 - * **Command** can contain labels of the block and its input(s) and output(s) that can be defined as:


```
disp('\fontsize12<BlockLabel>', 'texmode', 'on')
port_label('input', '<InputNumber>', '<InputLabel>',
'texmode', 'on')
port_label('output', '<OutputNumber>', '<OutputLabel>',
'texmode', 'on')
```
 - **Visualization Parameters** for Scilab Xcos
 - * **Define Section** defines options of the block in the `x2c_<BlockName>.sci` script between `// ++ BlockGenerator: Define Section` and `// - BlockGenerator: Define Section`.
 - * **Block Icon Default Size** defines the size of the block in Scilab Xcos units in the `x2c_<BlockName>.sci` script between `// ++ BlockGenerator: BlockIconDefaultSize` and `// - BlockGenerator: BlockIconDefaultSize`.
 - * **Plot Section** defines options of the block in the `x2c_<BlockName>.sci` script between `// ++ BlockGenerator: Style` and `// - BlockGenerator: Style`.
 - * **Style** defines options of the block in the `starter.sce` script between `// ++ BlockGenerator: Plot Section` and `// - BlockGenerator: Plot Section`.
- **Direct Feedthrough** should be generally checked. It should be unchecked when the block serves as a breaker of an algebraic loop.

Implementations

- **Current Implementation** serves as an identifier of the current implementation and can be arbitrarily named, whereby multiple implementations are possible. The internal naming convention of LCM defines **Bool** (Boolean), **FiP8** (8 Bit Fixed Point), **FiP16** (16 Bit Fixed Point), **FiP32** (32 Bit Fixed Point), **Float32** (32 Bit Floating Point), and **Float64** (64 Bit Floating Point) as implementations. A new implementation can be defined by clicking on the **Add** push-button as well as removed by clicking on the **Remove** button.
- **Default Implementation** can be selected by choosing the desired implementation from the **Current Implementation** drop-down menu (if multiple available) and clicking on the **Set Default** push-button.

Implementation Parameters

- **Name** is automatically taken from the **Current Implementation** drop-down menu and every change in the text-field directly renames the selected implementation in the **Current Implementation** drop-down menu. The internal naming convention of LCM defines **Bool**, **FiP8**, **FiP16**, **FiP32**, **Float32**, and **Float64** as names.
- **Display Name** of the current implementation is displayed in the dialog window of the block in the **Used Implementation** drop-down menu. The internal naming convention of LCM defines **Boolean**, **8 Bit Fixed Point**, **16 Bit Fixed Point**, **32 Bit Fixed Point**, **32 Bit Floating Point**, and **64 Bit Floating Point** as display names. This name is used for naming of the corresponding C and Java files.
- **Description** of the current implementation in the documentation of the block. The internal naming convention of LCM defines **Boolean Implementation**, **8 Bit Fixed Point Implementation**, **16 Bit Fixed Point Implementation**, **32 Bit Fixed Point Implementation**, **32 Bit Floating Point Implementation**, or **64 Bit Floating Point Implementation** as descriptions.
- **ID** of the current implementation needs to be an integer number between 0 and 15, including those two limits.
- **Author** of the current implementation should be specified.
- **Revision** of the current implementation should be specified to enable distinction between different implementations of the block.
- **Date Created** is automatically specified upon the creation of the current implementation.
- **Date Changed** is automatically specified every time the current implementation is changed.
- **Controller Inputs** of the current implementation need to be defined with respect to **Mask Imports**, whereby the data type can be selected from the drop-down menu.
- **Controller Outputs** of the current implementation need to be defined with respect to **Mask Outputs**, whereby the data type can be selected from the drop-down menu.
- **Controller Parameters** of the current implementation need to be defined with respect to **Mask Outputs** together with any additional internal parameter can also be defined) by clicking on the **Add** push-button that opens up the *Controller Parameter* window in which the **Name**, **Description**, and **Default Value** text-fields together with the **Data Type** drop-down menu and the **Load & Save Enable** and **Array** check-boxes under the **Controller Parameters** section become available. Every controller parameter can also be removed or edited by clicking on the **Remove** or **Modify** push-button, respectively.

– Controller Parameters

- * **Name** is displayed in the dialog window of the block in both MATLAB Simulink and Scilab Xcos and denotes a parameter of the block.
- * **Description** is displayed in the dialog window of the block in both MATLAB Simulink and Scilab Xcos and should describe the parameter of the block.
- * **Data Type** determines the data type that is to be used on the target.
- * **Default Value** sets the default value of the parameter.
- **Conversion Function Type** can be selected from the drop-down menu between **Java**, **Python**, and **JavaScript**. After selecting the conversion function type, a template of the conversion function used for the conversion of mask parameters, which are of the type

double, into the data type of the current implementation is generated. The template needs to be manually adapted. If there are no mask parameters, no conversion function is necessary.

20.2 Coding the source file

The functionality of the block needs to be manually implemented in the automatically generated `<BlockName>_<Implementation>.c` source file located in `<ProjectRoot>\Library\<LibraryName>\Controller\src\`. In that source file, everything between each pair of the comments `/* USERCODE-BEGIN: ... */` and `/* USERCODE-END: ... */` stays unchanged even if the source file is regenerated by *X2C Block Generator*. Between the first pair of such comments, namely `/* USERCODE-BEGIN:Description */` and `/* USERCODE-END:Description */`, a short description of the block can be written in the form of comments. The definitions of the input(s) and the output(s) as well as parameters, variables, constants, and if necessary, the inclusions of header files should be defined between `/* USERCODE-BEGIN:PreProcessor */` and `/* USERCODE-END:PreProcessor */` as

```
#include "<HeaderFile>.h"
#define <INPUT>      (*pT<BlockName>_<Implementation>-><ControllerInput>)
#define <OUTPUT>     (pT<BlockName>_<Implementation>-><ControllerOutput>)
#define <PARAMETER> (pT<BlockName>_<Implementation>-><ControllerParameter>)
#define <VARIABLE>   (pT<BlockName>_<Implementation>-><ControllerParameter>)
#define <CONSTANT>   <HexadecimalValue>
```

The functionality of the block should be defined between `/* USERCODE-BEGIN:UpdateFnc */` and `/* USERCODE-END:UpdateFnc */` and can be demonstrated by an example in a `FiP16` implementation as

```
int32 <Result>;
<Result> = (int32)<INPUT> * (int32)<VARIABLE>;
<Result> >>= <PARAMETER>;
<Result> += (int32)<CONSTANT>;
if (<Result> > INT16_MAX)
{
    <Result> = INT16_MAX;
}
else
{
    if (<Result> < -INT16_MAX)
    {
        <Result> = -INT16_MAX;
    }
}
<OUTPUT> = (int16)<Result>;
```

The initial values of used variables can be specified between `/* USERCODE-BEGIN:InitFnc */` and `/* USERCODE-END:InitFnc */` as

```
<Variable> = 0;
```

...between `/* USERCODE-BEGIN:LoadFnc */` and `/* USERCODE-END:LoadFnc */` and between `/* USERCODE-BEGIN:SaveFnc */` and `/* USERCODE-END:SaveFnc */`...???

20.3 Coding the conversion function

If the block uses mask parameters, the conversion function, which converts the mask parameters into controller parameters, has to be implemented in the corresponding programming language as well. The template of the conversion function is located in `<ProjectRoot>\Library\<LibraryName>\Conversion\<ConversionType>\.`

20.3.1 A conversion function in Java

In the case of Java, the conversion function of the block needs to be manually implemented in the automatically generated `ConvFnc_<BlockName>_<Implementation>.java` file located in `<ProjectRoot>\Library\<LibraryName>\Conversion\Java\src\...` Furthermore, **Eclipse** needs to be installed on the system and the project imported into the workspace via the menu bar as **File** \Rightarrow **Import...** \Rightarrow **General** \Rightarrow **Existing Project**. Under **Project** \Rightarrow **Build Automatically** needs to be enabled and by right-clicking on the project in the project tree, under **Properties** \Rightarrow **Java Compiler** \Rightarrow **Compiler Compliance Level** needs to be set to **1.6**. In the above mentioned file, everything between each pair of the comments `// USERCODE-BEGIN:` and `// USERCODE-END:` stays unchanged even if the source file is regenerated by *X2C Block Generator*. User-defined Java classes like

```
import at.lcm.x2c.utils.QFormat;
```

can be loaded between `// USERCODE-BEGIN:Imports` and `// USERCODE-END:Imports`, while the conversion of the controller parameters from the mask into the designated implementation needs to be written between `// USERCODE-BEGIN:ConvMaskToImplementation` and `// USERCODE-END:ConvMaskToImplementation` and can be demonstrated by an example in a `FiP16` implementation as

```
double <ControlParameter>;
final int BITS = 16;

// Getting the value of the mask parameter:
<ControlParameter> = Double.valueOf(<MaskParameter>MaskVal.getValue());

// Calculating the shift factor:
<ShiftFactor>CtrVal.setReal(0, 0, Double.valueOf(QFormat.getQFormat(
    <ControlParameter>, BITS, true)));

// Calculating the Q-value:
<ControlParameter>CtrVal.setReal(0, 0, Double.valueOf(QFormat.getQValue(
    <ControlParameter>, (int)(<ShiftFactor>CtrVal.getReal(0, 0)), BITS,
    true)));
```

The conversion of the controller parameters from the designated implementation into the mask needs to be written between `// USERCODE-BEGIN:ConvImplementationToMask` and `// USERCODE-END:ConvImplementationToMask` as

```
double <ControlParameter>, <ShiftFactor>;
final int BITS = 16;

// Getting the Q-value:
<ControlParameter> = <ControlParameter>CtrVal.getReal(0, 0);

// Getting the shift factor:
<ShiftFactor> = <ShiftFactor>CtrVal.getReal(0, 0);
```

```
// Calculating the value of the mask parameter:
<MaskParameter>MaskData.setReal(0, 0, QFormat.getDecValue(
    (long)<ControlParameter>, (int)<ShiftFactor>, BITS, true));
```

20.3.2 A conversion function in JavaScript

In the case of JavaScript, two JavaScript script files are automatically generated in `<ProjectRoot>\Library\<LibraryName>\Conversion\JavaScript\src\...`, where one is used for the conversion of the mask parameters to the implementation parameters, while the other one is used for the conversion of the implementation parameters to the mask parameters. The conversion of the mask parameters to the implementation parameters needs to be manually implemented in `ConvertMask2Imp_<BlockName>_<Implementation>.js`, while the conversion of the implementation parameters to the mask parameters needs to be implemented in `ConvertImp2Mask_<BlockName>_<Implementation>.js`. Both files contain `/* USERCODE-BEGIN:Description */` and `/* USERCODE-END:Description */` as well as `/* USERCODE-BEGIN:ExternalModules */` and `/* USERCODE-END:ExternalModules */`, where between the first pair a short description of the conversion function can be written, while between the second pair external modules can be imported. The conversion of the mask parameters to the implementation parameters comes between `/* USERCODE-BEGIN:Convert */` and `/* USERCODE-END:Convert */` in the first file, while the conversion of the implementation parameters to the mask parameters comes between `/* USERCODE-BEGIN:Revert */` and `/* USERCODE-END:Revert */` in the second file.

20.3.3 A conversion function in Python

Similar to the case of JavaScript, in the case of Python, two Python scripts are automatically generated in `<ProjectRoot>\Library\<LibraryName>\Conversion\Python\src\...`, where the `ConvertMask2Imp_<BlockName>_<Implementation>.py` script is used for the conversion of the mask parameters to the implementation parameters, while the `ConvertImp2Mask_<BlockName>_<Implementation>.py` script is used for the conversion of the implementation parameters to the mask parameters. The scripts are structurally identical to the above described JavaScript script files containing `# USERCODE-BEGIN: ...` and `# USERCODE-END: ...` sections, where the only difference is the scripting language.

20.4 Finalizing the block in Scilab

In Scilab execute the command `createXcosBlock('<LibraryName>', '<BlockName>', '<ProjectRoot>')`.

20.5 The block in Code Composer Studio 7

After including the project in Code Composer Studio 7, the library should be listed in the project tree. Before compiling, it is necessary to exclude the **Matlab** and **Conversion** folders from the build.

21 Setup X2C for use in a *B&R® Automation Studio®* project

X2C allows the user to modify an already created *Automation Studio®* project for use with X2C and generate the corresponding code. Therefore several configuration parameters have to be set.

21.1 Configuration

- Setup a new *Automation Studio®* project or use an existing one
- Head to the Communicator settings and configure the the *Automation Studio®* specific parts
 1. Enable the "Create Automation Studio code" option
 2. Select the project APJ file. After a valid project is selected, the configuration menu is updated and contains all project configurations. Further Settings elements will be enabled and updated.
 3. Select a configuration, a CPU module and a Application task class. This becomes the task in which the X2C Update function is called.
 4. Enable the Communication option in case TCP/IP communication should be used for online X2C Block parameter updates or Scope usage. After enabling, the task class for the X2C communication task and the TCP port can be selected.
 5. The "Use library" option allows you to use X2C as *Automation Studio®* library block.
 6. Sets the X2C Scope buffer size. This buffer is used to cache the sampled data if the Scope feature is used.

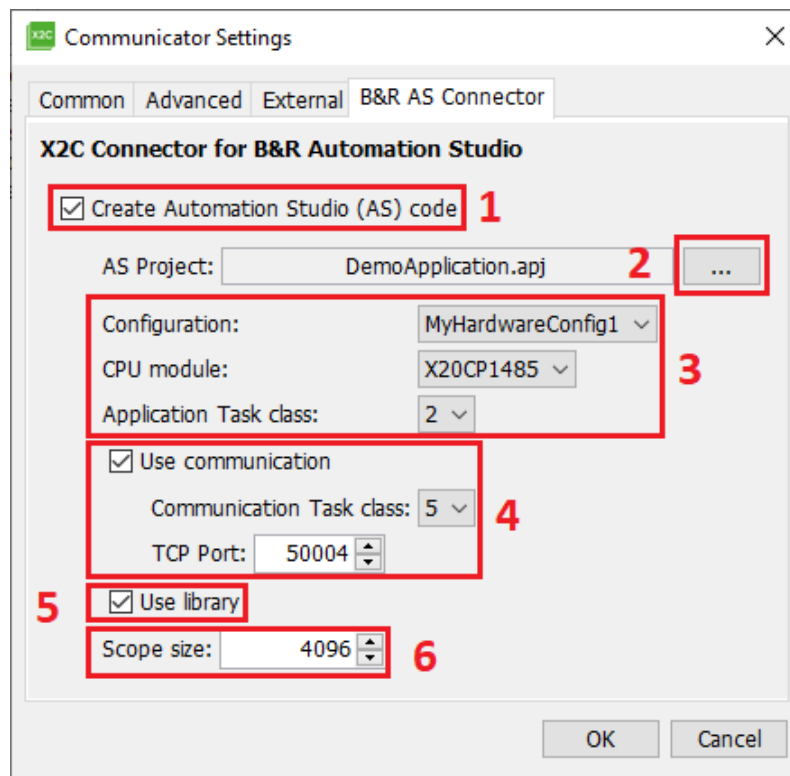


Figure 33: X2C Connector for *B&R® Automation Studio®* settings

- Confirm the changes by pressing the OK button

- Generate the *X2C* code as usual

All required *X2C* and *Automation Studio*® files will be created. The Automation Studio configuration files are being updated to include the newly generated *X2C* code.

21.2 Logical View

Now we can head over to *Automation Studio*® to check the modifications and build the project. *Automation Studio*® may ask you to reload changed components.

The "Logical View" should have been updated by X2C content as well as the Software configuration file in the "Configuration View". In case of enabled Communication, the *B&R*® library "AsTCP", required for TCP/IP communications, is added to your project libraries.

Therefore your *Automation Studio*® project may look like this:

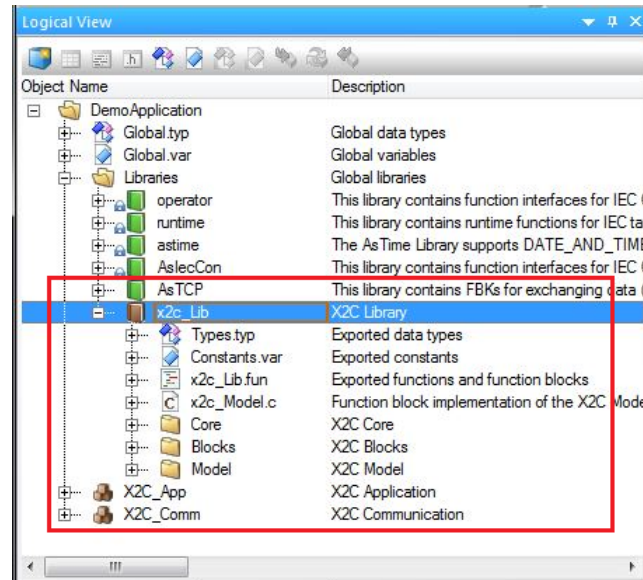


Figure 34: *Automation Studio*® Logical View

This example shows the added

- *B&R*® AsTCP library
- X2C as *Automation Studio*® library
- X2C application program package
- X2C communication program package

21.3 Software Configuration

The software configuration file shows the newly added programs and libraries.

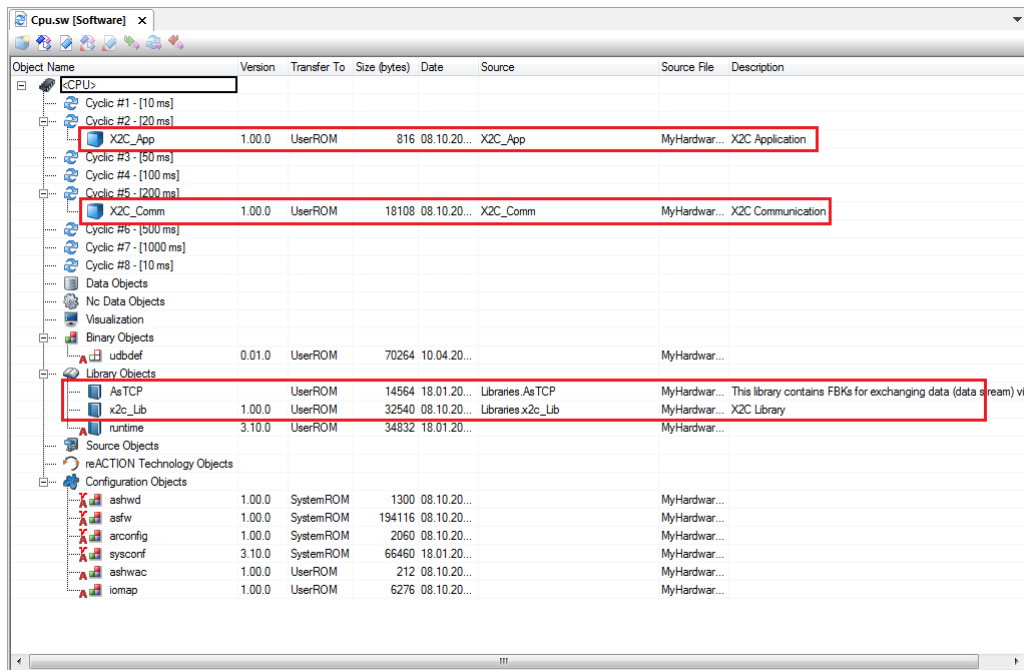


Figure 35: Automation Studio® Software Configuration

21.4 Communication configuration

In case of enabled communication don't forget to configure the Ethernet and TCP/IP settings for your hardware in Automation Studio®.

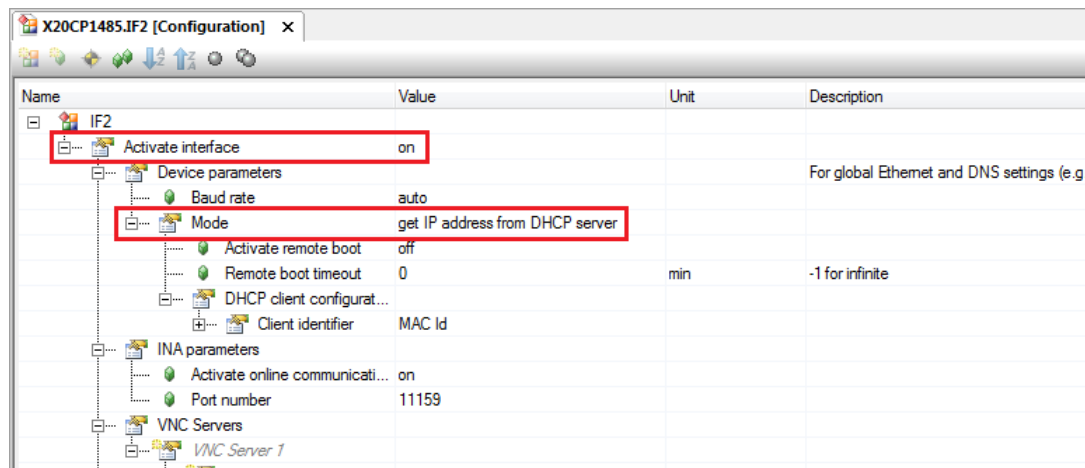


Figure 36: Automation Studio® Ethernet configuration using DHCP (X20CP1485)

The X2C integration is now complete and the Automation Studio® project is ready to be built.

Part VI

Libraries

22 Basic

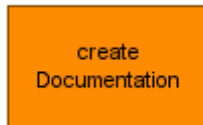
Block: CommunicatorStart (Xcos only)



Description:

With a double-click on this block, the X2C Communicator will start. The Communicator will connect to Scilab via Java Remote Method Invocation (Java RMI) to enable data exchange between Scilab and X2C.

Block: CreateDocumentation



Description:

With a double-click on this block, a documentation with all relevant information about the current X2C project can be created. The document will be created in `<ProjectDir>\Doc` and will be called `ProjectDocumentation_<NameOfModel>.pdf`.

Parameters

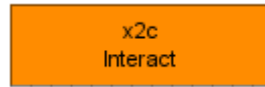
User documentation: It is possible to add user specific documentation to the project documentation. When creating the project documentation, the `X2CCode` directory is scanned for the specified tex file (`UserDoc.tex` by default). If the file is present, it will be included in the documentation.

Test reports: If the checkbox *Add test reports* is selected, test reports of the C-Unit tests of the used X2C blocks are added to the project documentation.

Requirements

In order to generate a documentation in PDF-format a TeX-compiler (e.g. *MiKTeX*) has to be installed. The software tools *Doxygen* and *Graphviz* are recommended to get documentation of the C-code.

Block: Interact (Xcos only)



Description:

When double-clicked, the block executes the Scilab script *doInteraction.sci*, if available. By customizing the script, the user can execute simple tasks, e.g. setting block parameters, read parameter values, display status information, etc., repeatedly and effortlessly.

Block: ModelTransformation (Xcos only)



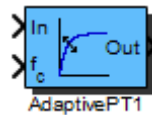
transform Model and
push to Communicator

Description:

With a double-click on this block, the Xcos model will be analyzed. All relevant information for code generation are gathered, transfered to the Communicator and written to the model XML file.

23 Control

Block: AdaptivePT1



Inports	
In	Input In(k)
fc	Cutoff frequency

Outputs	
Out	Output Out(k)

Mask Parameters		
Name	ID	Description
V	1	Gain
fmax	2	Maximum frequency [Hz] (not used in floating point implementations)
ts_fact	3	Multiplication factor of base sampling time (in integer format)
method	4	Discretization method

Description:

First order low pass with adaptive cut off frequency:

$$G(s) = V/(s/(2\pi fc) + 1)$$

Transfer function (zero-order hold discretization method):

$$G(z) = V \frac{1 - e^{-2\pi fc T_s}}{z - e^{-2\pi fc T_s}}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8
fc	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
fc	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
fc	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
fc	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
fc	float64

Outports Data Type	
Out	float64

Block: Delay



Inports	
In	Input In(k)

Outputs	
Out	Output Out(k)=In(k-1)

Mask Parameters		
Name	ID	Description
ts_fact	1	Multiplication factor of base sampling time (in integer format)

Description:

Output delay by one sample time interval.

This block can be used to enable feedback loops in the model.

Implementations:

Bool	Boolean Integration
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: Bool

Boolean Integration

Inports Data Type	
In	bool

Outputs Data Type	
Out	bool

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outputs Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outputs Data Type	
Out	float32

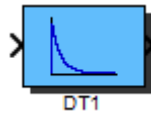
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outputs Data Type	
Out	float64

Block: DT1



Inports	
In	Input In(k)

Outputs	
Out	Output Out(k)

Mask Parameters		
Name	ID	Description
V	1	Gain
fc	2	Cut off frequency of low pass filter
ts_fact	3	Multiplication factor of base sampling time (in integer format)
method	4	Discretization method

Description:

First order high pass:

$$G(s) = V \cdot s / (s/w + 1)$$

Due to limited value range in the 8 bit fixed point implementation rather high deviations from expected output values may occur.

Developer note: The source code of block *TF1* is used.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outputs Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outputs Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outputs Data Type	
Out	float32

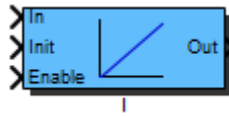
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: I



Inports	
In	Control error input
Init	Value which is loaded at initialization function call
Enable	Enable == 0: Deactivation of block; Out set to 0 Enable 0->1: Preload of integral part Enable == 1: Activation of block

Outputs	
Out	Control value

Mask Parameters		
Name	ID	Description
Ki	1	Integral Factor
ts_fact	2	Multiplication factor of base sampling time (in integer format)

Description:

I controller:

$$G(s) = K_i/s = 1/(T_i \cdot s)$$

Each fixed point implementation uses the next higher integer datatype for the integrational value storage variable.

A rising flank at the *Enable* input will preload the integrational part with the value present on the *Init* input.

Transfer function (zero-order hold discretization method):

$$G(z) = K_i T_s \frac{1}{z - 1}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8
Init	int8
Enable	bool

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
Enable	bool

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
Enable	bool

Outports Data Type	
Out	float32

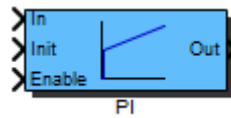
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
Enable	bool

Outports Data Type	
Out	float64

Block: PI



Inports	
In	Control error input
Init	Value which is loaded at initialization function call
Enable	Enable == 0: Deactivation of block; Out set to 0 Enable 0->1: Preload of integral part Enable == 1: Activation of block

Outputs	
Out	

Mask Parameters		
Name	ID	Description
Kp	1	Proportional Factor
Ki	2	Integral Factor
ts_fact	3	Multiplication factor of base sampling time (in integer format)

Description:

PI controller:

$$G(s) = K_p + K_i/s$$

Each fixed point implementation uses the next higher integer data type for the integral value storage variable.

A rising flank at the *Enable* inport will preload the integral part with the value present on the *Init* inport.

Transfer function (zero-order hold discretization method):

$$G(z) = K_p + K_i T_s \frac{1}{z - 1}$$

Developer note: For the fixed point implementations the source code of block [Block: PILimit](#) is used.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8
Init	int8
Enable	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
Enable	bool

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
Enable	bool

Outputs Data Type	
Out	float32

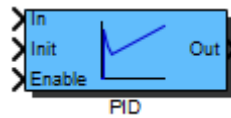
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
Enable	bool

Outputs Data Type	
Out	float64

Block: PID



Inports	
In	Control error input
Init	Value which is loaded at initialization function call
Enable	Enable == 0: Deactivation of block; Out set to 0 Enable 0->1: Preload of integral part Enable == 1: Activation of block

Outputs	
Out	

Mask Parameters		
Name	ID	Description
Kp	1	Proportional Factor
Ki	2	Integral Factor
Kd	3	Derivative Factor
fc	4	Cutoff frequency of realization low pass
ts_fact	5	Multiplication factor of base sampling time (in integer format)

Description:

PID controller:

$$G(s) = K_p + K_i/s + K_d*s/(s/(2*\pi*fc) + 1)$$

Each fixed point implementation uses the next higher integer datatype for the integrational value storage variable.

A rising flank at the *Enable* inport will preload the integrational part with the value present on the *Init* inport.

Transfer function (zero-order hold discretization method):

$$G(z) = K_p + K_i T_s \frac{1}{z-1} + K_d 2\pi f_c \frac{z-1}{z - e^{-2\pi f_c T_s}}$$

FiP8 bug: When using the TI compiler the step response of the derivative part does not return to zero, but generates an overflow at zero crossing if the derivative parameter value is too high.

Developer note: For the fixed point implementations the source code of block *PIDLimit* is used.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8
Init	int8
Enable	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
Enable	bool

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
Enable	bool

Outputs Data Type	
Out	float32

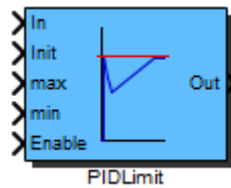
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
Enable	bool

Outputs Data Type	
Out	float64

Block: PIDLimit



Inports	
In	Control error input
Init	Value which is loaded at initialization function call
max	Maximum output value
min	Minimum output value
Enable	Enable == 0: Deactivation of block; Out set to 0 Enable 0->1: Preload of integral part Enable == 1: Activation of block

Outputs	
Out	

Mask Parameters		
Name	ID	Description
Kp	1	Proportional Factor
Ki	2	Integral Factor
Kd	3	Derivative Factor
fc	4	Cutoff frequency of realization low pass
ts_fact	5	Multiplication factor of base sampling time (in integer format)

Description:

PID Controller with Output Limitation:

$$G(s) = K_p + K_i/s + K_d*s/(s/(2*\pi*fc) + 1)$$

Each fixed point implementation uses the next higher integer datatype for the integrational value storage variable.

A rising flank at the *Enable* inport will preload the integrational part with the value present on the *Init* inport.

Transfer function (zero-order hold discretization method):

$$G(z) = K_p + K_i T_s \frac{1}{z-1} + K_d 2\pi f_c \frac{z-1}{z - e^{-2\pi f_c T_s}}$$

FiP8 bug: When using the TI compiler the step response of the derivative part doesn't return to zero, but generates an overflow at zero crossing if the derivative parameter value is

too high.

Developer note: The fixed point implementation source code of this block is used for block *PID*.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8
Init	int8
max	int8
min	int8
Enable	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
max	int16
min	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
max	int32
min	int32
Enable	bool

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
max	float32
min	float32
Enable	bool

Outports Data Type	
Out	float32

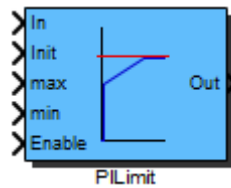
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
max	float64
min	float64
Enable	bool

Outports Data Type	
Out	float64

Block: PILimit



Inports	
In	Control error input
Init	Value which is loaded at initialization function call
max	Maximum output value
min	Minimum output value
Enable	Enable == 0: Deactivation of block; Out set to 0 Enable 0->1: Preload of integral part Enable == 1: Activation of block

Outputs	
Out	

Mask Parameters		
Name	ID	Description
Kp	1	Proportional Factor
Ki	2	Integral Factor
ts_fact	3	Multiplication factor of base sampling time (in integer format)

Description:

PI controller with output limitation:

$$G(s) = K_p + K_i/s$$

Each fixed point implementation uses the next higher integer data type for the integral value storage variable.

A rising flank at the *Enable* inport will preload the integral part with the value present on the *Init* inport.

Transfer function (zero-order hold discretization method):

$$G(z) = K_p + K_i T_s \frac{1}{z - 1}$$

Developer note: The fixed point implementation source code of this block is used for block [Block: PI](#).

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8
Init	int8
max	int8
min	int8
Enable	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
max	int16
min	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
max	int32
min	int32
Enable	bool

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
max	float32
min	float32
Enable	bool

Outports Data Type	
Out	float32

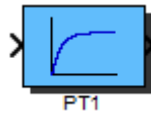
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
max	float64
min	float64
Enable	bool

Outports Data Type	
Out	float64

Block: PT1



Inports	
In	Input In(k)

Outputs	
Out	Output Out(k)

Mask Parameters		
Name	ID	Description
V	1	Gain
fc	2	Cut off frequency of low pass filter
ts_fact	3	Multiplication factor of base sampling time (in integer format)
method	4	Discretization method

Description:

First order low pass:

$$G(s) = V/(s/w + 1)$$

Due to limited value range in the 8 bit fixed point implementation rather high deviations from expected output values may occur.

Developer note: The source code of block *TF1* is used.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outputs Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outputs Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outputs Data Type	
Out	float32

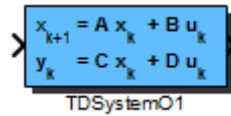
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: TDSysTemO1



Inports	
In	Input #1

Outports	
Out	Output #1

Mask Parameters		
Name	ID	Description
A	1	State matrix A
B	2	Input matrix B
C	3	Output matrix C
D	4	Feedthrough matrix D

Description:

1st order time discrete system with one input and one output.

Calculation:

$$\begin{aligned}x_{1,k+1} &= a_{1,1}x_{1,k} + b_{1,1}u_{1,k} \\ y_{1,k} &= c_{1,1}x_{1,k} + d_{1,1}u_{1,k}\end{aligned}$$

or short

$$\begin{aligned}\mathbf{x}_{k+1} &= \mathbf{A}\mathbf{x}_k + \mathbf{B}u_k \\ \mathbf{y}_k &= \mathbf{C}\mathbf{x}_k + \mathbf{D}u_k\end{aligned}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

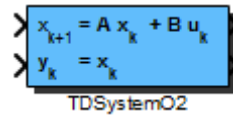
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: TDSysTemO2



Inports	
In1	Input #1
In2	Input #2

Outputs	
Out1	Output #1
Out2	Output #2

Mask Parameters		
Name	ID	Description
A	1	State matrix A
B	2	Input matrix B

Description:

2nd order time discrete system with two inputs and two outputs.

Calculation:

$$\begin{bmatrix} x_{1,k+1} \\ x_{2,k+1} \end{bmatrix} = \begin{bmatrix} a_{1,1} & a_{1,2} \\ a_{2,1} & a_{2,2} \end{bmatrix} \begin{bmatrix} x_{1,k} \\ x_{2,k} \end{bmatrix} + \begin{bmatrix} b_{1,1} & b_{1,2} \\ b_{2,1} & b_{2,2} \end{bmatrix} \begin{bmatrix} u_{1,k} \\ u_{2,k} \end{bmatrix}$$

$$\begin{bmatrix} y_{1,k} \\ y_{2,k} \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \begin{bmatrix} x_{1,k} \\ x_{2,k} \end{bmatrix} + \begin{bmatrix} 0 & 0 \\ 0 & 0 \end{bmatrix} \begin{bmatrix} u_{1,k} \\ u_{2,k} \end{bmatrix}$$

or short

$$\mathbf{x}_{k+1} = \mathbf{A}\mathbf{x}_k + \mathbf{B}\mathbf{u}_k$$

$$\mathbf{y}_k = \mathbf{x}_k$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In1	int8
In2	int8

Outports Data Type	
Out1	int8
Out2	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
In2	int16

Outports Data Type	
Out1	int16
Out2	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
In2	int32

Outports Data Type	
Out1	int32
Out2	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
In2	float32

Outports Data Type	
Out1	float32
Out2	float32

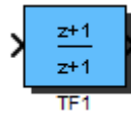
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
In2	float64

Outports Data Type	
Out1	float64
Out2	float64

Block: TF1



Inports	
In	Input In(k)

Outputs	
Out	Output Out(k)

Mask Parameters		
Name	ID	Description
b1	1	b1
b0	2	b0
a0	3	a0
ts_fact	4	Multiplication factor of base sampling time (in integer format)

Description:

First order transfer function:

$$G(z) = (b1.z + b0) / (z + a0)$$

Due to limited value range in the 8 bit fixed point implementation rather high deviations from expected output values may occur.

Developer note: The source code of this block is used for blocks *DT1* and *PT1*.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outputs Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outputs Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outputs Data Type	
Out	float32

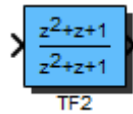
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: TF2



Inports	
In	Input In(k)

Outports	
Out	Output Out(k)

Mask Parameters		
Name	ID	Description
b2	1	b2
b1	2	b1
b0	3	b0
a1	4	a1
a0	5	a0
ts_fact	6	Multiplication factor of base sampling time (in integer format)

Description:

Second order transfer function:

$$G(z) = (b2.z^2 + b1.z + b0) / (z^2 + a1.z + a0)$$

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP8	8 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outputs Data Type	
Out	int16

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outputs Data Type	
Out	int8

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outputs Data Type	
Out	float32

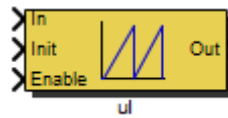
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: ul



Inports	
In	Control error input
Init	Value which is loaded at initialization function call
Enable	Enable == 0: Deactivation of block; Out is set to 0. Enable 0->1: Preload of integral part. Enable == 1: Activation of block

Outputs	
Out	Integrator output

Mask Parameters		
Name	ID	Description
Ki	1	Integral Factor
ts_fact	2	Multiplication factor of base sampling time (in integer format)

Description:

Integrator for angle signals:

$$G(s) = K_i/s = 1/(T_i \cdot s)$$

Each fixed point implementation uses the next higher integer datatype for the integrational value storage variable.

A rising flank at the *Enable* input will preload the integrational part with the value present on the *Init* input.

Transfer function (zero-order hold discretization method):

$$G(z) = K_i T_s \frac{1}{z - 1}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8
Init	int8
Enable	bool

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
Enable	bool

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
Enable	bool

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
Enable	bool

Outports Data Type	
Out	float64

24 General

Block: And



Inports	
In1	
In2	

Outports	
Out	

Description:

Logical AND block.

Implementations:

Bool Boolean Implementation

Implementation: Bool

Boolean Implementation

Inports Data Type	
In1	bool
In2	bool

Outports Data Type	
Out	bool

Block: AutoSwitch



Inports	
In1	Input #1
Switch	Input #2: Threshold signal
In3	Input #3

Outputs	
Out	Either value of input #1 or input #3 dependent on value of input #2

Mask Parameters		
Name	ID	Description
Thresh_up	1	Threshold level for rising switch signal
Thresh_down	2	Threshold level for falling switch signal

Description:

Switch between In1 and In3 dependent on Switch signal:
Switch signal rising: Switch \geq Threshold up \rightarrow Out = In1
Switch signal falling: Switch $<$ Threshold down \rightarrow Out = In3

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
Switch	int16
In3	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
Switch	int32
In3	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
Switch	float32
In3	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
Switch	float64
In3	float64

Outports Data Type	
Out	float64

Block: Constant



Outputs	
Out	Constant output

Mask Parameters		
Name	ID	Description
Value	1	Constant factor

Description:

Constant value.

Implementations:

Bool	Boolean Implementation
Int8	8 Bit Integer Implementation
Int16	16 Bit Integer Implementation
Int32	32 Bit Integer Implementation
FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: Bool

Boolean Implementation

Outputs Data Type	
Out	bool

Implementation: Int8

8 Bit Integer Implementation

Outputs Data Type	
Out	int8

Implementation: Int16

16 Bit Integer Implementation

Outports Data Type	
Out	int16

Implementation: Int32

32 Bit Integer Implementation

Outports Data Type	
Out	int32

Implementation: FiP8

8 Bit Fixed Point Implementation

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Outports Data Type	
Out	float64

Block: Gain



Inports	
In	Input

Outputs	
Out	Amplified input

Mask Parameters		
Name	ID	Description
Gain	1	Gain factor in floating point format

Description:

Amplification of input by gain factor.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: Inport



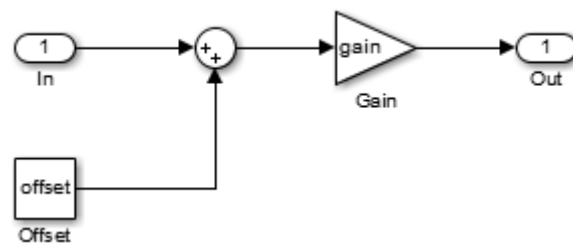
Inports	
IN	Signal from frame program

Mask Parameters	
ts_fact	Multiplication factor of base sampling time (in integer format)
Gain	Gain value used in simulation
Offset	Offset value used in simulation

Description:

Serves as interface to the frame program. The input of this block is intended for simulation purposes and can be left unconnected if not used. Also the parameters *Gain* and *Offset* are only used during simulation. The schematic for simulation can be seen in the figure below.

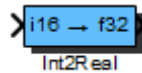
Note: Currently, *Gain* and *Offset* parameters are only available in Matlab/Simulink.



Data Types:

int8	8 Bit Fixed Point
int16	16 Bit Fixed Point
int32	32 Bit Fixed Point
float32	32 Bit Floating Point
float64	64 Bit Floating Point

Block: Int2Real



Inports	
In	Integer input

Outputs	
Out	Real output

Mask Parameters		
Name	ID	Description
Scale	1	Scaling factor from integer to real

Description:

Conversion block from integer (fixed point) datatypes to real (floating point) datatypes.
 $\text{Out} = \text{In} * \text{Scale}$

Implementations:

FiP8_Float32	8 Bit Fixed Point to 32 Bit Floating Point Implementation
FiP16_Float32	16 Bit Fixed Point to 32 Bit Floating Point Implementation
FiP32_Float32	32 Bit Fixed Point to 32 Bit Floating Point Implementation
FiP8_Float64	8 Bit Fixed Point to 64 Bit Floating Point Implementation
FiP16_Float64	16 Bit Fixed Point to 64 Bit Floating Point Implementation
FiP32_Float64	32 Bit Fixed Point to 64 Bit Floating Point Implementation
Bool_Float32	Boolean to 32 Bit Floating Point Implementation
Bool_Float64	Boolean to 64 Bit Floating Point Implementation

Implementation: FiP8_Float32

8 Bit Fixed Point to 32 Bit Floating Point Implementation

Inports Data Type	
In	int8

Outputs Data Type	
Out	float32

Implementation: FiP16_Float32

16 Bit Fixed Point to 32 Bit Floating Point Implementation

Inports Data Type	
In	int16
Outports Data Type	
Out	float32

Implementation: FiP32_Float32

32 Bit Fixed Point to 32 Bit Floating Point Implementation

Inports Data Type	
In	int32
Outports Data Type	
Out	float32

Implementation: FiP8_Float64

8 Bit Fixed Point to 64 Bit Floating Point Implementation

Inports Data Type	
In	int8
Outports Data Type	
Out	float64

Implementation: FiP16_Float64

16 Bit Fixed Point to 64 Bit Floating Point Implementation

Inports Data Type	
In	int16
Outports Data Type	
Out	float64

Implementation: FiP32_Float64

32 Bit Fixed Point to 64 Bit Floating Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	float64

Implementation: Bool_Float32

Boolean to 32 Bit Floating Point Implementation

Inports Data Type	
In	bool

Outports Data Type	
Out	float32

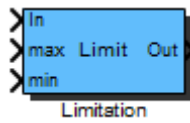
Implementation: Bool_Float64

Boolean to 64 Bit Floating Point Implementation

Inports Data Type	
In	bool

Outports Data Type	
Out	float64

Block: Limitation



Inports	
In	Input signal
max	Upper limit
min	Lower limit

Outports	
Out	Limited input signal

Description:

Limits the input signal to min and max_sci.

Caution: For correct computation the upper limit max has to be greater than the lower limit min!

Calculation:

$$\text{Out} = \begin{cases} \text{max} & \text{In} > \text{max} \\ \text{In} & \\ \text{min} & \text{In} < \text{min} \end{cases}$$

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
max	int16
min	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
max	int32
min	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
max	float32
min	float32

Outports Data Type	
Out	float32

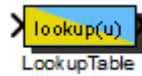
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
max	float64
min	float64

Outports Data Type	
Out	float64

Block: LookupTable



Inports	
In	Table index

Outports	
Out	Table output

Mask Parameters		
Name	ID	Description
Lookup	1	Look-up Table

Description:

Look-up Table with 256+1 values.

Note: 257th value is used for preventing index overflow during interpolation.

-> for periodic signals the 257th value should be set equal to 1st value

-> for non-periodic signals the 257th value should be set equal to 256th value

Implementations:

FiP8 8 Bit Fixed Point Implementation

FiP16 16 Bit Fixed Point Implementation

FiP32 32 Bit Fixed Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Block: LookupTable1D



Inports	
x	Table index in x direction

Outputs	
Out	Table output

Mask Parameters		
Name	ID	Description
TableData	1	Look-up table data
DimX	2	Number of data points in x-direction

Description:

One dimensional look-up table with selectable number of data points.

Table data must be an array of size DimX.

FiP: Input range is from -1 to 1

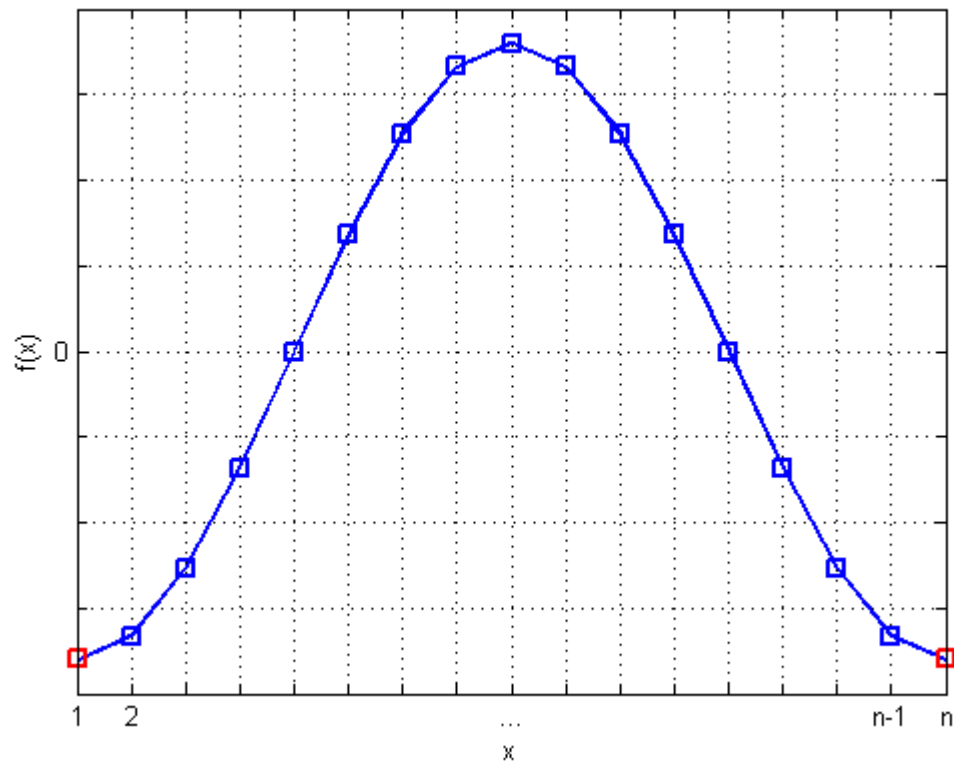
Float: Input range is from 0 to DimX-1. If input is out of range, output will be cut off (no extrapolation).

The table of the LookupTable1D block must contain DimX data points and they have to be arranged as

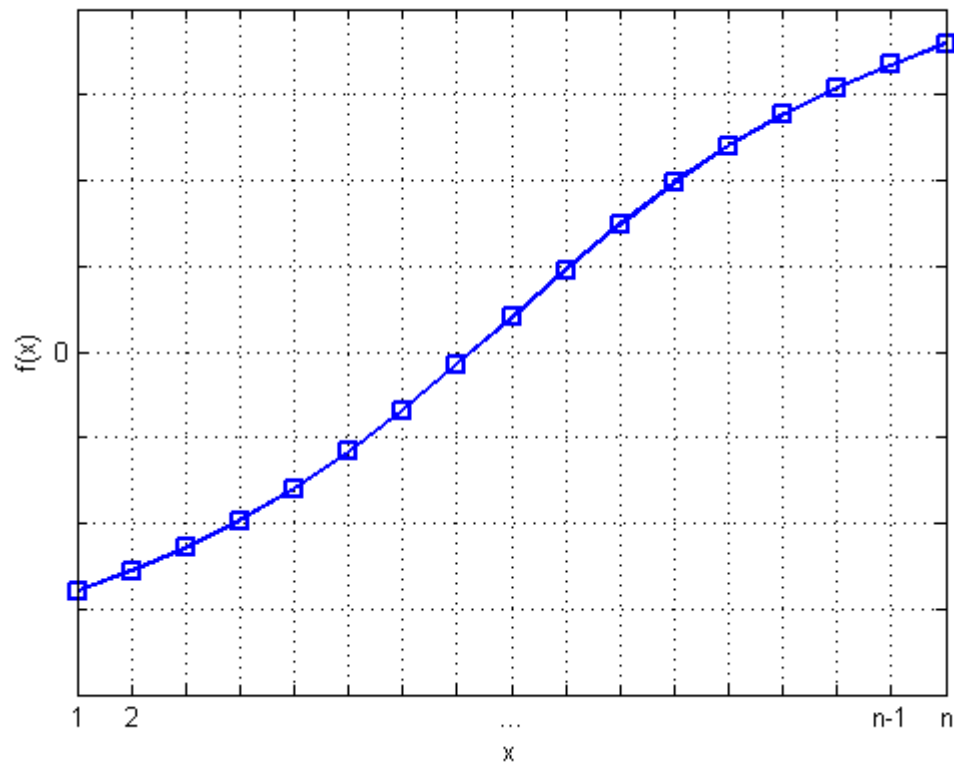
$$\text{TableData} = [f(x_1), f(x_2), \dots, f(x_{n-1}), f(x_n)]$$

with n as the selected DimX value.

For periodic signals, the last entry must be identical to the first entry, see the example in the following figure.



For non-periodic signals there is no restriction regarding the last data point, see the example in the figure below.



Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
x	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
x	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
x	float32

Outports Data Type	
Out	float32

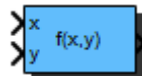
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
x	float64

Outports Data Type	
Out	float64

Block: LookupTable2D



Inports	
x	Table index in x direction
y	Table index in y direction

Outputs	
Out	Table output

Mask Parameters		
Name	ID	Description
TableData	1	Look-up table data
DimX	2	Number of data points in x-direction
DimY	3	Number of data points in y-direction

Description:

Two dimensional look-up table with selectable number of data points.

Table data must be an array of size DimX*DimY.

FiP: Input range is from -1 to 1

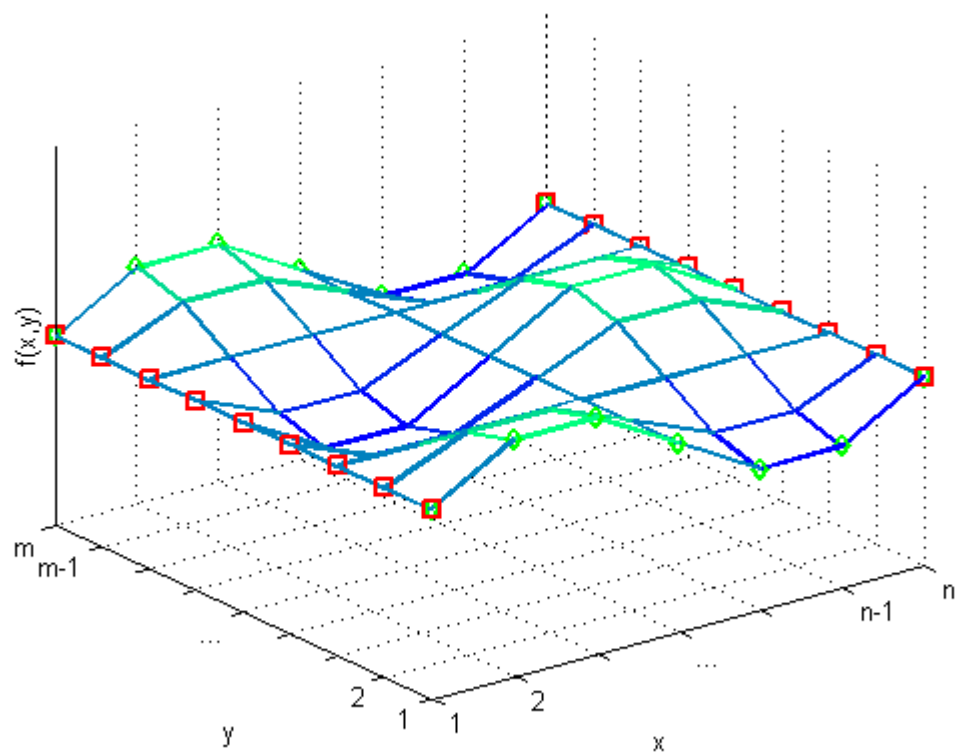
Float: Input range is from 0 to dimension-1. If input is out of range, output will be cut off (no extrapolation).

The table of the LookupTable2D block must contain DimX times DimY data points and they have to be arranged as

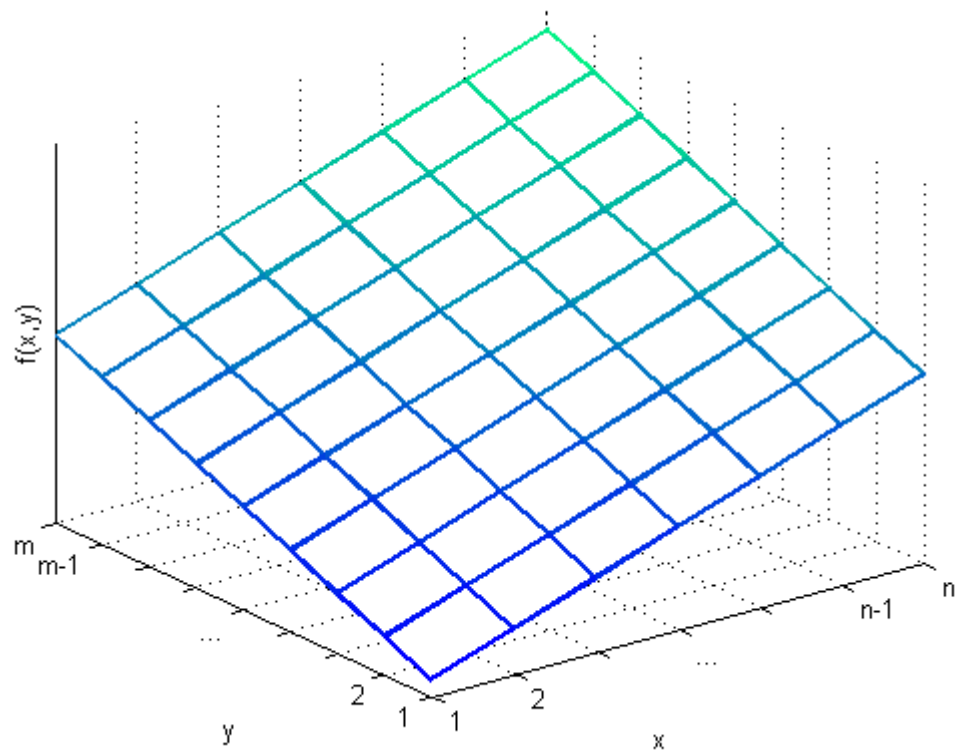
$$\begin{aligned}
 \text{TableData} = & [f(x_1, y_1), f(x_2, y_1), \dots, f(x_{n-1}, y_1), f(x_n, y_1), \\
 & f(x_1, y_2), f(x_2, y_2), \dots, f(x_{n-1}, y_2), f(x_n, y_2), \\
 & \dots \\
 & f(x_1, y_{m-1}), f(x_2, y_{m-1}), \dots, f(x_{n-1}, y_{m-1}), f(x_n, y_{m-1}), \\
 & f(x_1, y_m), f(x_2, y_m), \dots, f(x_{n-1}, y_m), f(x_n, y_m)]
 \end{aligned}$$

with n as selected DimX and m as selected DimY values.

For periodic signals, the last entries per dimension must be identical to the first entries in this dimension, see the example in the following figure.



For non-periodic signals there is no restriction regarding the last data points, see the example in the figure below.



Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
x	int16
y	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
x	int32
y	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
x	float32
y	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
x	float64
y	float64

Outports Data Type	
Out	float64

Block: LoopBreaker



Inports	
In	Input In(k)

Outports	
Out	Output Out(k)=In(k-1)

Description:

Block to break algebraic loops.

Implementations:

Bool	Boolean Integration
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: Bool

Boolean Integration

Inports Data Type	
In	bool

Outports Data Type	
Out	bool

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: ManualSwitch



Inports	
In1	Input #1
In2	Input #2

Outputs	
Out	

Mask Parameters		
Name	ID	Description
Toggle	1	Toggle

Description:

Toggling between inputs by double-clicking on block.

Doubleclicking of the *ManualSwitch* block changes the routing of the input signals and doesn't open the *Function Block Parameters* dialog. So if changing the implementation is required, one has to open the dialog via *Mask Parameters* command of the context menu.

Developer note: To get the double-click feature the callback function of *OpenFnc* in *Block Properties* is manually altered to

```
1 if get_param(gcb,'Toggle') == '0'
2     set_param(gcb,'Toggle','1');
3 else
4     set_param(gcb,'Toggle','0');
5 end
6 setBlockData(gcs,gcb);
7 initSFunction(gcb);
```

Implementations:

Bool	Boolean Implementation
FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: Bool

Boolean Implementation

Inports Data Type	
In1	bool
In2	bool

Outports Data Type	
Out	bool

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In1	int8
In2	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
In2	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
In2	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
In2	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
In2	float64

Outports Data Type	
Out	float64

Block: Maximum



Inports	
In1	Input #1
In2	Input #2

Outports	
Out	Maximum of Input #1 and Input #2

Description:

Outputs the greater value of the two input signals.

Calculation:

$$\text{Out} = \max(\text{In}_1, \text{In}_2)$$

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
In2	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
In2	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
In2	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
In2	float64

Outports Data Type	
Out	float64

Block: Minimum



Inports	
In1	Input #1
In2	Input #2

Outports	
Out	Minimum of Input #1 and Input #2

Description:

Outputs the lesser value of the two input signals.

Calculation:

$$\text{Out} = \min(\text{In}_1, \text{In}_2)$$

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
In2	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
In2	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
In2	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
In2	float64

Outports Data Type	
Out	float64

Block: Not



Inports	
In	

Outports	
Out	

Description:

Logical inverter block.

Implementations:

Bool Boolean Implementation

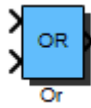
Implementation: Bool

Boolean Implementation

Inports Data Type	
In	bool

Outports Data Type	
Out	bool

Block: Or



Inports	
In1	
In2	

Outports	
Out	

Description:

Logical OR block.

Implementations:

Bool Boolean Implementation

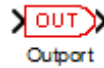
Implementation: Bool

Boolean Implementation

Inports Data Type	
In1	bool
In2	bool

Outports Data Type	
Out	bool

Block: Output



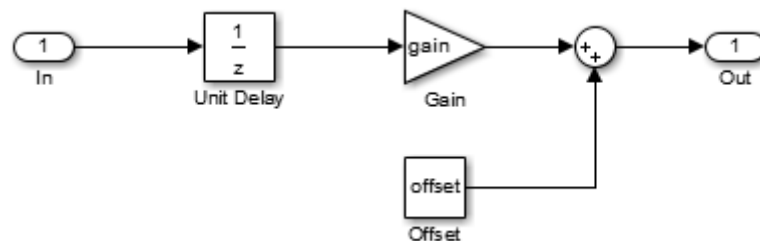
Outputs	
OUT	Signal to frame program

Mask Parameters	
ts_fact	Multiplication factor of base sampling time (in integer format)
Gain	Gain value used in simulation
Offset	Offset value used in simulation

Description:

Serves as interface to the frame program. The output of this block is intended for simulation purposes and can be left unconnected if not used. Also the parameters *Gain*, and *Offset* are only used during simulation. The schematic for simulation can be seen in the figure below. The Unit Delay block is only used during simulation and should reflect the time delay caused by a discrete controller.

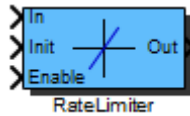
Note: Currently, *Gain* and *Offset* parameters are only available in Matlab/Simulink.



Data Types:

int8	8 Bit Fixed Point
int16	16 Bit Fixed Point
int32	32 Bit Fixed Point
float32	32 Bit Floating Point
float64	64 Bit Floating Point

Block: RateLimiter



Inports	
In	
Init	Value which is loaded at rising flanke of enable signal
Enable	Enable == 0: Deactivation of block; Out is set to In. Enable != 0: Activation of block; Out is rate limited. Enable 0->1: Preloading of output; Out is set to value of Init input

Outputs	
Out	

Mask Parameters		
Name	ID	Description
Tr	1	Rising time in seconds. Slew rate will be $1/Tr$
Tf	2	Falling time in seconds. Slew rate will be $1/Tf$
ts_fact	3	Multiplication factor of base sampling time (in integer format)

Description:

Limitation of rising and falling rate.

Function of Enable:

0: rate limiting disabled, signal is passed through

1: rate limiting enabled, signal is rate limited

0->1: preload of output with value from init input

Rising and falling time refer to a step from 0 to 1. Entries for *Tr*: *Rising time* and *Tf*: *Falling time* smaller than the actual sample time will be limited to the sample time internally.

The 16- and 32-Bit fixed point implementations are based on an internal 32-Bit wide slew-rate variable while the 8-Bit fixed point implementation uses a 16-Bit wide slew-rate variable.

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
Enable	bool

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
Enable	bool

Outports Data Type	
Out	float32

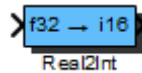
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
Enable	bool

Outports Data Type	
Out	float64

Block: Real2Int



Inports	
In	Real input

Outputs	
Out	Integer output

Mask Parameters		
Name	ID	Description
Scale	1	Scaling factor from real to integer

Description:

Conversion block from real (floating point) datatypes to integer (fixed point) datatypes.
 $\text{Out} = \text{In} / \text{Scale}$

Implementations:

Float32_FiP8	32 Floating Point to 8 Bit Fixed Point Implementation
Float32_FiP16	32 Floating Point to 16 Bit Fixed Point Implementation
Float32_FiP32	32 Floating Point to 32 Bit Fixed Point Implementation
Float64_FiP8	64 Floating Point to 8 Bit Fixed Point Implementation
Float64_FiP16	64 Floating Point to 16 Bit Fixed Point Implementation
Float64_FiP32	64 Floating Point to 32 Bit Fixed Point Implementation
Float32_Bool	32 Floating Point to Boolean Implementation
Float64_Bool	64 Floating Point to Boolean Implementation

Implementation: Float32_FiP8

32 Floating Point to 8 Bit Fixed Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	int8

Implementation: Float32_FiP16

32 Floating Point to 16 Bit Fixed Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	int16

Implementation: Float32_FiP32

32 Floating Point to 32 Bit Fixed Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	int32

Implementation: Float64_FiP8

64 Floating Point to 8 Bit Fixed Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	int8

Implementation: Float64_FiP16

64 Floating Point to 16 Bit Fixed Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	int16

Implementation: Float64_FiP32

64 Floating Point to 32 Bit Fixed Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	int32

Implementation: Float32_Bool

32 Floating Point to Boolean Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	bool

Implementation: Float64_Bool

64 Floating Point to Boolean Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	bool

Block: Saturation



Inports	
In	Input

Outputs	
Out	Limited output

Mask Parameters		
Name	ID	Description
max	1	Upper Limit
min	2	Lower Limit

Description:

Saturation of output to adjustable upper and lower limit.

If the entry for *Upper Limit* is lower than the entry for *Lower Limit* then the limits will be swapped internally.

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: SaveSignal



Inports	
In	Input signal to be saved

Description:

Makes the incoming signal accessible for reading with parameter numbers.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Implementation: Float32

32 Bit Floating Point Implementation

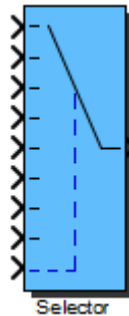
Inports Data Type	
In	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Block: Selector



Inports	
In0	Input #0
In1	Input #1
In2	Input #2
In3	Input #3
In4	Input #4
In5	Input #5
In6	Input #6
In7	Input #7
Select	Input select

Outputs	
Out	Selected input signal

Description:

Passing through of input signal selected by the select inport:

Select = 0 (DSP): Out = In0

Select = 1 (DSP): Out = In1

...

Select = 7 (DSP): Out = In7

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In0	int8
In1	int8
In2	int8
In3	int8
In4	int8
In5	int8
In6	int8
In7	int8
Select	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In0	int16
In1	int16
In2	int16
In3	int16
In4	int16
In5	int16
In6	int16
In7	int16
Select	int8

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In0	int32
In1	int32
In2	int32
In3	int32
In4	int32
In5	int32
In6	int32
In7	int32
Select	int8

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In0	float32
In1	float32
In2	float32
In3	float32
In4	float32
In5	float32
In6	float32
In7	float32
Select	int8

Outports Data Type	
Out	float32

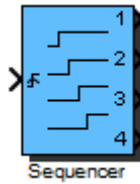
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In0	float64
In1	float64
In2	float64
In3	float64
In4	float64
In5	float64
In6	float64
In7	float64
Select	int8

Outports Data Type	
Out	float64

Block: Sequencer



Inports	
Start	Start signal. Rising flank triggers sequence

Outputs	
Out1	Output #1
Out2	Output #2
Out3	Output #3
Out4	Output #4

Mask Parameters		
Name	ID	Description
Delay1	1	Time delay for output 1
Delay2	2	Time delay for output 2
Delay3	3	Time delay for output 3
Delay4	4	Time delay for output 4
ts_fact	5	Multiplication factor of base sampling time (in integer format)

Description:

Generation of time delayed (enable) sequence.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
Start	int8

Outports Data Type	
Out1	int8
Out2	int8
Out3	int8
Out4	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
Start	int16

Outports Data Type	
Out1	int16
Out2	int16
Out3	int16
Out4	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
Start	int32

Outports Data Type	
Out1	int32
Out2	int32
Out3	int32
Out4	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
Start	float32

Outports Data Type	
Out1	float32
Out2	float32
Out3	float32
Out4	float32

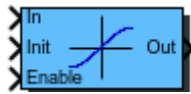
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
Start	float64

Outports Data Type	
Out1	float64
Out2	float64
Out3	float64
Out4	float64

Block: Sin2Limiter



Inports	
In	
Init	Value which is loaded at rising flanke of enable signal
Enable	Enable == 0: Deactivation of block; Out is set to zero. Enable != 0: Activation of block; Out is rate limited. Enable 0->1: Preloading of output; Out is set to value of Init input

Outports	
Out	

Mask Parameters		
Name	ID	Description
Tr	1	Rising time in seconds. Slew rate will be 1/Tr
Tf	2	Falling time in seconds. Slew rate will be 1/Tf
ts_fact	3	Multiplication factor of base sampling time (in integer format)

Description:

Limitation of rising and falling rate with \sin^2 characteristic.

Note: A running limitation process can not be interrupted!

Function of Enable:

0: rate limiting disabled, signal is set to zero

1: rate limiting enabled, signal is rate limited

0->1: preload of output with value from init input

Rising and falling time refer to a step from 0 to 1. Entries for *Tr*: Rising time and *Tf*: Falling time smaller than the actual sample time will be limited to the sample time internally.

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
Enable	bool

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
Enable	bool

Outports Data Type	
Out	float32

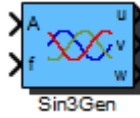
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
Enable	bool

Outports Data Type	
Out	float64

Block: Sin3Gen



Inports	
A	Amplitude
f	Frequency

Outputs	
u	Sine wave output phase u
v	Sine wave output phase v
w	Sine wave output phase w

Mask Parameters		
Name	ID	Description
fmax	1	Maximum Frequency in Hz
Offset	2	Offset
ts_fact	3	Multiplication factor of base sampling time (in integer format)

Description:

Generation of a 3 sine waves with amplitude (A) and frequency (f).

Calculation fixed point implementation:

$$\begin{aligned}
 u_k &= A_k \sin(2f_k f_{\max} k T_s) + A_{\text{offset}} \\
 v_k &= A_k \sin\left(2f_k f_{\max} k T_s - \frac{2\pi}{3}\right) + A_{\text{offset}} \\
 w_k &= A_k \sin\left(2f_k f_{\max} k T_s + \frac{2\pi}{3}\right) + A_{\text{offset}}
 \end{aligned}$$

For sine calculation a lookup table with 256 entries is used. This results in a short computation time but with the downside of reduced accuracy for the FiP32 implementation.

Calculation floating point implementation (parameter f_{\max} is ignored):

$$\begin{aligned}
 u_k &= A_k \sin(2\pi f_k k T_s) + A_{\text{offset}} \\
 v_k &= A_k \sin\left(2\pi f_k k T_s - \frac{2\pi}{3}\right) + A_{\text{offset}} \\
 w_k &= A_k \sin\left(2\pi f_k k T_s + \frac{2\pi}{3}\right) + A_{\text{offset}}
 \end{aligned}$$

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
A	int16
f	int16

Outports Data Type	
u	int16
v	int16
w	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
A	int32
f	int32

Outports Data Type	
u	int32
v	int32
w	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
A	float32
f	float32

Outports Data Type	
u	float32
v	float32
w	float32

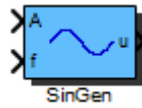
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
A	float64
f	float64

Outports Data Type	
u	float64
v	float64
w	float64

Block: SinGen



Inports	
A	Amplitude
f	Frequency

Outputs	
u	Sine wave output

Mask Parameters		
Name	ID	Description
fmax	1	Maximum Frequency in Hz
Offset	2	Offset
Phase	3	Phase [-Pi..Pi]
ts_fact	4	Multiplication factor of base sampling time (in integer format)

Description:

Generation of a sine wave with amplitude (A) and frequency (f).

Calculation fixed point implementation:

$$u_k = A_k \sin(2f_k f_{\max} k T_s + \phi_{\text{phase}}) + A_{\text{offset}}$$

For sine calculation a lookup table with 256 entries is used. This results in a short computation time but with the downside of reduced accuracy for the FiP32 implementation.

Calculation floating point implementation (parameter f_{\max} is ignored):

$$u_k = A_k \sin(2\pi f_k k T_s + \phi_{\text{phase}}) + A_{\text{offset}}$$

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
A	int16
f	int16

Outports Data Type	
u	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
A	int32
f	int32

Outports Data Type	
u	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
A	float32
f	float32

Outports Data Type	
u	float32

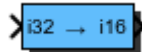
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
A	float64
f	float64

Outports Data Type	
u	float64

Block: TypeConv



Inports	
In	

Outports	
Out	

Description:

Data Type Conversion

Implementations:

FiP8_16	8 to 16 Bit Fixed Point Implementation
FiP8_32	8 to 32 Bit Fixed Point Implementation
FiP16_8	16 to 8 Bit Fixed Point Implementation
FiP16_32	16 to 32 Bit Fixed Point Implementation
FiP32_8	32 to 8 Bit Fixed Point Implementation
FiP32_16	32 to 16 Bit Fixed Point Implementation
Bool_FiP16	Boolean to 16 Bit Fixed Point Implementation
Bool_FiP32	Boolean to 32 Bit Fixed Point Implementation
FiP16_Bool	16 Bit Fixed Point to Boolean Implementation
FiP32_Bool	32 Bit Fixed Point to Boolean Implementation

Implementation: FiP8_16

8 to 16 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int16

Implementation: FiP8_32

8 to 32 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int32

Implementation: FiP16_8

16 to 8 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int8

Implementation: FiP16_32

16 to 32 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int32

Implementation: FiP32_8

32 to 8 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int8

Implementation: FiP32_16

32 to 16 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int16

Implementation: Bool_FiP16

Boolean to 16 Bit Fixed Point Implementation

Inports Data Type	
In	bool

Outports Data Type	
Out	int16

Implementation: Bool_FiP32

Boolean to 32 Bit Fixed Point Implementation

Inports Data Type	
In	bool

Outports Data Type	
Out	int32

Implementation: FiP16_Bool

16 Bit Fixed Point to Boolean Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	bool

Implementation: FiP32_Bool

32 Bit Fixed Point to Boolean Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	bool

Block: uConstant



Outputs	
Out	Constant output

Mask Parameters		
Name	ID	Description
Value	1	Constant factor

Description:

Constant value.

Implementations:

Bool	Boolean Integration
Int8	8 Bit Integer Implementation
Int16	16 Bit Integer Implementation
Int32	32 Bit Integer Implementation
FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: Bool

Boolean Integration

Outputs Data Type	
Out	bool

Implementation: Int8

8 Bit Integer Implementation

Outputs Data Type	
Out	int8

Implementation: Int16

16 Bit Integer Implementation

Outports Data Type	
Out	int16

Implementation: Int32

32 Bit Integer Implementation

Outports Data Type	
Out	int32

Implementation: FiP8

8 Bit Fixed Point Implementation

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Outports Data Type	
Out	float64

Block: uGain



Inports	
In	Input

Outputs	
Out	Amplified input

Mask Parameters		
Name	ID	Description
Gain	1	Gain factor in floating point format

Description:

Amplification of input by gain factor with output wrapping.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	32 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outputs Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

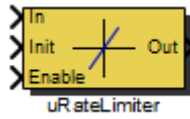
Implementation: Float64

32 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: uRateLimiter



Inputs	
In	
Init	Value which is loaded at rising flanke of enable signal
Enable	Enable == 0: Deactivation of block; Out is set to In. Enable != 0: Activation of block; Out is rate limited. Enable 0->1: Preloading of output; Out is set to value of Init input

Outputs	
Out	

Mask Parameters		
Name	ID	Description
Tr	1	Rising time in seconds. Slew rate will be 1/Tr
Tf	2	Falling time in seconds. Slew rate will be 1/Tf
ts_fact	3	Multiplication factor of base sampling time (in integer format)

Description:

Limitation of rising and falling rate.

Function of Enable:

0: rate limiting disabled, signal is passed through

1: rate limiting enabled, signal is rate limited

0->1: preload of output with value from init input

Rising and falling time refer to a step from 0 to 1. Entries for *Tr*: *Rising time* and *Tf*: *Falling time* smaller than the actual sample time will be limited to the sample time internally.

The 16- and 32-Bit fixed point implementations are based on an internal 32-Bit wide slew-rate variable while the 8-Bit fixed point implementation uses a 16-Bit wide slew-rate variable.

Implementations:

FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16
Init	int16
Enable	bool

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32
Init	int32
Enable	bool

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32
Init	float32
Enable	bool

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64
Init	float64
Enable	bool

Outports Data Type	
Out	float64

Block: uSaveSignal



Inports	
In	Input signal to be saved

Description:

Makes the incoming signal accessible for reading with parameter numbers.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Implementation: Float32

32 Bit Floating Point Implementation

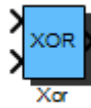
Inports Data Type	
In	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Block: Xor



Inports	
In1	
In2	

Outports	
Out	

Description:

Logical XOR block.

Implementations:

Bool Boolean Implementation

Implementation: Bool

Boolean Implementation

Inports Data Type	
In1	bool
In2	bool

Outports Data Type	
Out	bool

25 Math

Block: Abs



Inports	
In	Input u

Outputs	
Out	Absolute value of u

Description:

Calculation of absolute value of input.

Calculation:

$$\text{Out} = |\text{In}|$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

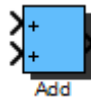
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: Add



Inports	
In1	Addend 1
In2	Addend 2

Outports	
Out	Sum

Description:

Addition of input 1 and input 2.

Calculation:

$$\text{Out} = \text{In}_1 + \text{In}_2$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In1	int8
In2	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
In2	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
In2	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
In2	float32

Outports Data Type	
Out	float32

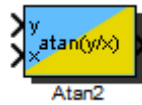
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
In2	float64

Outports Data Type	
Out	float64

Block: Atan2



Inports	
y	
x	

Outputs	
Out	Result of atan2(y/x)

Description:

Computation of the angle between the inputs x and y.

Calculation:

$$\text{Out} = \begin{cases} \arctan\left(\frac{y}{x}\right) & x > 0 \\ \arctan\left(\frac{y}{x}\right) + \pi & x < 0, y \geq 0 \\ \arctan\left(\frac{y}{x}\right) - \pi & x < 0, y < 0 \\ +\frac{\pi}{2} & x = 0, y > 0 \\ -\frac{\pi}{2} & x = 0, y < 0 \\ 0 & x = 0, y = 0 \end{cases}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
y	int8
x	int8

Outputs Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
y	int16
x	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
y	int32
x	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
y	float32
x	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
y	float64
x	float64

Outports Data Type	
Out	float64

Block: Average



Inports	
In	Input value

Outputs	
Out	Averaged value

Mask Parameters		
Name	ID	Description
n	1	Number of points to be averaged over
ts_fact	2	Multiplication factor of base sampling time (in integer format)

Description:

Calculation of moving average value over n numbers.

Calculation:

$$\text{Out}_k = \frac{1}{n} \sum_{i=k-n}^k \text{In}_i$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outputs Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outputs Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outputs Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outputs Data Type	
Out	float64

Block: Cos



Inports	
In	Input u

Outputs	
Out	Result of cos(u)

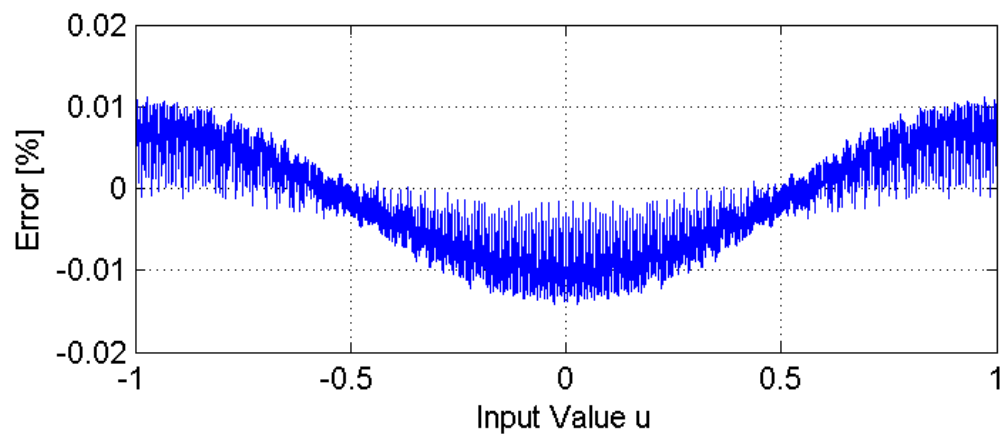
Description:

Cosine computation of input value.

Calculation:

$$\text{Out} = \cos(\text{In})$$

Error for 16 Bit Fixed Point Implementation:



Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: Div



Inports	
Num	Dividend (Numerator)
Den	Divisor (Denominator)

Outports	
Out	Quotient

Description:

Division of input Num by input Den.

Calculation:

$$\text{Out} = \begin{cases} 0 & \text{Num} = 0, \text{Den} = 0 \\ \max & \text{Num} > 0, \text{Den} = 0 \\ \min & \text{Num} < 0, \text{Den} = 0 \\ \frac{\text{Num}}{\text{Den}} & \text{otherwise} \end{cases}$$

Note: *maxVal* and *minVal* refer to the maximum/minimum representable value of the implementation.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
Num	int8
Den	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
Num	int16
Den	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
Num	int32
Den	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
Num	float32
Den	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
Num	float64
Den	float64

Outports Data Type	
Out	float64

Block: Exp



Inports	
In	Input u

Outputs	
Out	Result of exp(u)

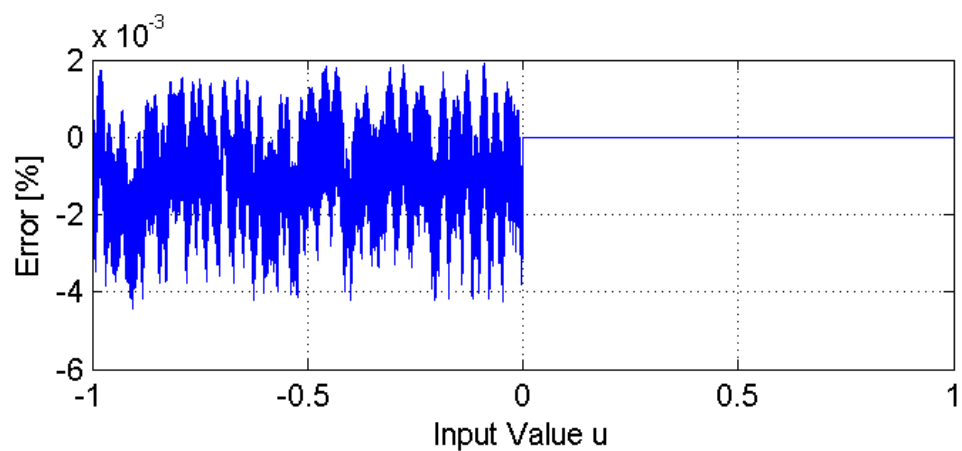
Description:

Computation of the exponential of the input.

Calculation:

$$\text{Out} = \begin{cases} e^{\text{In}} & \text{In} \leq 0 \\ 1 & \text{In} > 0 \end{cases}$$

Error for 16 Bit Fixed Point Implementation:



Implementations:

- FiP8** 8 Bit Fixed Point Implementation
- FiP16** 16 Bit Fixed Point Implementation
- FiP32** 32 Bit Fixed Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Block: L2Norm



Inports	
u1	Input u1
u2	Input u2

Outputs	
Out	Euclidean norm of u1 and u2

Description:

Calculation of L2-norm (euclidean norm).

Calculation:

$$\text{Out} = \|u\| = \sqrt{u_1^2 + u_2^2}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
u1	int8
u2	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
u1	int16
u2	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
u1	int32
u2	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
u1	float32
u2	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
u1	float64
u2	float32

Outports Data Type	
Out	float64

Block: Mult



Inports	
In1	Multiplicand 1
In2	Multiplicand 2

Outports	
Out	Product

Description:

Multiplication of input 1 with input 2.

Calculation:

$$\text{Out} = \text{In}_1 \cdot \text{In}_2$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In1	int8
In2	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
In2	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
In2	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
In2	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
In2	float64

Outports Data Type	
Out	float64

Block: Negation



Inports	
In	Input

Outputs	
Out	Negated input value

Description:

Negation of input signal.

Calculation:

$$\text{Out} = -\text{In}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outputs Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outputs Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outputs Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outputs Data Type	
Out	float64

Block: Sign



Inports	
In	Input u

Outports	
Out	Value corresponding to sign of u

Description:

Signum function.

Calculation:

$$\text{Out} = \text{sgn}(\text{In}) = \begin{cases} 1 & \text{In} \geq 0 \\ -1 & \text{In} < 0 \end{cases}$$

Implementations:

- FiP8** 8 Bit Fixed Point Implementation
- FiP16** 16 Bit Fixed Point Implementation
- FiP32** 32 Bit Fixed Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outputs Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outputs Data Type	
Out	int32

Block: Sin



Inports	
In	Input u

Outputs	
Out	Result of sin(u)

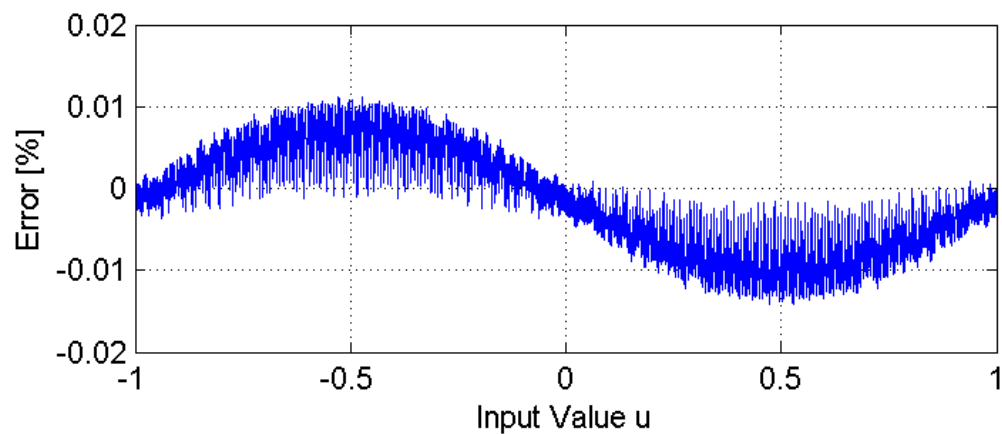
Description:

Sine computation of input value.

Calculation:

$$\text{Out} = \sin(\text{In})$$

Error for 16 Bit Fixed Point Implementation:



Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: Sqrt



Inports	
In	Input u

Outputs	
Out	Result of sqrt(u)

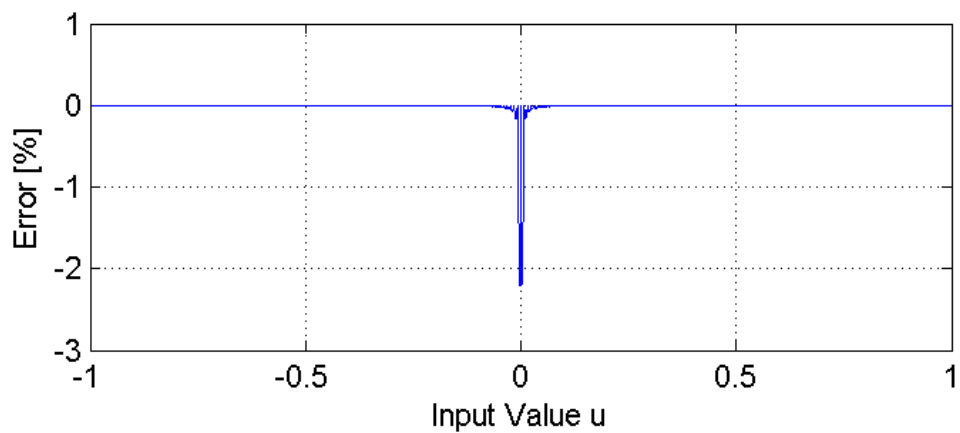
Description:

Square root computation of absolute input value.

Calculation:

$$\text{Out} = \sqrt{|\text{In}|}$$

Error for 16 Bit Fixed Point Implementation:



Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In	float64

Outports Data Type	
Out	float64

Block: Sub



Inports	
Plus	Minuend
Minus	Subtrahend

Outports	
Out	Difference

Description:

Subtraction of input Minus from input Plus.

Calculation:

$$\text{Out} = \text{Plus} - \text{Minus}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
Plus	int8
Minus	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
Plus	int16
Minus	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
Plus	int32
Minus	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
Plus	float32
Minus	float32

Outports Data Type	
Out	float32

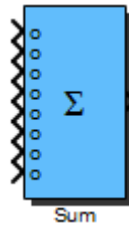
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
Plus	float64
Minus	float64

Outports Data Type	
Out	float64

Block: Sum



Inports	
In1	Input #1
In2	Input #2
In3	Input #3
In4	Input #4
In5	Input #5
In6	Input #6
In7	Input #7
In8	Input #8

Outputs	
Out	Result

Mask Parameters		
Name	ID	Description
In1	1	Input #1
In2	2	Input #2
In3	3	Input #3
In4	4	Input #4
In5	5	Input #5
In6	6	Input #6
In7	7	Input #7
In8	8	Input #8

Description:

Sum of inputs:

+ ... Input will be added to result.

- ... Input will be subtracted from result.

0 ... Input will be ignored.

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In1	int8
In2	int8
In3	int8
In4	int8
In5	int8
In6	int8
In7	int8
In8	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
In2	int16
In3	int16
In4	int16
In5	int16
In6	int16
In7	int16
In8	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
In2	int32
In3	int32
In4	int32
In5	int32
In6	int32
In7	int32
In8	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
In2	float32
In3	float32
In4	float32
In5	float32
In6	float32
In7	float32
In8	float32

Outports Data Type	
Out	float32

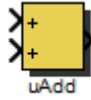
Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
In2	float64
In3	float64
In4	float64
In5	float64
In6	float64
In7	float64
In8	float64

Outports Data Type	
Out	float64

Block: uAdd



Inports	
In1	Addend 1
In2	Addend 2

Outports	
Out	Sum

Description:

Addition of input 1 and input 2 with output wrapping.

Calculation:

$$\text{Out} = \text{In}_1 + \text{In}_2$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
In1	int8
In2	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
In1	int16
In2	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
In1	int32
In2	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
In1	float32
In2	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
In1	float64
In2	float64

Outports Data Type	
Out	float64

Block: uSub



Inports	
Plus	Minuend
Minus	Subtrahend

Outports	
Out	Difference

Description:

Subtraction of input Minus from input Plus with output wrapping.

Calculation:

$$\text{Out} = \text{Plus} - \text{Minus}$$

Implementations:

FiP8	8 Bit Fixed Point Implementation
FiP16	16 Bit Fixed Point Implementation
FiP32	32 Bit Fixed Point Implementation
Float32	32 Bit Floating Point Implementation
Float64	64 Bit Floating Point Implementation

Implementation: FiP8

8 Bit Fixed Point Implementation

Inports Data Type	
Plus	int8
Minus	int8

Outports Data Type	
Out	int8

Implementation: FiP16

16 Bit Fixed Point Implementation

Inports Data Type	
Plus	int16
Minus	int16

Outports Data Type	
Out	int16

Implementation: FiP32

32 Bit Fixed Point Implementation

Inports Data Type	
Plus	int32
Minus	int32

Outports Data Type	
Out	int32

Implementation: Float32

32 Bit Floating Point Implementation

Inports Data Type	
Plus	float32
Minus	float32

Outports Data Type	
Out	float32

Implementation: Float64

64 Bit Floating Point Implementation

Inports Data Type	
Plus	float64
Minus	float64

Outports Data Type	
Out	float64