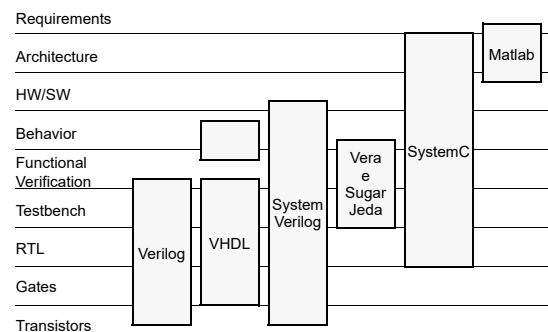




SystemC™

- **System-on-Chips (SoC) designs**
 - Multiple design domains: hardware, software, analog, ...
 - Multiple source components: DSPs, ASICs, IP-Cores, ...
 - Hard constraints: realtime, low power, ...
- **SystemC = C/C++ & HW-libraries**
- **C/C++ features**
 - **Classes & objects**
 - Encapsulation - data & behavior
 - Operator overloading - new types & behavior
 - Stronger typing - additional protection
 - Inheritance - declaration re-use
 - Templates - building patterns



Benefits of a C/C++ Based Design Flow

- **Productivity aspect**
 - Specification between architect and implementer is executable
 - High speed and high level simulation and prototyping
 - Refinement, no translation into hardware (no “semantic gap”)
- **System level aspect**
 - Tomorrow’s systems designers will be designing mostly software and less hardware !
 - Co-design, co-simulation, co-verification, co-debugging, ...
- **Re-use aspect**
 - Optimum re-use support by object-oriented techniques
 - Efficient testbench re-use
- **Especially C/C++ is widespread and commonly used !**



Drawbacks of a C/C++ Based Design Flow

- C/C++ was *not* created to design hardware !
- C/C++ does not support
 - Hardware style communication
 - Signals, protocols
 - Notion of time
 - Clocks, time sequenced operations
 - Concurrency
 - Hardware is inherently concurrent, operates in parallel
 - Reactivity
 - Hardware is inherently reactive, responds to stimuli, interacts with its environment (-> requires handling of exceptions)
 - Hardware data types
 - Bit type, bit-vector type, multi-valued logic types, signed and unsigned integer types, fixed-point types



μ C++

- μ C++ extends the C++ language in somewhat the same way that C++ extends the C programming language
 - light-weight concurrency on uniprocessor
 - parallel execution on multiprocessor computers
 - Peter A. Buhr, Richard A. Strooboscher, 1992
- Execution properties:
 - *thread* - execution of a code that occurs independently of and possible concurrently with other executions
 - *execution-state* - state information needed to permit independent executions
 - *mutual exclusion* - mechanism that permits an action to be performed on a resource without interruption by other actions on the resource

<http://plg.uwaterloo.ca/~usystem/uC++.html>



μC++ (example)

```
#include <uC++.h>
#include <uIOStream.h>

uMonitor ReaderWriter {
    // ...
public:
    ReaderWriter() { /*...*/ }
    //...
};

uTask Worker {
    ReaderWriter &rw;
    void main() {
        // ...
    }
public:
    Worker( ReaderWriter &rw ) :
        rw (rw) { }
};

void uMain::main() {
    ReaderWriter rw;
    Worker *workers;

    workers = new Worker[MaxTask] (rw);
    delete [] workers;

    uCout << uAcquire <<
        "successful completion" <<
        endl << uRelease;
}
```



Hardware in C/C++ – do it yourself...

```
#include <parallel.H>
class test_proc: public proc {
protected:
    int delay, icounter;
    sig counter;
public:
    test_proc(const char *nm, const int del): proc(nm)
    { delay=del; icounter=0; counter=0; }
    void body(void) {
        wait(delay);
        icounter++;
        counter=counter+1; counter.Update();
        fprintf(stdout, "***s*0** %d: %d: %d\n",
            name, now, icounter, (int) counter);
    }
};

int main(const int argc, const char ** argv)
{
    reset_prctbl();
    test_proc *prc1=cNew(test_proc, ("prc1", 20));
    test_proc *prc2=cNew(test_proc, ("prc2", 15));
    run(200);
    dDelete(prc1); dDelete(prc2);
    return 0;
}

**run** 200
**prc2*0** 15: 1: 1
**prc1*0** 20: 1: 1
**prc2*0** 30: 2: 2
**prc1*0** 40: 2: 2
**prc2*0** 45: 3: 3
**prc1*0** 60: 3: 3
**prc2*0** 60: 4: 4
**prc2*0** 75: 5: 5
**prc1*0** 80: 4: 4
**prc2*0** 90: 6: 6
**prc1*0** 100: 5: 5
**prc2*0** 105: 7: 7
**prc1*0** 120: 6: 6
**prc2*0** 120: 8: 8
**prc2*0** 135: 9: 9
**prc1*0** 140: 7: 7
**prc2*0** 150: 10: 10
**prc1*0** 160: 8: 8
**prc2*0** 165: 11: 11
**prc1*0** 180: 9: 9
**prc2*0** 180: 12: 12
**prc2*0** 195: 13: 13
**prc1*0** 200: 10: 10
```



... but is it worth of it?

```

// parallel.H
class sig {                                // signal
private:
    char const *name;
    int val, val_new;
public:
    sig(const char *nm=NULL);
    sig(const sig &s);
    int operator = (const sig &s);
    int operator = (const int v);
    operator int (void);
    void Update(void);                    // updating
};

class proc {                               // process
private:
    int prc;
protected:
    char *name;
public:
    proc(const char *nm);
    virtual ~proc();
    virtual void body(void) = 0;
    bool __wait__(const int del);
};

extern int now;
#define wait(D)    { if (__wait__(D)) return; }
extern void run(const int stop_simulation);
extern void reset_prc_tbl(void);

// "execution engine"
void run(const int stop_simulation)
{
    now=0;
    for (now=0;now<=stop_simulation;now++) {
        // Delta-delay cycle
        for ( ; ; ) {
            int prc;
            // All processes
            for (prc=0;prc<process_count;prc++) {
                if (prc_tbl[prc].ref!=NULL) {
                    prc_tbl[prc].skip=false;
                    prc_tbl[prc].ref->body();
                }
            }

            for (prc=0;prc<process_count;prc++)
                { if (!prc_tbl[prc].skip) break; }
            if (prc>=process_count) break;

            // Updating all signals
            // ...

            // Updating simulation time (i.e. now)
            // ...
        }
    }
}

```



Why SystemC for System Design ?

- **The Gap**
 - Tomorrow's systems designers will be designing mostly software and little hardware
 - A software language is not capable of describing concurrency, clocks, hardware data types, reactivity
- **Requirements**
 - Allow hardware/software co-design and co-verification
 - Fast simulation for validation and optimization
 - Smooth path to hardware and software
 - Support of design and architectural re-use
- <http://www.accellera.org/community/systemc>
- <http://www.doulos.com/knowhow/systemc/>



What is SystemC ?

- **A library of C++ classes**
 - Processes (for concurrency)
 - Clocks (for time)
 - Modules, ports, signals (for hierarchy)
 - Hardware data types
- **A modeling style**
 - ... for modeling systems consisting of multiple design domains, abstraction levels, architectural components, real-life constraints
- **A light-weight simulation kernel**
 - ... for high-speed cycle-accurate simulation
- <http://www.accellera.org/community/systemc> / IEEE Std. 1666-2011
- <http://www.doulos.com/knowhow/systemc/>



A brief history

- **Open SystemC Initiative (OSCI) – a language and modeling platform, based on C++**
- **September 1999 – SystemC 0.9 - first version, cycle based**
- **March 2000 – SystemC 1.0 - widely accessed major release**
 - a set of constructs for RTL and behavioral modeling
- **August 2002 – SystemC 2.0 - channels & events, cleaner syntax**
 - enabling system-level modeling for both software and hardware implementations
- **April 2005 – SystemC TLM 1.0 (Transaction Level Modeling)**
- **September 2005 – SystemC 2.1**
- **July 2006 – SystemC 2.2 (updated in March 2007)**
- **June 2008 – SystemC TLM 2.0.0 (library)**
- **July 2009 – SystemC TLM-2.0 LRM (TLM-2.0.1 library)**
- **March 2010 – SystemC AMS 1.0 LRM**
- **November 2011 – IEEE 1666–2011 standard**
- **July 2012 – SystemC 2.3 (TLM integrated)**
- **March 2013 – SystemC AMS 2.0 completed**
- **April 2014 – SystemC 2.3.1 (TLM integrated)**



Benefits of a SystemC-Based Design Flow

- **C/C++ based design methodology**
 - 1. conceptualize
 - 2. simulate in C/C++
 - 3. write specification document
 - 4. hand over
 - executable specification
 - testbenches
 - written specification
 - 5. understand specification
 - 6. refine in C/C++
 - 7. validate re-using testbenches
 - 8. synthesize from C/C++



SystemC Key Features

- **Concurrency – Sync. and async. processes**
- **Notion of time – Multiple clocks with arbitrary phase relation**
- **Data types – Bit vectors, arbitrary precision integers, ...**
 - v.1: arbitrary precision fixed point data types
- **Communication – Signals, channels**
 - v.2: advanced communication protocols
- **Reactivity – Watching for events**
- **Debug support – Waveform tracing**
- **Simulation support**
- **Support of multiple abstraction levels and iterative refinement**
- **Support of functional model creation**
-
 - v.3: RTOS modeling



Modules

- **Modules are basic building blocks of a SystemC design**
- **A module contains processes (-> functionality) and/or sub-modules (-> hierarchical structure)**

```
SC_MODULE( module_name ) {
    // Declaration of module ports
    // Declaration of module signals
    // Declaration of processes
    // Declaration of sub-modules
    SC_CTOR( module_name ) { // Module constructor
        // Specification of process type and sensitivity
        // Sub-module instantiation and port mapping
    }
    // Initialization of module signals
};
```



Modules

- **A module correspond to a C++ class**
 - class data members <-> ports
 - class member functions <-> processes
 - class constructor <-> process generation

```
SC_MODULE ( module_name ) { ..... };
-----
struct module_name : ::sc_core::sc_module { ..... };

SC_CTOR ( module_name ) { ..... }
-----
typedef module_name SC_CURRENT_USER_MODULE;
module_name ( ::sc_core::sc_module_name ) { ..... }
```



Ports

- External interface of a module
- Passing data from and to processes / sub-modules
- Triggering of actions within the module
- A ports has a mode (direction) and a type
 - mode: in, out, inout;
 - type: C++ type, SystemC type, user-defined type


```
// input port declaration
sc_in< type > in_port_name;
// output port declaration
sc_out< type > out_port_name;
// bidirectional port declaration
sc_inout< type > inout_port_name;
```
- Vector port / port array:


```
sc_out< int > result [32];
```



Signals

- Connects a port of one module to the port of another module
- Local to a module
- Signal semantics is the same as VHDL and Verilog deferred assignment semantics
- A signal has a type
 - type: C++ type, SystemC type, user-defined type


```
// signal declaration
sc_signal< type > signal_name;
```
- Vector signal / signal array:


```
sc_signal< double > a[4];
```
- Internal data storage not by signals but by local variables
Local variable types: C++ types, SystemC types, user-defined types



Ports & Signals

- **Port and Signal Binding**
 - Ports and signals to be bound need to have the same type
 - A signal connects two ports
 - A port is bound to one signal (port-to-signal) or to one sub-module port (port-to-port)
- **Resolution**
 - SystemC supports resolved ports and signals
 - Resolved ports/signals have 4-valued logic type (0,1,Z,X)
 - Resolved ports/signals allow multiple drivers
 - Resolved vector ports/vector signals

```
sc_in_rv< n > x;      // n bits wide resolved input port
sc_signal_rv< n> y;   // n bits wide resolved signal
```

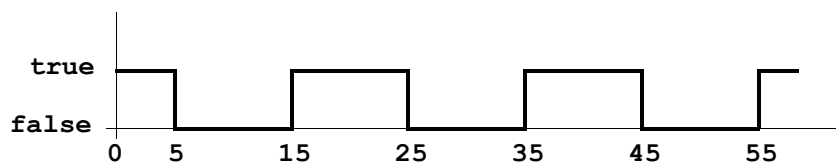


Clocks

- SystemC provides a special object *sc_clock*
 - Clocks generate timing signals to synchronize events
 - Multiple clocks with arbitrary phase relations are supported
 - Clock generation:

```
sc_clock clock_name("label", period, duty_ratio, offset, start_value);
sc_clock my_clk ("CLK", 20, SC_NS, 0.5, 5, SC_NS, true);
```

 - time units recommended for *period* & *offset*



- Clock binding:

```
my_module.clk( my_clk );
```



Data Types

- **Native C/C++ types**
 - integer types: char, unsigned char, short, unsigned short, int, unsigned int, long, unsigned long
 - floating point types: float, double, long double
- **SystemC types**
 - 2-value ('0', '1') logic / logic vector
 - 4-value ('0', '1', 'Z', 'X') logic / logic vector
 - Arbitrary sized integer (signed/unsigned)
 - Fixed point types (signed/unsigned, templated/untemplated)
- **User-defined types**



SystemC Data Types

Type	Description
sc_bit	2-value single bit use bool
sc_logic	4-value single bit
sc_int	1 to 64 bit signed integer
sc_uint	1 to 64 bit unsigned integer
sc_bigint	arbitrary sized signed integer
sc_biguint	arbitrary sized unsigned integer
sc_bv	arbitrary length 2-value vector
sc_lv	arbitrary length 4-value vector
sc_fixed	templated signed fixed point
sc_ufixed	templated unsigned fixed point
sc_fix	untemplated signed fixed point
sc_ufix	untemplated unsigned fixed point



sc_bit / sc_logic

- ~~2-value single bit type: sc_bit~~ use of type bool recommended
- '0'=false, '1'=true
- 4-value single bit type: *sc_logic*
 - '0'=false, '1'=true, 'X'=unknown/indeterminate value, 'Z'=high-impedance/floating value
- Features:
 - Mixed use of operand types *sc_bit* and *sc_logic*
 - Use of character literals for constant assignments
- ~~sc_bit~~ / *sc_logic* operators

bitwise	& (and)	(or)	^ (xor)	~ (not)
assignment	=	&=	=	^=
equality	==	!=		



sc_int / sc_uint / sc_bigint / sc_biguint

- Fixed precision integer types
 - signed: *sc_int*<*n*> (*n*: word length, $1 \leq n \leq 64$)
 - unsigned: *sc_uint*<*n*> (*n*: word length, $1 \leq n \leq 64$)
- Arbitrary precision integer types
 - signed: *sc_bigint*<*n*> (*n*: word length, $n > 64$)
 - unsigned: *sc_biguint*<*n*> (*n*: word length, $n > 64$)
- Features:
 - Mixed use of operand types *sc_int*, *sc_uint*, *sc_bigint*, *sc_biguint* and C++ integer types
 - Truncation and/or sign extension if required
 - 2's complement representation



sc_int / sc_uint / sc_bigint / sc_biguint

- sc_int / sc_uint / sc_bigint / sc_biguint operators

bitwise	&		^	~	>>	<<			
arithmetic	+	-	*	/	%				
assignment	=	+=	-=	*=	/=	%=	&=	=	^=
equality	==	!=							
relational	<	<=	>	>=					
auto-inc/dec	++	--							
bit/part select	[]	range ()							
concatenation	(,)								



sc_bv / sc_lv

- Arbitrary length bit vector: `sc_bv<n>` (*n*: vector length)
- Arbitrary length logic vector: `sc_lv<n>` (*n*: vector length)
- Features:
 - Assignment between `sc_bv` and `sc_lv`
 - Use of string literals for vector constant assignments
 - Conversions between `sc_bv/sc_lv` and SystemC integer types
 - No arithmetic operation available





- sc_bv / sc_lv

bitwise	&		^	~	>>	<<
assignment	=	&=	=	^=		
equality	==	!=				
bit/part select	[]	range ()				
concatenation	(,)					
reduction	and_reduce ()	or_reduce ()	xor_reduce ()			
conversion	to_string ()					



sc_fixed / sc_ufixed / sc_fix / sc_ufix

- Fixed point types

- sc_fixed  templated
- sc_ufixed  signed
- sc_fix  unsigned
- sc_ufix  untemplated

- templated - static arguments (to be known at compile time)
- untemplated - nonstatic arguments (to be configured during runtime)
- signed - 2's complement representation
- unsigned

- Features:

- Operations performed using arbitrary precision
- Multiple quantization and overflow modes



sc_fixed / sc_ufixed / sc_fix / sc_ufix

- Templated signed fixed point type: `sc_fixed`

- `sc_fixed< wl, iwl, q_mode, o_mode, n_bits > var_name (init_val);`

- Arguments:

- wl - total number of bits
- iwl - number of integer bits
- q_mode - quantization mode (optional)
- o_mode - overflow mode (optional)
- n_bits - number of bits for overflow mode (optional)

- `sc_fixed_fast`, `sc_ufixed_fast`, `sc_fix_fast`, `sc_ufix_fast`

- precision limited to 53 bits (C++ type *double* is used)



sc_fixed / sc_ufixed / sc_fix / sc_ufix

- **Example**
 - `sc_fixed< 8, 4 > my_var (-1.75);`
 - $(1.75)_{10} = (0001.1100)_2$
 - 2's complement of $(0001.1100)_2 = (1110.0100)_2$
- **Quantization and overflow modes**

Quantization Mode	
SC_RND	Round
SC_RND_ZERO	Round towards zero
SC_RND_MIN_INF	Rounding towards minus infinity
SC_RND_INF	Rounding towards infinity
SC_RND_CONV	Convergent rounding
SC_TRN	Truncate
SC_TRN_ZERO	Truncate towards Zero

Overflow Mode	
SC_SAT	Saturate
SC_SAT_ZERO	Saturate to zero
SC_SAT_SYM	Saturate symmetrically
SC_WRAP	Wrap-around
SC_WRAP_SYM	Wrap-around symmetrically



Operators

- **Comparison:** `== != > >= < <=`
- **Arithmetic:** `++ -- * / % + -`
- **Bitwise:** `~ & | ^`
- **Assignment:** `= &= |= ^= *= /= += -= <<= >>=`
- **Bit selection:** `bit(idx) [idx]`
- **Range selection:** `range(high,low) (high,low)`
- **Conversion:** `to_double() to_int() to_int64() to_long()`
`to_uint() to_uint64() to_ulong() to_string()`
- **Testing:** `is_zero() is_neg() length()`
- **Bit reduction:** `and_reduce() nand_reduce() or_reduce() nor_reduce()`
`xor_reduce() xnor_reduce()`



User-Defined Data Types

- User-defined data types can be used for ports and signals

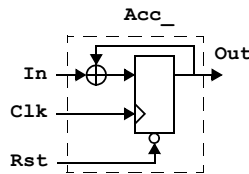
```
class complex {
private:
    double re, im;
public:
    complex () { re=0.0; im=0.0; }
    complex (double r, double i) { re=r; im=i; }
    void set(double r, double i) { re=r; im=i; }
    double get_re() { return re; }
    double get_im() { return im; }
    int operator == (const complex &c) const {
        if ( ( re == c.re ) && ( im == c.im() ) ) return 1;
        else return 0;
    }
    // ...
};

sc_signal< complex > c;
```



Modules

- Module is a structural entity
 - helps to split complex designs
- Module can contain
 - ports
 - processes
 - user defined C++ functions
 - internal member data
 - constructor
 - modules and signals
- Valid for Hardware, Firmware/Software & System



```
SC_MODULE(accumulator) {
    // ports (input)
    sc_in<int> In;
    sc_in<bool> Rst;
    sc_in<bool> Clk;
    // ports (output)
    sc_out<int> Out;
    // local member functions
    void accumulate();
    void display(ostream& = cout);
    // local member data
    int Acc_;
    // constructor
    SC_CTOR(accumulator) {
        SC_METHOD(accumulate);
        sensitive_pos << Clk;
        Acc_ = 0 ;
    }
};
```



Module Ports

- Pass data between module-boundary and internal module-processes
- Direction: *in* (read), *out* (write), and *inout* (read & write)
- Type: *<int>* , *<bool>* , etc.
- Special: *clock*

Module Member functions

- Processes
 - functions registered with the SystemC kernel
- User defined functions
 - can be called within processes



Modules & Hierarchy

- Modules may contain sub-modules (hierarchical structure)

- In `SC_MODULE`:

```
// sub-module declaration
module_type *my_module;
```

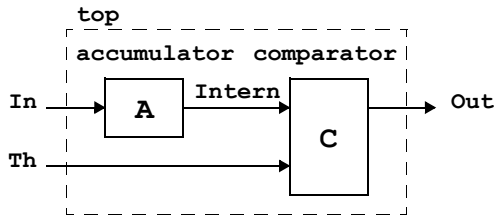
- In the module constructor of `SC_MODULE`:

```
// sub-module instantiation and port mapping
SC_CTOR( module_name ) {
    my_module = new module_type ("label");
    my_module -> in1 (sig1);
    my_module -> in2 (sig2);
    my_module -> out1 (sig3);
}
```




Modules & Hierarchy

- Module instances
- Signals



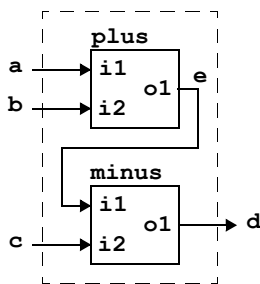
```

SC_MODULE(top) {
    // ports
    sc_in<int> In;
    ...
    // module instances
    accumulator A;
    comparator C;
    // signals
    sc_signal<int> Intern;
    // constructor
    SC_CTOR(top): A("A"), C("C") {
        A.In(In);
        A.Out(Intern);
        ...
    }
};

```



Modules & Hierarchy



$$d = (a + b) - c$$

```

SC_MODULE( plus ) {
    sc_in<int> i1;
    sc_in<int> i2;
    sc_out<int> o1;
    ...
};

```

```

SC_MODULE( minus ) {
    sc_in<int> i1;
    sc_in<int> i2;
    sc_out<int> o1;
    ...
};

```

```

SC_MODULE( alu ) {
    sc_in<int> a;
    sc_in<int> b;
    sc_in<int> c;
    sc_out<int> d;
    plus *p;
    minus *m;
    sc_signal<int> e;
    SC_CTOR( alu ) {
        p = new plus ( "PLUS" );
        p->i1 ( a );
        p->i2 ( b );
        p->o1 ( e );
        m = new minus ( "MINUS" );
        (*m) ( e, c, d );
    }
};

```



Processes

- **Basic unit of concurrent execution**
- **Not hierarchical**
- **Contained inside modules**
- **Communication done via signals, module ports**
- **Encapsulates functionality**

- **SystemC takes care of scheduling the concurrent processes**

- **SystemC = Language (C++ Library) + Scheduler**



Process Activation

- **Processes have sensitivity lists**
- **Processes are triggered by events on sensitive signals**

- **Process Types**
 - **Method (SC_METHOD)**
 - asynchronous block, like a combinational function
 - **Thread (SC_THREAD)**
 - asynchronous process
 - **Clocked Thread (SC_CTHREAD)**
 - synchronous process
 - limited suspend/resume control
 - **Remote Procedure Call (RPC)**



Process Declaration

- **Declaration of member function (in SC_MODULE)**

```
// process declaration
void my_process ();
```
- **Instantiation (in module constructor of SC_MODULE)**

```
// specification of process type and sensitivity
SC_CTOR( module_name ) {
    SC_METHOD( my_process );
    sensitive << sig1 << sig2;
}
```
- **Definition of member function (in SC_MODULE or somewhere else)**

```
// process specification
void module_name::my_process () {
    ...
}
```



Method – SC_METHOD

- **Entire process executed once when a signal in its sensitivity list changes**
 - static sensitivity – “sensitive << i1 << i2;”
 - dynamic sensitivity – “next_trigger(...);” overrides previous sensitivity list (timeout possible)
- **Can not be suspended**
- **Local variables loose their values between successive calls**
- **Most similar to a usual C++ function**
- **Fastest**

```

SC_MODULE( plus ) {
    sc_in<int> i1, i2;
    sc_out<int> o1;

    void do_plus();
    SC_CTOR( plus ) {
        SC_METHOD( do_plus );
        sensitive << i1 << i2;
    }
};

```

sensitivity list →

```

void plus::do_plus() {
    int arg1, arg2, sum;

    arg1 = i1.read();
    arg2 = i2.read();
    sum = arg1 + arg2;
    o1.write(sum);
}

```



Thread – SC_THREAD

- Infinite loop limited by event boundaries: execution suspended by “wait()” statement(s)
 - static sensitivity – “sensitive << i1 << i2;” and “wait();”
 - dynamic sensitivity – “wait(conditions);” “wait_until(delay_expr)” – (timeout possible)
 - subject for interpretations...
- Activated (re-activated) when any of the signals in the sensitivity list changes
- Local variables are saved (similar to static variables in C++ functions)
- Slower than method with module data members to store the ‘state’

```

SC_MODULE( plus ) {
    sc_in<int> i1, i2;
    sc_out<int> o1;

    void do_plus();
    SC_CTOR( plus ) {
        SC_THREAD( do_plus );
        sensitive << i1 << i2;
    }
};

void plus::do_plus() {
    int arg1, arg2;
    int sum;
    while ( true ) {
        arg1 = i1.read();
        arg2 = i2.read();
        sum = arg1 + arg2;
        o1.write(sum);
        wait();
    }
}
    
```

sensitivity list →



Thread – SC_THREAD

• Sensitivity

```

wait(time);
wait(event);
wait(event1 | event2 ...);           // any of these
wait(event1 & event2 ...);           // all of these
wait(timeout, event);                 // event with timeout
wait(timeout, event1|event2...);     // any event with timeout
wait(timeout, event1&event2...);     // all events with timeout
wait();                               // static sensitivity

// Example
sc_event ack_event, bus_error_event;
// ...
wait(t_MAX_DELAY, ack_event | bus_error_event);
if ( timed_out() ) break;           // deprecated
    
```



Clocked thread – SC_CTHREAD

- Particular thread: infinite loop, sensitive only to one edge of one clock
- Suspended by
 - “wait()” – waiting for the next clock edge
 - “wait(N)” – delay N clock cycles
- Only synchronous systems
- Slowest

```

SC_MODULE( plus ) {
    sc_in_clk clk;
    sc_in<int> i1, i2;
    sc_out<int> o1;

    void do_plus();
    SC_CTOR( plus ) {
        SC_CTHREAD (do_plus,clk.pos());
    }
};

void plus::do_plus() {
    int arg1, arg2;
    int sum;
    while ( true ) {
        arg1 = i1.read();
        arg2 = i2.read();
        sum = arg1 + arg2;
        o1.write(sum);
        wait();
    }
}
    
```



Processes

	SC_METHOD	SC_THREAD	SC_CTHREAD
triggered	by signal events	by signal events	by clock edge
infinite loop	no	yes	yes
execution suspended	no	yes	yes
suspend & resume	-	wait() wait_until()	wait()
construct & sensitize method	SC_METHOD(p); sensitive << s; sensitive << s.pos(); sensitive << s.neg();	SC_THREAD(p); sensitive << s; sensitive << s.pos(); sensitive << s.neg();	SC_CTHREAD (p,clk.pos()); SC_CTHREAD (p,clk.neg());
modelling example (hardware)	combinational logic	sequential logic at RT level (asynchronous reset, etc.)	sequential logic at higher design levels



Remote Procedure Call – RPC

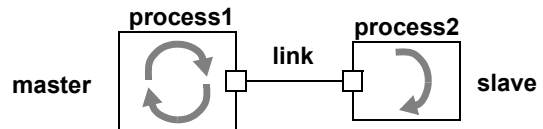
- Abstract communication and execution semantics for functional level
- Master/slave ports and processes
- Equivalent to function call but without function pointer
- Structure is key for re-use (split behavior of modules)
- RPC chain / concurrent RPC chains

```

SC_MODULE(M1) {
    sc_outmaster<int> Out;
    ...
    void process1();
    SC_CTOR(M1) {
        SC_METHOD(process1);
        sensitive << ...;
    }
};

SC_MODULE(M2) {
    sc_inslave<int> In;
    ...
    void process2();
    SC_CTOR(M2) {
        SC_SLAVE(process2, In);
    }
};

SC_MODULE(top) {
    sc_link_mp<int> link;
    ...
};
    
```



Time Control in SystemC

- “sc_time” – numeric magnitude + time unit
- time units – SC_SEC, SC_MS, SC_US, SC_NS, SC_PS, SC_FS
`sc_time t_PERIOD (5, SC_NS)`
- “sc_start()” – simulation phase = initialization + execution
- “sc_start()”, “~~sc_start(10000)~~”, “sc_start(10, SC_SEC)”
- “sc_time_stamp()” – current simulation time
- “cout << sc_time_stamp() << endl;”
- “wait()” – delaying for a certain time
- “wait(2, SC_MS);”
- **Waiting and Watching**
 - Suspend / reactivate process execution (SC_THREAD, SC_CTHREAD)
 - Suspension: wait(); / Reactivation: event on a sensitive signal
 - Halt process execution until an event occurs (SC_CTHREAD only)
 - do { wait(); } while (my_bool_sig.read() != true);



Cycle-Accurate Simulation Scheduler

- (1) All clock signals that change their value at the current time are assigned their new value.
- (2) All *SC_METHOD* / *SC_THREAD* processes with inputs that have changed are executed. The entire bodies of *SC_METHOD* processes are executed. *SC_THREAD* processes are executed until the next *wait()* statement suspends execution. *SC_METHOD* / *SC_THREAD* processes are not executed in a fixed order.
- (3) All *SC_CTHREAD* processes that are triggered have their outputs updated and are saved in a queue to be executed in step 5. All outputs of *SC_METHOD* / *SC_THREAD* processes that were executed in step 2 are also updated.
- (4) Step 2 and step 3 are repeated until no signal changes its value.
- (5) All *SC_CTHREAD* processes that were triggered and queued in step 3 are executed. There is no fixed execution order of these processes. Their outputs are updated at the next active edge (when step 3 is executed), and therefore are saved internally.
- (6) Simulation time is advanced to the next clock edge and the scheduler goes back to step 1.



Example #1

```
// David C. Black, Jack Donovan. SystemC: From the Ground Up. Springer, 2004
#include <systemc.h>
#include <iostream>
SC_MODULE (HelloWorld) {
    sc_in_clk iclk;
    SC_CTOR (HelloWorld) {
        SC_METHOD (main_method);
        sensitive << iclk.neg();
        dont_initialize();
    }
    void main_method (void)
    { std::cout << sc_time_stamp() << " Hello world!" << std::endl; }
};

int sc_main (int argc, char *argv[]) {
    const sc_time t_PERIOD(8,SC_NS);
    sc_clock clk ("clk",t_PERIOD);
    HelloWorld iHelloWorld ("iHelloWorld");
    iHelloWorld.iclk(clk);
    sc_start(10,SC_NS);
    return 0;
}
```



Example #1

```
> g++ -I/cad/sysC/2.2/include -I/cad/sysC/2.2/lib hello.C -lsystemc
> a.out
```

```
SystemC 2.2.0 --- Nov 25 2010 16:19:37
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4 ns Hello world!
```

- **Debugging?**

- VCD - Value Change Dump format
- GTKWave Electronic Waveform Viewer
- <http://www.cs.manchester.ac.uk/apt/projects/tools/gtkwave/>

```
// Create a file for waveform
sc_trace_file *trcf = sc_create_vcd_trace_file("trace-it");
if (trcf==NULL) cout << "Sorry, no tracing..." << endl;
sc_trace(trcf,clk,"clk");

sc_start(10,SC_NS); // Invoke the simulator
sc_close_vcd_trace_file(trcf);
```



Example #2 (process_1)

```
// header file: process_1.h // implementation file: process_1.cc

SC_MODULE( process_1 ) { #include "systemc.h"
                           #include "process_1.h"

    // Ports
    sc_in<clk> clk;
    sc_in<int> a;
    sc_in<bool> ready_a;
    sc_out<int> b;
    sc_out<bool> ready_b;

    // Process functionality
    void do_process_1();

    // Constructor
    SC_CTOR( process_1 ) {
        SC_CTHREAD(do_process_1,clk.pos());
    }

}; void process_1::do_process_1()
{
    int v;
    while ( true ) {
        do wait(); while(ready_a.read()!=true);
        v = a.read();
        v += 5;
        cout << "P1: v = " << v << endl;
        b.write( v );

        ready_b.write( true );
        wait();
        ready_b.write( false );
    }
}
```




Example #2 (process_2)

```
// header file: process_2.h
SC_MODULE( process_2 ) {
    // Ports
    sc_in<clk> clk;
    sc_in<int> a;
    sc_in<bool> ready_a;
    sc_out<int> b;
    sc_out<bool> ready_b;

    // Process functionality
    void do_process_2();

    // Constructor
    SC_CTOR( process_2 ) {
        SC_CTHREAD( do_process_2, clk.pos() );
    }
};

// implementation file: process_2.cc
#include "systemc.h"
#include "process_2.h"

void process_2::do_process_2()
{
    int v;
    while ( true ) {
        do wait(); while(ready_a.read()!=true);
        v = a.read();
        v += 3;
        cout << "P2: v = " << v << endl;
        b.write( v );

        ready_b.write( true );
        wait();
        ready_b.write( false );
    }
}
```



Example #2 (main)

```
// implementation file: main.cc
#include "systemc.h"
#include "process_1.h"
#include "process_2.h"

int sc_main (int ac, char *av[])
{
    sc_report_handler::set_actions
        ("/IEEE Std 1666/deprecated",
        SC_DO_NOTHING);
    sc_signal<int> s1 ( "Signal-1" );
    sc_signal<int> s2 ( "Signal-2" );
    sc_signal<bool> ready_s1 ( "Ready-1" );
    sc_signal<bool> ready_s2 ( "Ready-2" );

    sc_clock clock("Clock", 20, 0.5, 0.0);

    process_1 p1 ( "P1" );
    p1.clk( clock );
    p1.a( s1 );
    p1.ready_a( ready_s1 );

    p1.b( s2 );
    p1.ready_b( ready_s2 );

    process_2 p2 ( "P2" );
    p2.clk( clock );
    p2.a( s2 );
    p2.ready_a( ready_s2 );
    p2.b( s1 );
    p2.ready_b( ready_s1 );

    s1.write(0);
    s2.write(0);
    ready_s1.write(true);
    ready_s2.write(false);

    sc_start(100000, SC_NS);

    return 0;
}
```



Example #2 (results)

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```
P1: v = 5
P2: v = 8
P1: v = 13
P2: v = 16
P1: v = 21
P2: v = 24
P1: v = 29
P2: v = 32
P1: v = 37
P2: v = 40
...
P1: v = 19973
P2: v = 19976
P1: v = 19981
P2: v = 19984
P1: v = 19989
P2: v = 19992
P1: v = 19997
```



ModelSim SE & SystemC

- From “ModelSim SE User’s Manual”
- The following modifications are needed:
 - Replace “sc_main()” with an SC_MODULE, and potentially add a process to contain any testbench code
 - Replace “sc_start()” by using the “run” command in the GUI
 - Remove calls to “sc_initialize()”
 - Export the top level SystemC design unit(s) using the SC_MODULE_EXPORT macro
 - Verify that SystemC signal, ports and modules are explicitly named to avoid port binding and debugging errors. Disabling of automatic name binding may be needed.
 - SC_CTOR (or the SC_MTI_BIND_NAME) macro is used
 - use “-nonamebind” argument when compiling



ModelSim SE & SystemC

```

int sc_main(int argc, char* argv[])
{
    sc_signal<bool> mysig;
    mymod mod("mod");
    mod.outp(mysig);

    sc_start(100, SC_NS);
}

SC_MODULE(mytop)
{
    sc_signal<bool> mysig;
    mymod mod;

    SC_CTOR(mytop):
        mysig("mysig"),
        mod("mod")
    {
        mod.outp(mysig);
    }
};

SC_MODULE_EXPORT(mytop);

```



MUX example & GNU C/C++

```

// mux.h
#include "systemc.h"

SC_MODULE(mux) {
    int const static bit_number=8;
    sc_in <sc_bv <bit_number> > a_in;
    sc_in <sc_bv <bit_number> > b_in;
    sc_in <sc_bit> juht;
    sc_out <sc_bv <bit_number> > out_sig;

    SC_CTOR(mux): a_in("a_in"), b_in("b_in"),
        juht("juht"), out_sig("out_sig") {
        cout<<"mux constructor"<<endl;
        SC_METHOD( choose_out );
        sensitive<<juht<<a_in<<b_in;
    }

    void choose_out() {
        if (juht.read())
            out_sig.write(a_in.read());
        else out_sig.write(b_in.read());
    }
};

// t_mux.cpp
#include "systemc.h"
#include "mux.h"

SC_MODULE(t_mux) {
    int const static num_bits=8;
    sc_signal <sc_bv <num_bits> > t_a_in;
    sc_signal <sc_bv <num_bits> > t_b_in;
    sc_signal <sc_bit> t_juht;
    sc_signal <sc_bv <num_bits> > t_out_sig;
    mux* mux_instance;
    void stimulus();

    SC_CTOR(t_mux): t_a_in("t_a_in"),
        t_b_in("t_b_in"), t_juht("t_juht"),
        t_out_sig("t_out_sig") {
        cout<<"t_mux constructor"<<endl;
        mux_instance=new mux("mux");
        mux_instance->a_in(t_a_in);
        mux_instance->b_in(t_b_in);
        mux_instance->juht(t_juht);
        mux_instance->out_sig(t_out_sig);
        SC_THREAD(stimulus);
    }
};

```



MUX example & GNU C/C++

```
// t_mux.cpp ...
void t_mux::stimulus()
{
    t_a_in.write("11111111");
    t_b_in.write("00001111");
    t_juht.write((sc_bit)0);
    wait(1, SC_PS);

    t_juht.write((sc_bit)1);
    wait(10, SC_NS);

    t_juht.write((sc_bit)0);
    wait(10, SC_NS);

    t_a_in.write("11110000");
    t_b_in.write("10101010");
    t_juht.write((sc_bit)0);
    wait(10, SC_NS);

    t_juht.write((sc_bit)1);
    wait();
}

// t_mux.cpp ...
int sc_main(int args, char* argv[])
{
    t_mux testMux("t_mux");
    sc_trace_file *trcf=
        sc_create_vcd_trace_file("trace-it");
    if(trcf==NULL) cout<<"Sorry, no tracing..."<<endl;
    sc_trace(trcf, testMux.t_a_in, "t_a_in");
    sc_trace(trcf, testMux.t_b_in, "t_b_in");
    sc_trace(trcf, testMux.t_juht, "t_juht");
    sc_trace(trcf, testMux.t_out_sig, "t_out_sig");
    sc_start(40, SC_NS);
    sc_close_vcd_trace_file(trcf);
    return 0;
}

-----
> g++ -I/cad/sysC/2.2/include -L/cad/sysC/2.2/lib
    t_mux.cpp -lsystemc -o mux
> ./mux
> gtkwave trace-it.vcd
```



MUX example & GTKWave

