Vivado Design Suite User Guide

Using Constraints

UG903 (v2013.1) March 20, 2013

XILINX®

Revision History

The following table shows the revision history for this document.

Date	Version	Revision
03/20/2013	2013.1	Added new sections on Multicycle Paths, False Paths, and Min/Max Delays in Chapter 6, Timing Exceptions. Moved Chapter 9, Defining Relatively Placed Macros, from the *Vivado Design Suite User Guide: Design Analysis and Closure Techniques (UG906)* [Ref 5] to the current document. Added substantial new material in Chapter 4, Clock Groups, particularly with respect to Asynchronous Clocks and Unexpandable Clocks. Added new Appendix B, Supported XDC and SDC Commands. Updated figures and coding examples.

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Introduction

Migrating From UCF Constraints to XDC Constraints

The Vivado® Integrated Design Environment (IDE) uses Xilinx® Design Constraints (XDC), and does not support the legacy User Constraints File (UCF) format.

There are key differences between Xilinx Design Constraints (XDC) and User Constraints File (UCF) constraints. XDC constraints are based on the standard Synopsys Design Constraints (SDC) format. SDC has been in use and evolving for more than 20 years, making it the most popular and proven format for describing design constraints.

If you are familiar with UCF but new to XDC, see the "Differences Between XDC and UCF Constraints" section in the "Migrating UCF Constraints to XDC" chapter of the *Vivado Design Suite Migration Methodology Guide (UG911)* [Ref 7]. That chapter also describes how to convert existing UCF files to XDC *as a starting point* for creating XDC constraints.

IMPORTANT: *XDC has fundamental differences from UCF that must be understood in order to properly constrain a design. The UCF to XDC conversion utility is not a replacement for properly understanding and creating XDC constraints. Each XDC constraint is described in this User Guide.*

About XDC Constraints

XDC constraints are a combination of:

- Industry standard Synopsys Design Constraints (SDC version 1.9); and
- Xilinx proprietary physical constraints

XDC constraints have the following properties:

- They are not simple strings, but are commands that follow the Tcl semantic.
- They can be interpreted like any other Tcl command by the Vivado Tcl interpreter.
- They are read in and parsed sequentially the same as other Tcl commands.

You can enter XDC constraints in several ways, at different points in the flow.

- Store the constraints in one or more XDC files.

  To load the XDC file in memory: (1) use the **read_xdc** command; or (2) add it to one of your project constraints sets. XDC files accept the following built-in Tcl commands only: set, list, and expr.

- Generate the constraints with a Tcl script.

  To execute the Tcl script: (1) run the **source** command; or (2) add the Tcl script to one of your project constraints sets.

IMPORTANT: *The Vivado Design Suite allows you to mix XDC files and Tcl scripts in the same constraints set. Modified constraints are saved back to their original location only if they originally came from an XDC file, and not from a Tcl script. A constraint generated by a Tcl script cannot be interactively modified. For more information, see Chapter 2, Constraints Methodology.*

To validate the syntax or impact of a particular constraint after loading your design in memory, use the Tcl console and the Vivado Design Suite reporting features. This is particularly powerful for analyzing and debugging timing constraints and physical constraints.

Constraints Methodology

About Constraints Methodology

Design constraints define the requirements that must be met by the compilation flow in order for the design to be functional on the board. Not all constraints are used by all steps in the compilation flow. For example, physical constraints are used only during the implementation steps (that is, by the placer and the router).

Because the Vivado® Integrated Design Environment (IDE) synthesis and implementation algorithms are timing-driven, you must create proper timing constraints. Over-constraining or under-constraining your design makes timing closure difficult. You must use reasonable constraints that correspond to your application requirements.

Organizing Your Constraints

The Vivado IDE allows you to use one or many constraint files. While using a single constraint file for the entire compilation flow might seem more convenient, it can be a challenge to maintain all the constraints as the design becomes more complex. This is usually the case for designs that use several IPs or large blocks developed by different teams.

RECOMMENDED: *Xilinx recommends that you separate timing constraints and physical constraints by saving them into two distinct files. You can also keep the constraints specific to a certain module in a separate file.*

Project Flows

You can add your XDC files to a constraints set during the creation of a new project, or later, from the Vivado IDE menus. For more information, see the *Vivado Design Suite User Guide: System-Level Design Entry (UG895)* [Ref 1].

Figure 2-1, Single or Multi XDC, shows two constraint sets in a project:

- The first constraint set includes two XDC files.
- The second constraint set uses only one XDC file containing all the constraints.

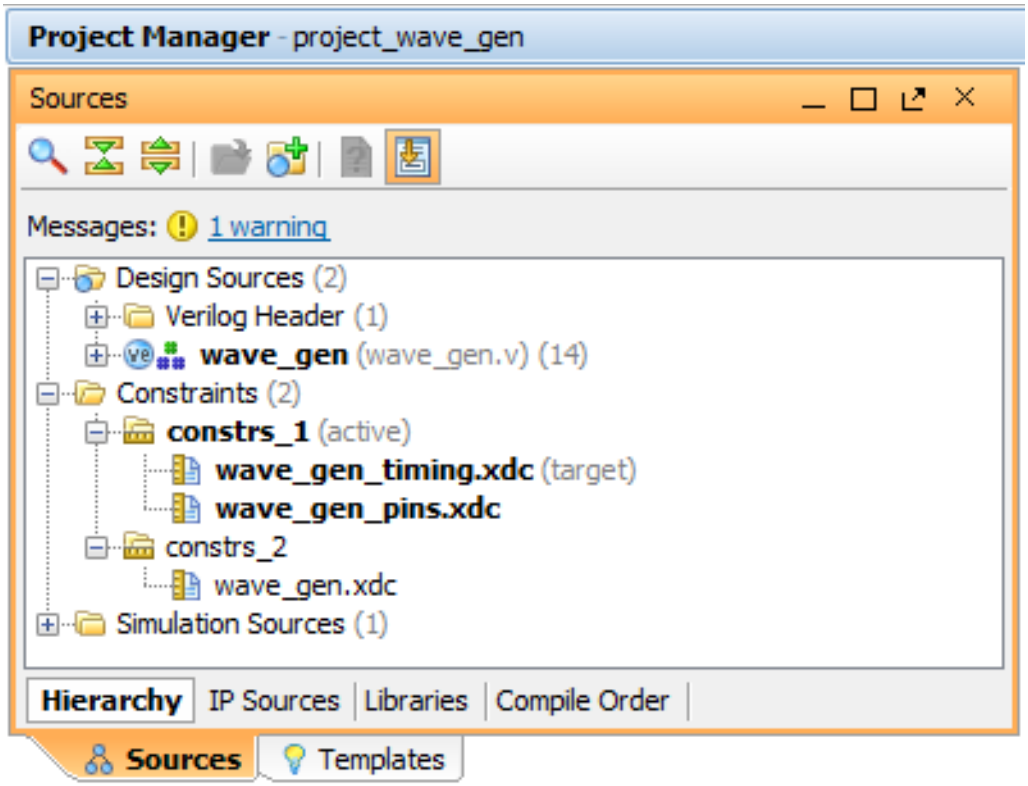

Figure 2-1: **Single or Multi XDC**

IMPORTANT: *If your project contains an IP that uses its own constraints, the corresponding constraint file does not appear in the constraints set. Instead, it is listed along with the IP source files.*

You can also add Tcl scripts to your constraints set. Tcl scripts are sourced last after the XDC files when opening a design in memory.

An XDC file or a Tcl script can be used in several constraints sets if needed. For more information on how to create and add constraint files and constraints sets to your project, see "Working with Constraints" in the *Vivado Design Suite User Guide: System-Level Design Entry (UG895)* [Ref 1].

Non-Project Flows

In a Non-Project flow, you must read each file individually before executing the compilation commands.

The example script below shows how to use one or more XDC files for synthesis and implementation.

Example Script

```
read_verilog [glob src/*.v]
read_xdc wave_gen_timing.xdc
read_xdc wave_gen_pins.xdc
synth_design -top wave_gen
opt_design
place_design
route_design
```

Synthesis and Implementation Constraint Files

By default, all XDC files and Tcl scripts added to a constraint set are used for both synthesis and implementation. Set the USED_IN_SYNTHESIS and USED_IN_IMPLEMENTATION properties on the XDC file or the Tcl script to change this behavior. This property can take the value of either TRUE or FALSE.

For example, to use a constraint file for implementation only:

1. Select the constraint file in the Sources window.
2. In the Source File Properties window:
   a. Uncheck **Synthesis**.
   b. Check **Implementation**.
3. Click **Apply**.

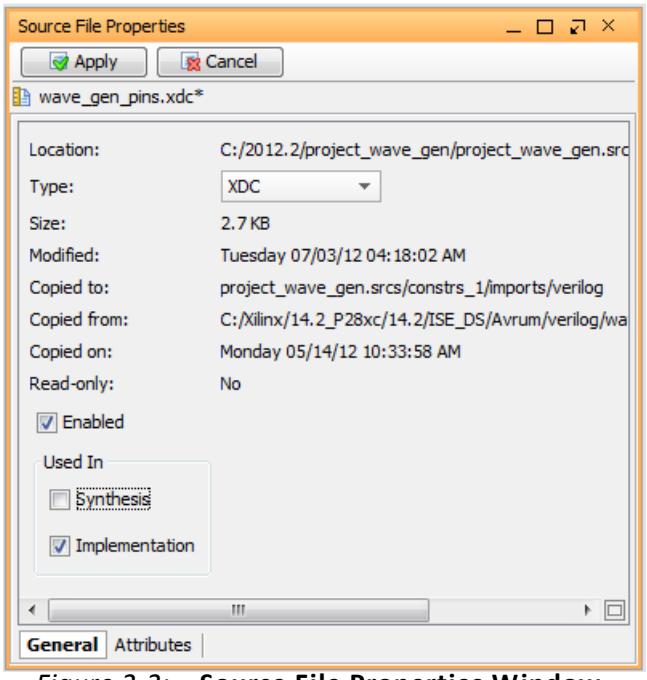

Figure 2-2: **Source File Properties Window**

The equivalent Tcl commands are:

```
set_property used_in_synthesis false [get_files wave_gen_pins.xdc]
set_property used_in_implementation true [get_files wave_gen_pins.xdc]
```

When running the Vivado IDE in Non-Project Mode, you can read in the constraints directly between any steps of the flow. The properties **used_in_synthesis** and **used_in_implementation** do not matter in this mode.

The following compilation Tcl script shows how to read two XDC files for different steps of the flow:

```
read_verilog [glob src/*.v]
read_xdc wave_gen_timing.xdc
synth_design -top wave_gen -part xc7k325tffg900-2
read_xdc wave_gen_pins.xdc
opt_design
place_design
route_design
```

Table 2-1: **Reading XDC Files Before and After Synthesis**

File Name	File Placement	Used For
wave_gen_timing.xdc	Before synthesis	• Synthesis • Implementation
wave_gen_pins.xdc	After synthesis	• Implementation

Note: The constraints read in *after* synthesis are applied in addition to the constraints read in *before* synthesis.

Ordering Your Constraints

Because XDC constraints are applied sequentially, and are prioritized based on clear precedence rules, you must review the order of your constraints carefully. For more information, see Chapter 7, XDC Precedence.

The Vivado IDE provides full visibility into your design. To validate your constraints step by step:

1. Run the appropriate report commands.
2. Review the messages in the Tcl Console or the Messages window.

Recommended Constraints Sequence

RECOMMENDED: *Whether you use one or several XDC files for your design, organize your constraints in the following sequence.*

```
## Timing Assertions Section
# Primary clocks
# Virtual clocks
# Generated clocks
# Clock Groups
# Input and output delay constraints

## Timing Exceptions Section
# False Paths
# Max Delay / Min Delay
# Multicycle Paths
# Case Analysis
# Disable Timing

## Physical Constraints Section
# located anywhere in the file, preferably before or after the timing constraints
# or stored in a separate constraint file
```

Start with the clock definitions. The clocks must be created before they can be used by any subsequent constraints. Any reference to a clock before it has been declared results in an error and the corresponding constraint is ignored. This is true within an individual constraint file, as well as across all the XDC files (or Tcl scripts) in your design.

The order of the constraint files matters. You must be sure that the constraints in each file do not rely on the constraints of another file. If this is the case, you must read the file that

contains the constraint dependencies last. If two constraint files have interdependencies, you must either:

- Merge them manually into one file that contains the proper sequence, or
- Divide the files into several separate files, and order them correctly.

Constraints Sequence Editing

The Vivado IDE constraints manager saves any edited constraint back to its original location in the XDC files, but not in Tcl scripts. Any new constraint is saved at the end of the XDC file marked as *target*. In many cases, when your constraints set contains several XDC files, the target constraint file is not the last file in the list, and will not be loaded last when opening or reloading your design. As a consequence, the constraints sequence saved on disk can be different from the one you had previously in memory.

IMPORTANT: *You must verify that the final sequence stored in the constraint files still works as expected. If you must modify the sequence, you must modify it by directly editing the constraint files. This is especially important for timing constraints.*

Constraint Files Order

In a project flow without any IP, all the constraints are located in a constraints set. By default, the order of the XDC files displayed in the Vivado IDE defines the read sequence used by the tool when loading an elaborated or synthesized design into memory (except for Tcl scripts, which are always sourced last, in the same sequence you added them to the constraints set). The file at the top of the list is read in first, and the bottom one is read in last. You can change the order by simply selecting the file in the IDE, and moving it to the desired place in the list.

For example, in Figure 2-3, Changing XDC File Order in the Vivado IDE Example, the file `wave_gen_pin.xdc` was moved to before the file `wave_gen_timing.xdc` by using drag and drop.

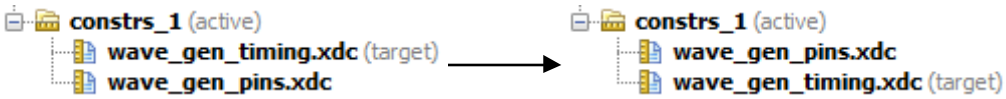

Figure 2-3: **Changing XDC File Order in the Vivado IDE Example**

The equivalent Tcl command is:

```
reorder_files -fileset constrs_1 -before [get_files wave_gen_timing.xdc] \
  [get_files wave_gen_pins.xdc]
```

Table 2-2: **File Order Before and After**

File	Order (Before)	Order (After)
Wave_gen_timing.xdc	1	2
Wave_gen_pins.xdc	2	1

In a Non-Project flow, the sequence of the **read_xdc** calls determines the order in which the constraint files are evaluated.

Constraint Files Order with IPs

Many IPs are delivered with one or more XDC files. When such IPs are generated within your RTL project, their XDC files are also used during the various design compilation steps.

For example, Figure 2-5, XDC Files in the IP Sources, shows that one of the IPs in the project comes with an XDC file.

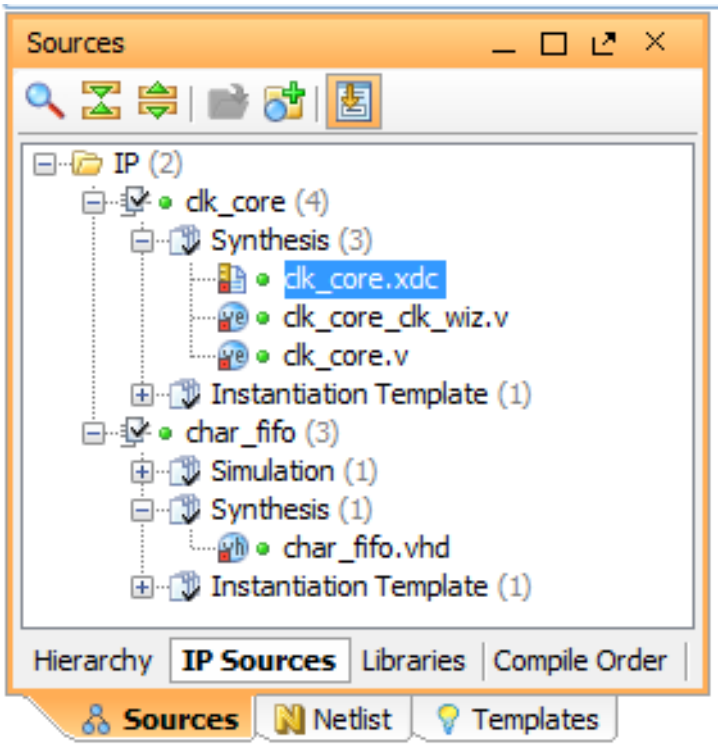

Figure 2-5: **XDC Files in the IP Sources**

By default, user XDC files are read in before the IP files. There is an exception for the IPs that define primary clocks, for example the Clocking Wizard. In this case, the IP XDC is read by default first, This allows the user constraints to refer to the clocks created by the IP.

This behavior is controlled by the PROCESSING_ORDER property, which is set for each XDC file:

- **EARLY:** Files that must be read first
- **NORMAL:** Default
- **LATE:** Files that must be read last

For user XDC files that belong to the same PROCESSING_ORDER group, their relative order displayed in the Vivado IDE determines their read sequence. The order within the group can be modified by moving the files in the Vivado IDE constraints set, or by using the **reorder_files** command. The same rule applies to Tcl scripts present in the constraint set. Finally, for user constraint files of a same PROCESSING_ORDER group, the XDC files are loaded first, and the Tcl scripts next.

For IP XDC files which belong to the same PROCESSING_ORDER group, the order is determined by import or creation sequence of the IPs. This order cannot be changed once the project has been created.

Finally, the relative order between user groups and IP XDC PROCESSING_ORDER groups are as follow:

1. User Constraints marked as EARLY
2. IP Constraints marked as EARLY
3. User Constraints marked as NORMAL
4. IP Constraints marked as NORMAL
5. IP Constraints marked as LATE
6. User Constraints marked as LATE

Figure 2-6, Setting the XDC File PROCESSING_ORDER Example, shows an example of how to set the PROCESSING_ORDER property:

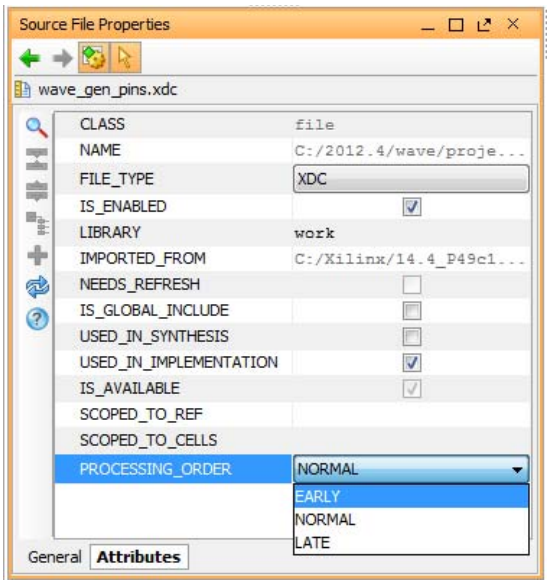

Figure 2-6: **Setting the XDC File PROCESSING_ORDER Example**

The equivalent Tcl command is:

```
set_property PROCESSING_ORDER EARLY [get_files wave_gen_pins.xdc]
```

RECOMMENDED: *Use the* **report_compile_order –constraints** *command in the Tcl console to report the XDC files read sequence determined by the tool based the properties mentioned above, including IS_ENABLED, USED_IN_SYNTHESIS, and USED_IN_IMPLEMENTATION.*

Changing Read Order

To change the read order:

1. Select the XDC file you want to move.
2. Drag and drop the XDC file to the desired place in the list.

For the example shown in Figure 2-1, Single or Multi XDC, page 9, the equivalent Tcl command is:

```
reorder_files -fileset constrs_1 -before [get_files wave_gen_timing.xdc] \
  [get_files wave_gen_pins.xdc]
```

The same mechanism applies to Tcl scripts. In a Non-Project flow, the sequence of the **read_xdc** and **source** commands determines the order of the constraint files.

If you use the native IPs that come with a constraint file, the IP XDC files are loaded after your files, in the same sequence as the IPs are listed in the IP Sources window, unless the file PROCESSING_ORDER properties are not set to DEFAULT. For example, Figure 2-7, XDC Files in the IP Sources, shows that one of the project IPs comes with an XDC file.

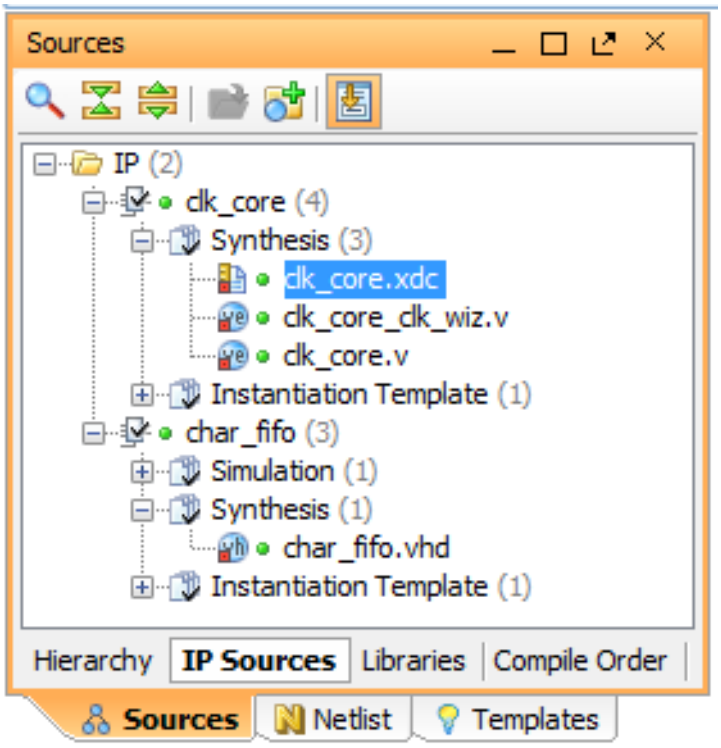

Figure 2-7: **XDC Files in the IP Sources**

When you open your design, the log file shows that the IP XDC file was loaded last:

```
Parsing XDC File [C:/project_wave_gen.srcs/constrs_2/wave_gen_all.xdc]
INFO: [Timing 38-35] Done setting XDC timing constraints.
[C:/project_wave_gen.srcs/constrs_2/wave_gen_all.xdc:9]
INFO: [Timing 38-2] Deriving generated clocks
[C:/project_wave_gen.srcs/constrs_2/wave_gen_all.xdc:9]
Finished Parsing XDC File [C:/project_wave_gen.srcs/constrs_2/wave_gen_all.xdc]
Parsing XDC File [c:/project_wave_gen.srcs/sources_1/ip/clk_core/clk_core.xdc] for
cell 'clk_gen_i0/clk_core_i0/inst'
Finished Parsing XDC File
[c:/project_wave_gen.srcs/sources_1/ip/clk_core/clk_core.xdc] for cell
'clk_gen_i0/clk_core_i0/inst'
```

Unlike with the User XDC files, you cannot directly change the read order of the IP XDC files that belong to the same PROCESSING_ORDER group. If you must modify the order, do the following:

1. Disable the corresponding IP XDC files (IS_ENABLED set to false).
2. Copy their content.
3. Paste the content into one of the XDC files included in your constraints set.

4. Update the copied IP XDC commands with the full hierarchical netlist object path names wherever needed. Doing so is required because the IP XDC constraints are written in such a manner that they can be scoped to the IP instance.
5. Review the **get_ports** queries that are processed in a special way for scoped constraints. For more information on XDC scoping, see Constraints Scoping.

Entering Constraints

The Vivado IDE provides several ways to enter constraints. Unless you directly edit the XDC file in a text editor, you must open a design database (elaborated, synthesized or implemented) in order to access the constraints windows in the Vivado IDE.

Saving Constraints in Memory

You must have a design in memory to validate your constraints during editing. When you edit a constraint using the Vivado IDE user interface, the equivalent XDC command is issued in the Tcl Console in order to apply it in memory. An edited timing constraint must be applied in memory before it can be saved to the XDC file.

Before you can run synthesis or implementation, you must save the constraints in memory back to an XDC file that belongs to the project. The Vivado IDE prompts you to save your constraints whenever necessary.

To manually save your constraints:

- Click **Save Constraints**, or
- Select **File > Save Constraints**.

Running these commands:

- Saves all *new* constraints to the XDC file marked `target` in the constraints set associated with your design.
- Saves all *edited* constraints back to the XDC file from which they originated.

  Note: The constraints management system preserves the original XDC files format as much as possible.

Constraints Editing Flow Options

Figure 2-8, Constraints Editing Flow, shows the recommended flow options. Do not use both options at the same time. Mixing these options may cause you to lose constraints. The recommended flow options are:

- User Interface Option
- Hand Edit Option

User Interface Option

Because the Vivado IDE manages your constraints, you must not edit your XDC files at the same time. When the Vivado IDE saves the memory content:

- The modified constraints replace the original constraints in their original file.
- The new constraints are appended to the file marked as *target*.
- All manual edits in the XDC files are overwritten.

Hand Edit Option

When you use the Hand Edit option, you are in charge of editing and maintaining the XDC files. While you will probably use the Tcl Console to verify the syntax of some constraints, you must discard the changes made in memory when closing or reloading your design.

In case of a conflict when saving the constraints, you are prompted to choose among:

- Discarding the changes made in memory, or
- Saving the changes in a new file, or
- Overwriting the XDC files.

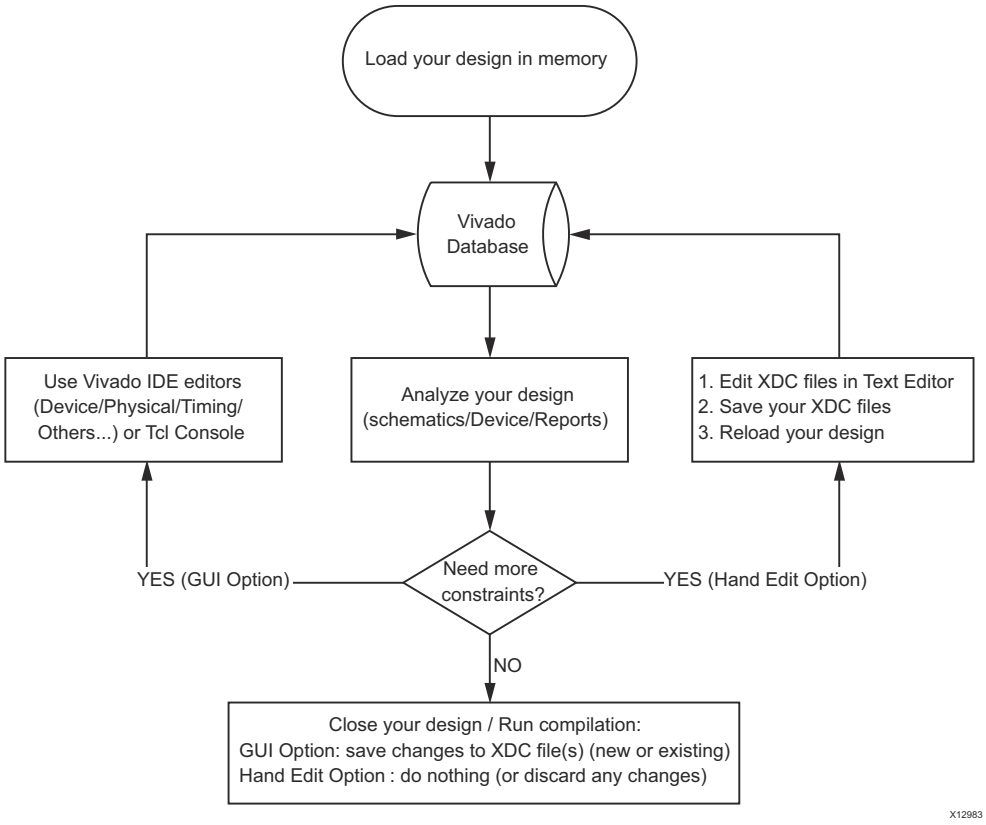

Figure 2-8: **Constraints Editing Flow**

Constraints creation is iterative. You can use IDE editors in some cases, and hand edit the constraint files in others.

Within each iteration described on Figure 2-8, Constraints Editing Flow, do not use both options at the same time.

If you switch between the two options, you must first save your constraints or reload your design, to ensure that the constraints in memory are properly synchronized with the XDC files.

Pin Assignment

To create and edit existing top-level ports placement when using the RTL Analysis, Synthesis, or Implementation views:

1. Select the I/O Planning pre-configured layout.

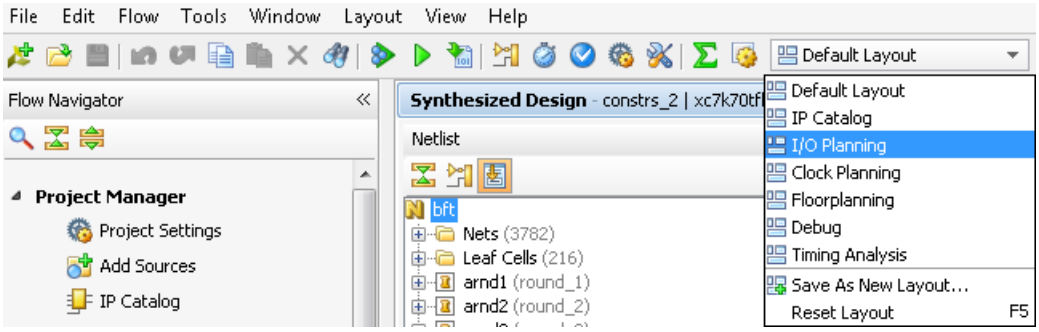

Figure 2-9: **IO Planning Layout**

2. Open the windows shown in Table 2-3, Creating and Editing Existing Top-Level Ports Placement.

Table 2-3: **Creating and Editing Existing Top-Level Ports Placement**

Window	Function
Device	View and edit the location of the ports on the device floorplan.
Package	View and edit the location of the ports on the device package.
I/O Ports	Select a port, drag and drop it to a location on the Device or Package view, as well as review current assignment and properties of each port.
Package Pins	View the resource utilization in each I/O bank.

For more information on Pin Assignment, see the *Vivado Design Suite User Guide: I/O and Clock Planning (UG899)* [Ref 2].

Clock Resources Assignment

To view and edit the placement of your clock trees when using the RTL Analysis, Synthesis, or Implementation views:

1. Select the Clock Planning pre-configured layout.

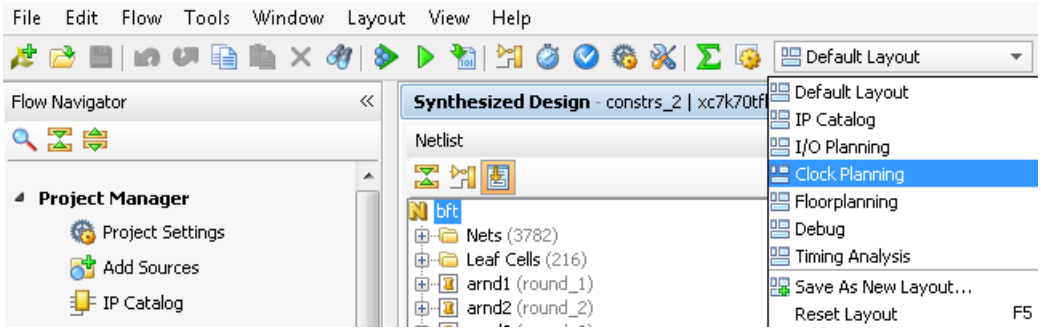

Figure 2-10: **Clock Planning Layout**

2. Open the windows shown in Table 2-4, Viewing and Editing the Placement of Clock Trees.

Table 2-4: **Viewing and Editing the Placement of Clock Trees**

Window	Function
Clock Resources	• View the connectivity between the clock resources in the architecture. • View where your clock tree cells are currently located.
Netlist	• Drag and drop the clock resources from your netlist to a specific location in the Clock Resources window or Device window.

For more information on Clock Resources Assignment, see the *Vivado Design Suite User Guide: I/O and Clock Planning (UG899)* [Ref 2].

Floorplanning

To create and edit Pblocks when using the RTL Analysis, Synthesis, or Implementation views:

1. Select the Floorplanning pre-configured layout.

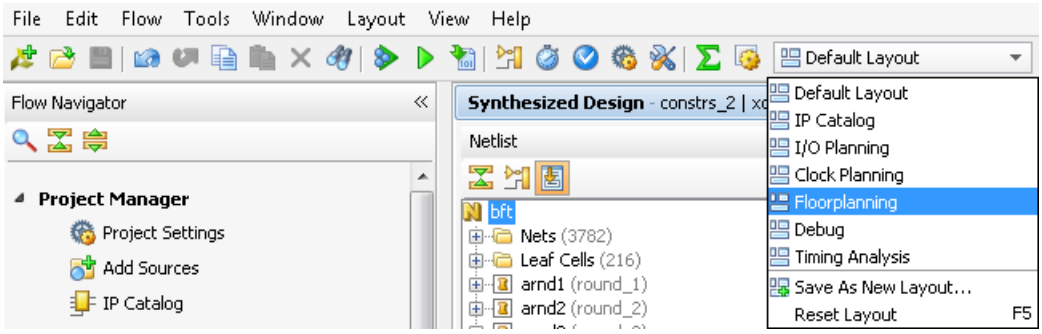

Figure 2-11: **Floorplanning Layout**

2. Open the windows shown in Table 2-5, Creating and Editing Pblocks.

Table 2-5: **Creating and Editing Pblocks**

Window	Function
Netlist	Select the cells to be assigned to a Pblock.
Physical Constraints	Review the existing Pblocks and their properties.
Device	Create or edit the shape and location of your Pblocks in the device.

To create cell placement constraints on a particular BEL or SITE:

1. Select the cell in the Netlist view.
2. Drag and drop the cell to the target location in the Device view.

For more information on Floorplanning, see the *Vivado Design Suite User Guide: Design Analysis and Closure Techniques (UG906)* [Ref 5].

Timing Constraints Window

The Timing Constraints window is available for Synthesized and Implemented designs only. For elaborated design constraints, you must use and edit XDC files directly. For more information, see Creating Synthesis Constraints.

You can open the Timing Constraints window using one of the following three options, as shown in Figure 2-12, Multiple Methods for Opening the Timing Constraints Window:

- Select **Window > Timing Constraints**.
- In the Synthesis section of the Flow Navigator panel, select **Synthesized Design > Edit Timing Constraints**.

- In the Implementation section of the Flow Navigator panel, select **Implemented Design > Edit Timing Constraints**.

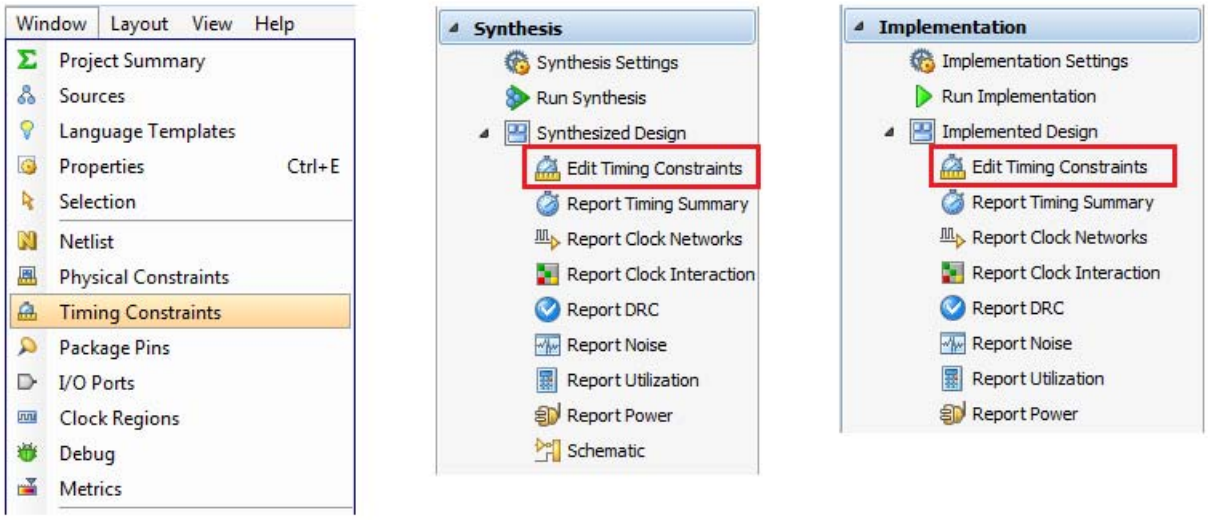

Figure 2-12: **Multiple Methods for Opening the Timing Constraints Window**

The Timing Constraints editor displays the timing constraints in memory, in either:

- The same sequence as in the XDC files and Tcl scripts, or
- The same sequence in which you entered them in the Tcl Console.

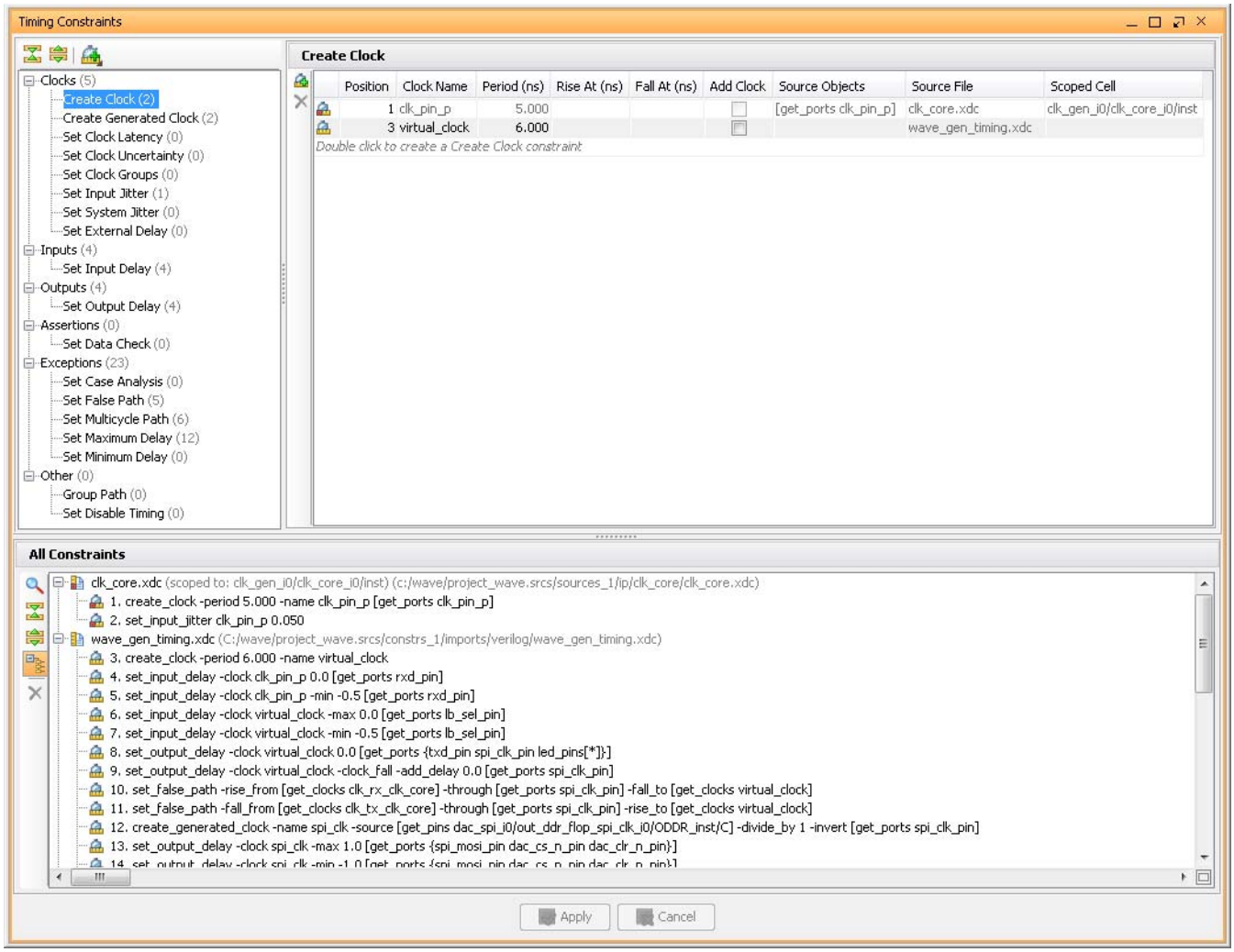

Figure 2-13: **Timing Constraints Window**

Some of the constraints cannot be edited from this window. They are marked with the XDC No Edit icon.

Timing Constraints Spreadsheet

The timing constraints spreadsheet displays the details of all existing constraints of a specific type. Use the timing constraints spreadsheet to review and edit constraint options.

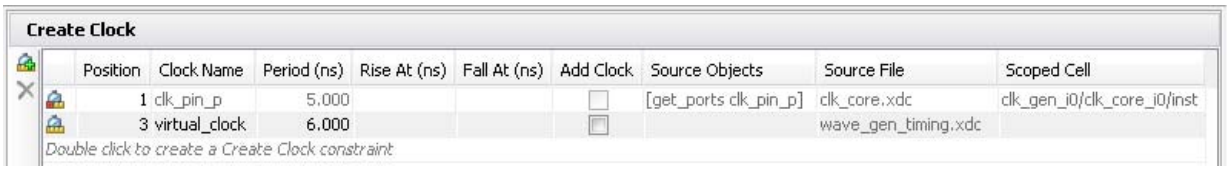

Figure 2-14: **Timing Constraints Spreadsheet**

The two last columns of the panel show:

- **Source File**: The name of the XDC file or Tcl script the constraint comes from
- **Scoped Cell**: The name of the current instance when the constraint was applied. This name usually corresponds to an IP instance which is delivered with dedicated constraints. For more information, see Constraints Scoping.

A new constraint of the selected type can be created by double clicking the last line of the spreadsheet. The corresponding constraint creation dialog opens and lets you fill in the details of the new constraint. Click **OK** to apply the constraint in memory and close the window. A new line in the spreadsheet shows the new constraint information.

You can edit any existing constraint by modifying the values directly in the spreadsheet. Once you have finished editing, click **Apply** to apply the modified constraints in memory.

IMPORTANT: *Applying a new or modified constraint does not save it in the XDC file. You must click* ***Save Constraints*** *to save it.*

IMPORTANT: *IP constraints cannot be edited or deleted. In order to modify a constraint delivered with an IP, you must: (1) disable the corresponding IP XDC file; (2) copy the constraint to your XDC file; and (3) edit the constraint as desired.*

Constraints Creation, Grouped by Category

When you select a constraint type, the corresponding spreadsheet appears on the right sub-window panel. This allows you to view all the constraints of the same type that have already been created.

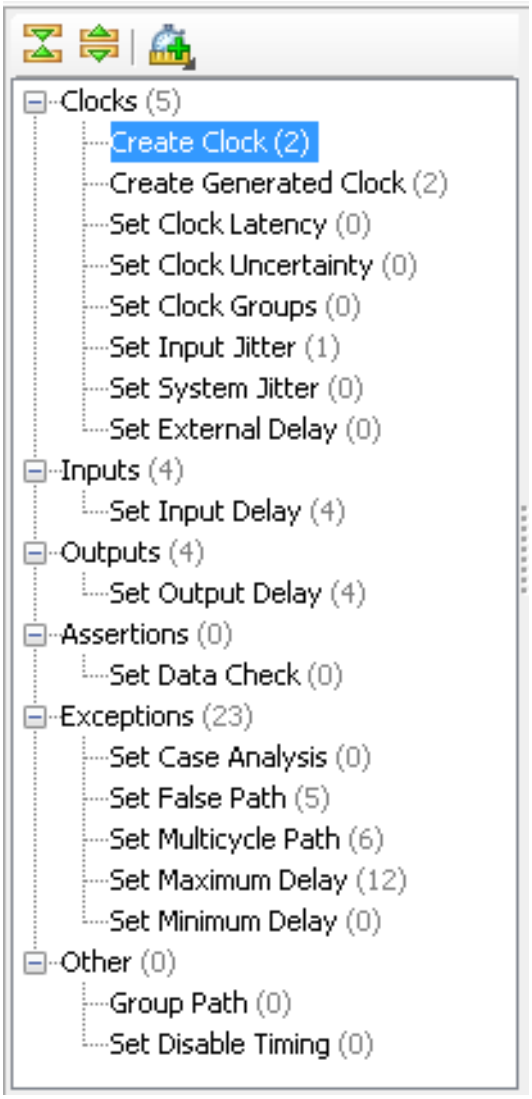

Figure 2-15: **Timing Constraints Categories**

To create a new constraint, double click the name of the target constraint. A dialog box allows you to specify the value for each option. When you click **OK**, the tool:

1. Validates the syntax.
2. Applies it to the memory.
3. Adds the new constraint at the end of the spreadsheet.
4. Adds the new constraint at the end of your complete list of constraints.

All Constraints

The bottom of the window displays the complete list of constraints loaded in memory, in the same sequence as they were applied. The constraints are grouped in accordance with the XDC file or the Tcl script from which they originated. When an XDC file is scoped to a particular hierarchical cell, the cell name is displayed next to the file name.

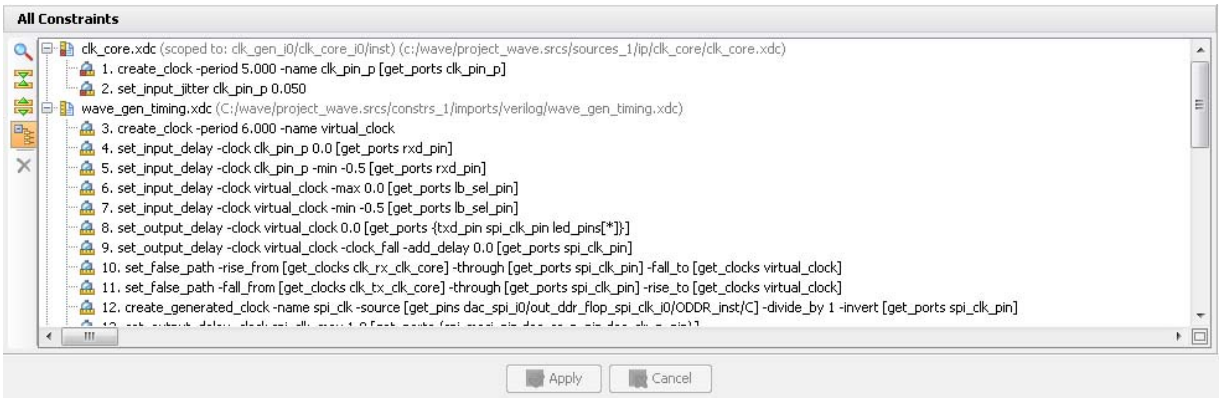

Figure 2-16: **Timing Constraints All Constraints List (Example One)**

You can expand and collapse the constraints by the associated source file, or completely by clicking the two corresponding button on the left side of the panel.

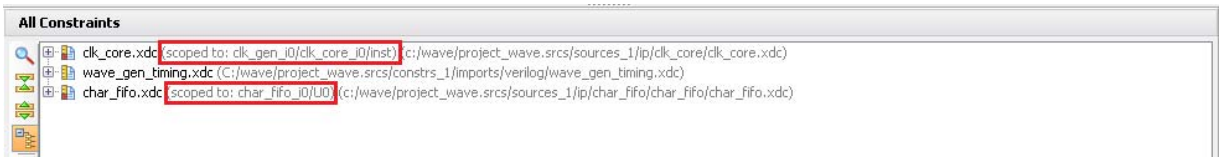

Figure 2-17: **Timing Constraints All Constraints List (Example Two)**

IMPORTANT: *The collapsed view provides a compact overview of which constraints file are loaded in memory, and where the scoping mechanism is used. The same information is available through the* ***report_compile_order -constraints*** *command.*

De-select the **Group by Source** icon  , to switch the view to a table in which the source constraint file and the scoped cell information appears in the two right columns.

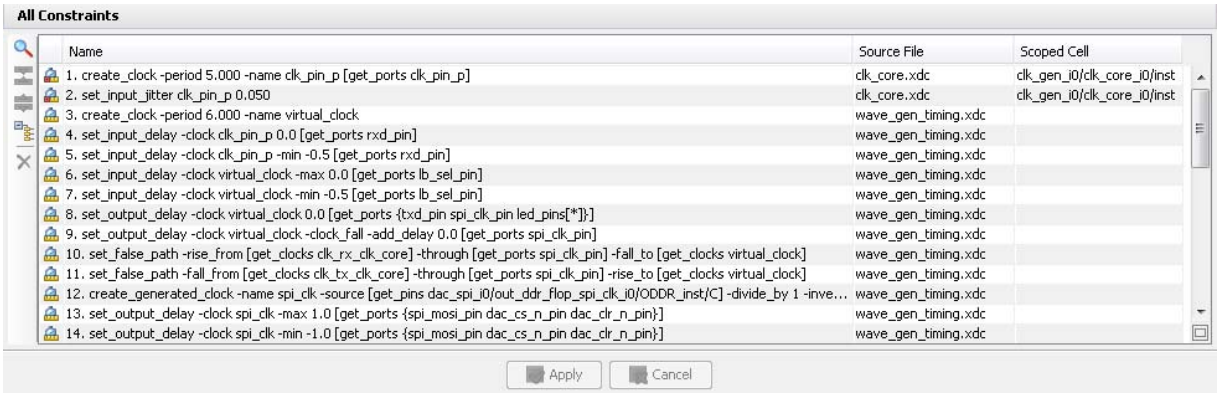

Figure 2-18: **Timing Constraints All Constraints List (Example Three)**

- To delete a constraint, select it and click **X**.
- To edit a constraint that is not read-only, use the spreadsheet view. Once your changes have been registered by the tool, you must click the **Apply** button to refresh the constraints in memory.
- To add new constraints, use the dialog boxes as previously described, or type the constraints in the Tcl console. The new constraint appears at the end of the list in a group named `<unsaved_constraints>`.

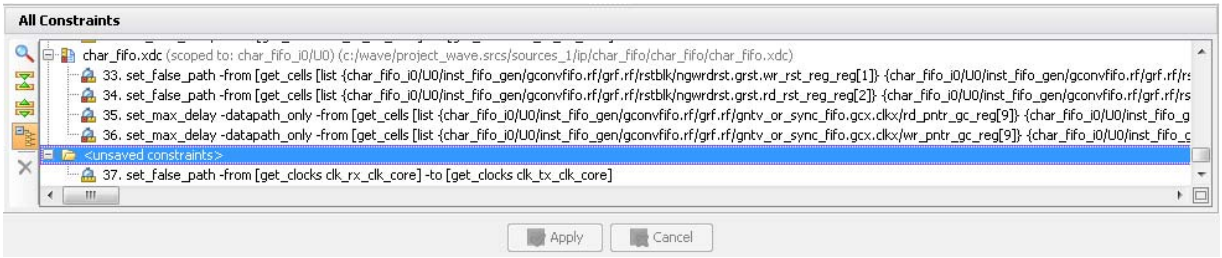

Figure 2-19: **Timing Constraints All Constraints List (Example Four)**

When saving the constraints, the new constraints are saved at the end of the XDC file marked as `target`. If there is no target XDC file in the constraint set associated with the design in memory, or if there is only a Tcl script in the constraint set, you are prompted to specify where to save the constraints.

IMPORTANT: *New and modified constraints cannot be saved back to a Tcl script.*

CAUTION! *Do not enter new constraints in the Tcl Console if any constraints in the Timing Constraints editor have not yet been applied. The final constraints order in the editor can become different from the constraints order in memory. In order to avoid any confusion, you must re-apply all constraints each time you edit an existing constraint.*

Regularly save your constraints. Click **Save**, or select **File > Save Constraints**.

XDC Templates

You can access XDC templates from the Language Templates window in the menu.

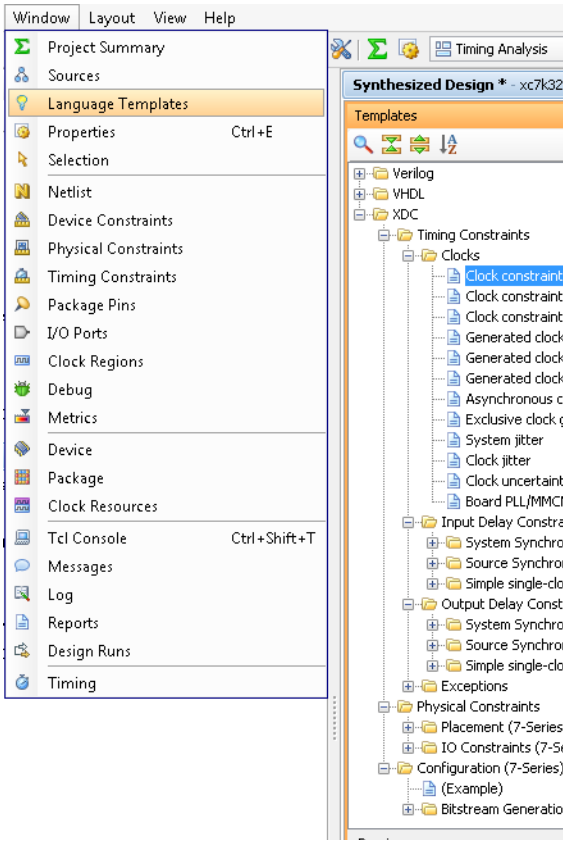

Figure 2-20: **XDC Templates**

XDC Template Contents

The XDC templates include:

- The most common timing constraints such as:
  - Clock definitions
  - Jitter
  - Input/output delay
  - Exceptions
- Physical constraints
- Configuration constraints

Using XDC Templates

To use an XDC template:

1. Select the template you want to use.
2. Copy the text displayed in the Preview window.
3. Paste the text in your XDC file.
4. Replace the generic strings with actual names from your design or with appropriate values.

Advanced XDC Templates

Some advanced templates such as System Synchronous and Source Synchronous I/O delay constraints require you to set some Tcl variables to capture the design requirements. The Tcl variables are used in the actual **set_input_delay** and **set_output_delay** constraints.

You must verify that all necessary values have been filled instead of using the default values.

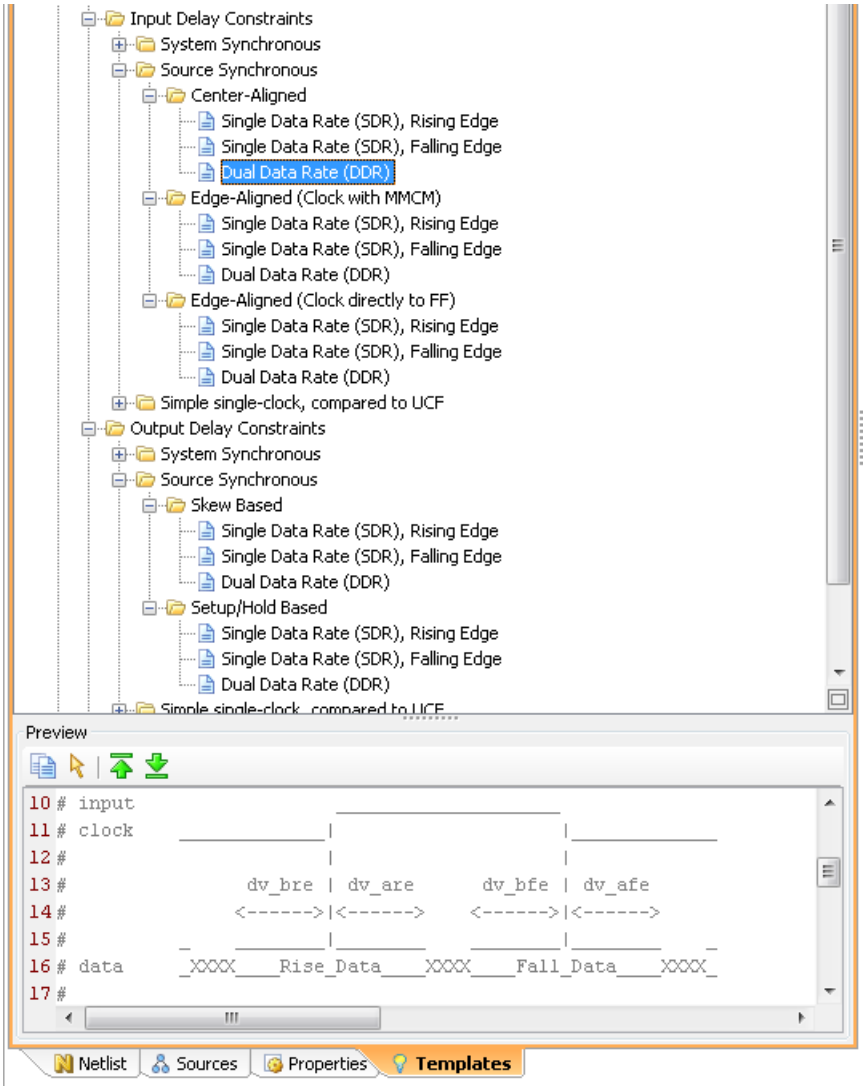

Figure 2-21: **IO Delay Constraint Templates**

Creating Synthesis Constraints

The Vivado IDE synthesis engine transforms the RTL description of your design into a technology mapped netlist. This process happens in several steps, and includes a number of timing-driven optimizations.

Xilinx® FPGA devices include many logic features that can be used in many different ways. Your constraints are needed to guide the synthesis engine towards a solution that meets all the design requirements at the end of implementation.

There are four categories of constraints for the Vivado IDE synthesis:

- RTL Attributes
- Timing Constraints
- Physical and Configuration Constraints
- Elaborated Design Constraints

RTL Attributes

RTL attributes must be written in the RTL files. They usually correspond to directives related to the mapping style of certain part of the logic, as well as preserving certain registers and nets, or controlling the design hierarchy in the final netlist.

For more information, see the *Vivado Design Suite User Guide: Synthesis (UG901)* [Ref 3].

Only the DONT_TOUCH attribute can be set from the XDC file as a property on a netlist object.

DONT_TOUCH Attribute Example

```
set_property DONT_TOUCH true [get_cells fsm_reg]
```

Timing Constraints

Timing constraints must be passed to the synthesis engine by means of one or more XDC files. Only the following constraints related to setup analysis have any real impact on synthesis results:

- create_clock
- create_generated_clock
- set_input_delay
- set_output_delay
- set_clock_groups

- set_false_path
- set_max_delay
- set_multicycle_path

Physical and Configuration Constraints

Physical and configuration constraints are ignored by the synthesis algorithms.

Elaborated Design Constraints

RECOMMENDED: *When you create the first version of your synthesis XDC, use simple timing constraints to describe the high-level design requirements.*

At this point in the flow, the net delay modeling is still not very accurate. The main goal is to obtain a synthesized netlist which meets timing, or fail by a small amount, before starting implementation. In many cases, you will have to go through several XDC and RTL modification iterations before you can reach this state.

The RTL-based XDC creation iteration is shown in Figure 2-22, Creating Constraints with the Elaborated Design. It is based on the utilization of the Elaborated design to find the object names in your design that you want to constrain for synthesis.

You must use the Tcl Console to validate the syntax of the XDC commands before saving them in the XDC files. With the elaborated design, you can create constraints, query clocks, and query design objects, but you cannot run any timing report command.

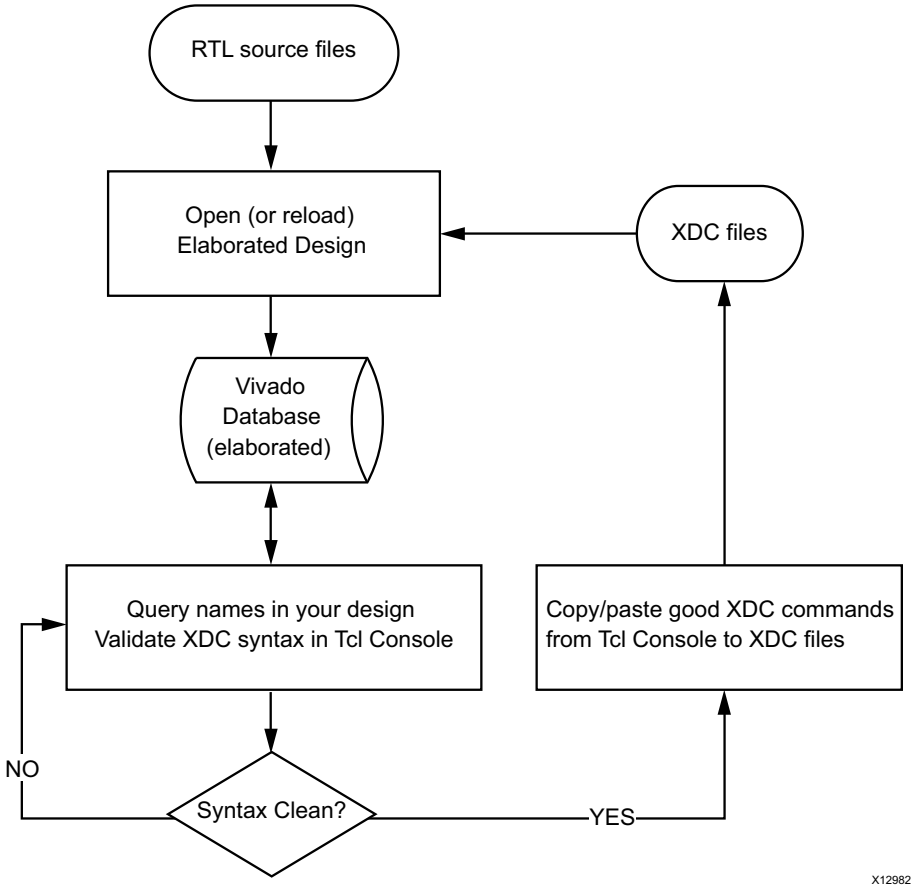

Figure 2-22: **Creating Constraints with the Elaborated Design**

Design objects that are safe to use when writing constraints for synthesis are:

- Top level ports
- Manually instantiated primitives (cells and pins)

Some RTL names are modified or lost during the creation of the elaborated design. Following are the most common cases:

- Single-Bit Register Names
- Multi-Bit Register Names
- Absorbed Registers and Nets
- Hierarchical Names

Single-Bit Register Names

By default, the register name is based on the signal name in the RTL, plus the **_reg** suffix.

For example, for a signal defined as follows in VHDL and Verilog, the instance name generated during the elaboration is **wbDataForInputReg_reg**:

```
VHDL: signal wbDataForInputReg : std_logic;
Verilog: reg wbDataForInputReg;
```

Figure 2-23, Single-Bit Register in Elaborated Design, shows the schematic of the register, and its pins. It is possible to define a constraint on the register instance or its pins.

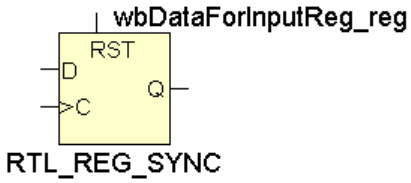

Figure 2-23: **Single-Bit Register in Elaborated Design**

Multi-Bit Register Names

By default, the register name is based on the signal name in the RTL, plus the **_reg** suffix. You can only query and constrain individual bits of the multi-bit register in your XDC commands.

For example, for a signal defined as follows in VHDL and Verilog, the instance names generated during the elaboration are **loadState_reg[0]**, **loadState_reg[1]**, and **loadState_reg[2]**:

```
VHDL: signal loadState: std_logic_vector(2 downto 0);
Verilog: reg [2:0] loadState;
```

Figure 2-24, Multi-Bit Register in Elaborated Design, shows the schematic of the register. The multi-bit register appears as a vector of single-bit registers. The vector is represented in a compact way whenever possible in the schematics. Each individual bit can also be displayed separately.

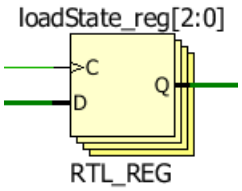

Figure 2-24: **Multi-Bit Register in Elaborated Design**

You can only constrain each register individually or as a group by using the following patterns:

- Register bit **0** only

```
loadState_reg[0]
```

- All register bits

```
loadState_reg[*]
```

IMPORTANT: *You cannot query the multi-bit register, or more generally any multi-bit instance, by using the following pattern:* **loadState_reg[2:0]**

Because the names above also correspond to the names in the post-synthesis netlist, any constraint based on them will most probably work for implementation as well.

Absorbed Registers and Nets

Some registers or nets in the RTL sources can disappear in the elaborated design (or synthesized design) for various reasons. For example, memory block, DSP or shift register inference requires absorbing several design objects into one resource. If you must use these objects to define constraints, try to find other connected registers or nets that you can use instead.

Hierarchical Names

Unless you plan to force Vivado synthesis to keep the complete hierarchy of your design, some or all levels of the hierarchy can be flattened during synthesis. For more information, see the *Vivado Design Suite User Guide: Synthesis (UG901)* [Ref 3].

RECOMMENDED: *Use fully resolved hierarchical names in your synthesis constraints. They are more likely to be matching the final netlist names regardless of the hierarchy transformations.*

For example, consider the following register located in a sub-level of the design.

Elaborated Design Example

```
inst_A/inst_B/control_reg
```

During synthesis (assuming no special optimization is performed on this register), you can get either flat or hierarchical name depending on the tool options or the design structure.

Instance name in a flat netlist:

```
inst_A/inst_B/control_reg     (F)
```

Instance name in a hierarchical netlist:

```
inst_A/inst_B/control_reg     (H)
```

There is no obvious difference because the **/** character is also used to mark flattened hierarchy levels. You will notice the difference when querying the object in memory. The following commands will return the netlist object for F but not H:

```
% get_cells -hierarchical *inst_B/control_reg
% get_cells inst_A*control_reg
```

In order to avoid problems related to hierarchical names, Xilinx recommends that you:

- Use **get_*** commands without the **-hierarchical** option.
- Mark explicitly with the **/** character all the levels of hierarchy as they show in the elaborated design view.

Examples Without Hierarchical Option

This option works for both flat and hierarchical netlists.

```
% get_cells inst_A/inst_B/*_reg
% get_cells inst_*/inst_B/control_reg
```

CAUTION! *(1) Do not attach constraints to hierarchical pins during synthesis for the same reason as explained above for hierarchical cells. (2) Do not attach constraints to nets connecting combinatorial logic operators. They will likely be merged into a LUT and disappear from the netlist.*

RECOMMENDED: *Regularly save your XDC files after editing, and reload the Elaborated design in order to make sure the constraints in memory and the constraints in the XDC files are the same. After running synthesis, load the synthesized design with the same synthesis XDC in memory, and run timing analysis by using the timing summary report.*

For more information, see the *Vivado Design Suite User Guide: Design Analysis and Closure Techniques (UG906)* [Ref 5].

Some pre-synthesis constraints may no longer apply properly because of the transformations performed by synthesis on the design. To resolve these problem:

1. Find the new XDC syntax that applies to the synthesized netlist.
2. Save the constraints in a new XDC file to be used during implementation only.
3. Move the synthesis constraints that can no longer be applied to a separate XDC file that will be used for synthesis only.

Creating Implementation Constraints

Once you have a synthesized netlist, you can load it into memory together with the XDC files or Tcl scripts enabled for implementation. You must review the messages issued by the tool when loading the XDC in order to verify and correct any constraint that cannot be applied.

In some cases, the object names in the synthesized netlist are different from the names in the elaborated design. If this is the case, you must recreate some constraints with the corrected names, and save them in an implementation-only XDC file.

Once the tool can properly load all the XDC files, you can run timing analysis in order to:

- Add missing constraints, such as input and output delay.
- Add timing exceptions, such as false paths, multicycle paths, and min/max delay constraints.
- Identify large violations due to long paths in the design and correct the RTL description.

You can use the same base constraints as during synthesis, and create a second XDC file to store all new constraints specific to implementation. You can choose to save physical and configuration constraints in a separate XDC file.

The netlist-based XDC iteration is shown in Figure 2-25, page 40.

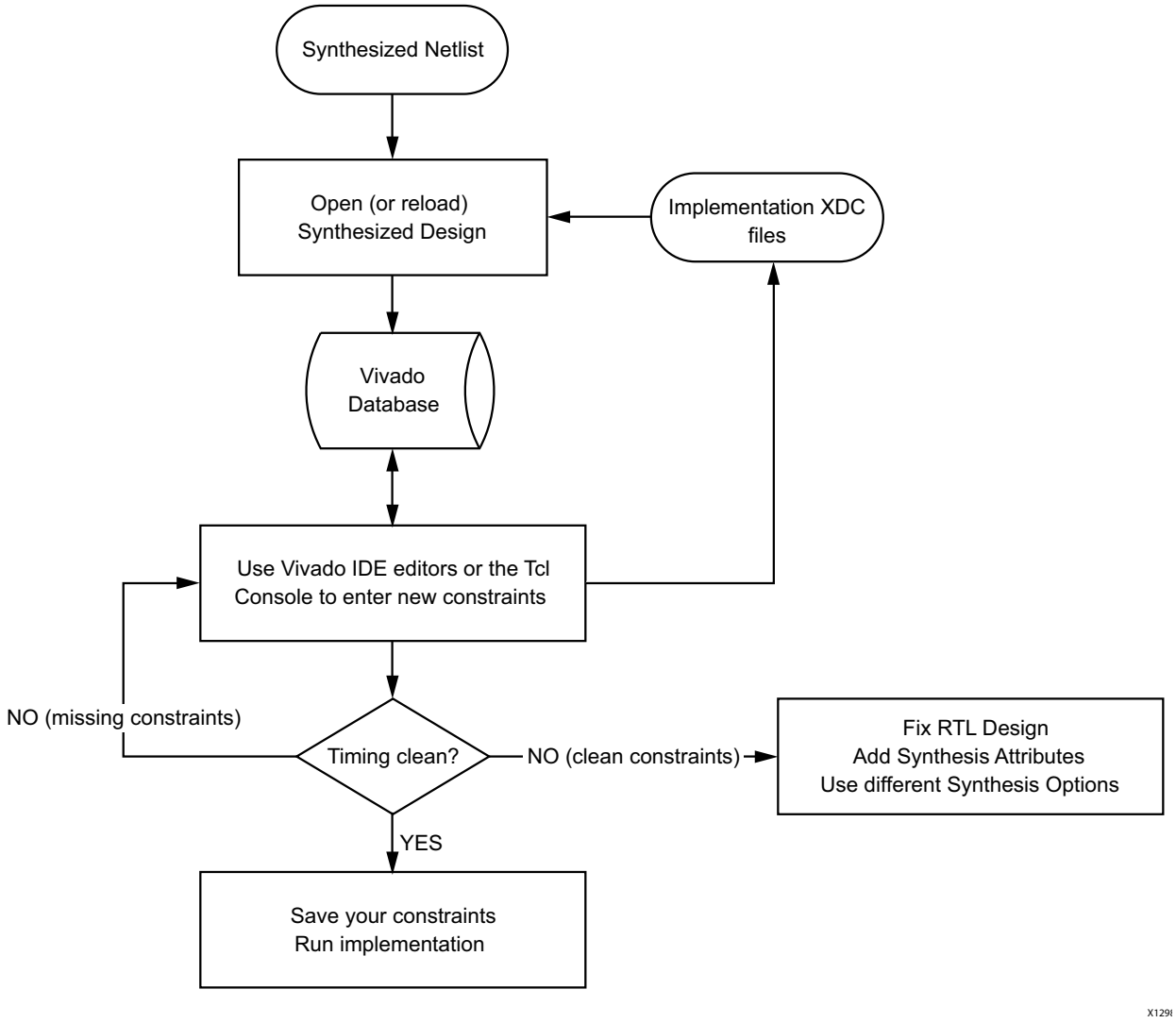

Figure 2-25: **Creating Constraints with the Synthesized Design**

Before proceeding to implementation, you must verify that your design does not include any major timing violation. The place-and-route tools can fix most reasonable timing violations, but they cannot fix fundamental design issues that make timing closure impossible.

RECOMMENDED: *Revisit the RTL to reduce the number of logic levels on the violating paths and to clean up the clock trees in order to use dedicated clock resources and minimize the skew between related clocks. You can also add synthesis attributes and use different synthesis options.*

For more information, see the *Vivado Design Suite User Guide: Synthesis (UG901)* [Ref 3].

Constraints Scoping

The constraints from a particular XDC file can be optionally scoped to a specific module, to specific cells of your design, or both, if needed. This is convenient for creating and applying constraints to a sub-level of your design without having any information about the top-level. It also prevents constraints from being applied outside the target hierarchical cell. By default, all the IPs from the Vivado IP Catalog generated within a Vivado project use this mechanism to load their constraints in memory.

XDC File Scoping Properties

The constraints scoping mechanism is activated by specifying the following properties on the XDC files:

- **SCOPED_TO_REF:** This property takes the name of a module (or entity). The constraints are applied to ALL instances of the specified module (or entity) only,
- **SCOPED_TO_CELLS:** This property takes a list of hierarchical cell names. The constraints are scoped and applied to each hierarchical cell individually,
- **SCOPED_TO_REF + SCOPED_TO_CELLS:** If BOTH these properties are specified, the constraints are applied to each cell of the SCOPED_TO_CELLS list, located inside the module (or entity) specified by SCOPED_TO_REF.

These properties are automatically set by Vivado for IPs added to your RTL project by means of the IP Catalog.

Setting XDC File Scoping Properties Example

Figure 2-26, Setting XDC File Scoping Properties Example, page 42, shows the `uart_tx_i0` cell, an instance of the `uart_tx module`, which includes two hierarchical cells, `uart_tx_ctl_i0` and `uart_baud_gen_tx_i0`.

The project includes an XDC file `uart_tx_ctl.xdc` to constrain the `uart_tx_ctl` module.

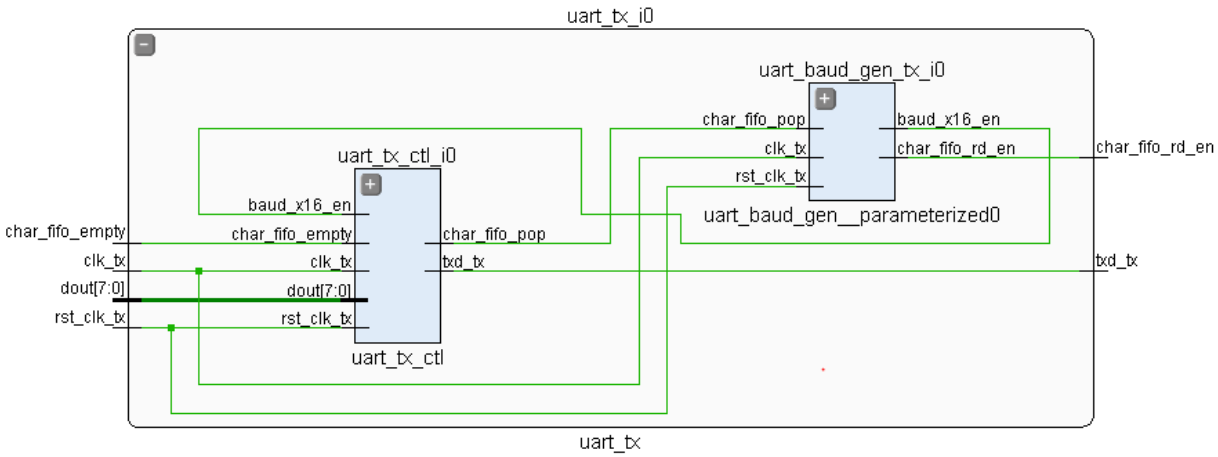

Figure 2-26: **Setting XDC File Scoping Properties Example**

Following are three equivalent Tcl examples to use the scoping properties on `uart_tx_ctl.xdc`. The same values can be set in the Properties windows of the XDC file in the Vivado IDE.

```
# Using the reference module name only:
set_property SCOPED_TO_REF uart_tx_ctl [get_files uart_tx_ctl.xdc]

# Using the cell name only:
set_property SCOPED_TO_CELLS uart_tx_i0/uart_tx_ctl_i0 [get_files uart_tx_ctl.xdc]

# Using both the uart_tx reference module and uart_tx_ctl_i0 instance:
set_property SCOPED_TO_REF uart_tx [get_files uart_tx_ctl.xdc]
set_property SCOPED_TO_CELLS uart_tx_ctl_i0 [get_files uart_tx_ctl.xdc]
```

When using Vivado in a Non-Project mode, you can use the **`read_xdc`** command with the **`-ref`** and **`-cells`** options to achieve the same result:

```
# Using the reference module name only:
read_xdc -ref uart_tx_ctl uart_tx_ctl.xdc
# Using the cell name only:
read_xdc -cells uart_tx_i0/uart_tx_ctl_i0 uart_tx_ctl.xdc
# Using both the uart_tx reference module and uart_tx_ctl_i0 instance
read_xdc -ref uart_tx -cells uart_tx_ctl_i0 uart_tx_ctl.xdc
```

XDC Scoping Mechanism

Except for ports, constraints scoping relies on the **current_instance** mechanism, which is part of the Synopsys SDC standard. When setting the scope to a lower level of the design hierarchy with the **current_instance** command, only the objects included in that level or below can be returned by the object query commands.

The only exceptions are with timing clock objects and netlist ports:

- Timing clocks are defined by **create_clock** or **create_generated_clock**. They are visible throughout the design regardless of the current instance setting. The **get_clocks** command can query clocks that are not present in the current instance, or that propagate beyond the current instance. Xilinx does not recommend defining timing exceptions on clocks when creating scoped constraints unless they are fully contained in the current instance. For a clock to be available for reference in an XDC, the clock must have already been defined. This may require changing the order of the XDC files in the project.
- Top-level ports are returned by the **get_ports** command when the scope is set to a lower level instance with the **current_instance** command. But when reading an XDC file scoped to a lower-level instance with the **read_xdc –ref/-cells** command or when loading a design after setting the SCOPED_TO_REF/SCOPED_TO_CELLS file properties, the **get_ports** command behavior is different:
  - The port names to be used with **get_ports** are the port names of the scoped instance interface, not the top-level port names.
  - If a scoped instance port is directly connected to a top-level port through the hierarchy of the design, the top-level port is returned by the **get_ports** command and the constraint is applied to the top-level port.
  - If there is any leaf cell, including IO and clock buffers, between the scoped instance port and the top-level ports, the **get_ports** command becomes a **get_pins** command and returns the hierarchical scoped instance pin.

The XDC scoping mechanism is used for reading all Vivado IP constraint files. Figure 2-27, IP Port Migration to the Corresponding Top-level Port, and Figure 2-28, IP Port Migration to a Hierarchical Pin, show the two examples of how the **get_ports** commands are treated when reading in the IP-level XDC using this methodology.

In Figure 2-27, IP Port Migration to the Corresponding Top-level Port, the I/O buffer is instantiated inside the IP and the IP interface pin is directly connected to a top-level port (regardless of the hierarchy). When the XDC for the IP is applied, the argument of the **get_ports** command is automatically replaced with the top-level port.

This enables setting physical properties such as a LOC or IOSTANDARD at the IP level and having them be placed on the top-level port where they need to be. This is accomplished without the IP knowing the name of the top-level ports of the design.

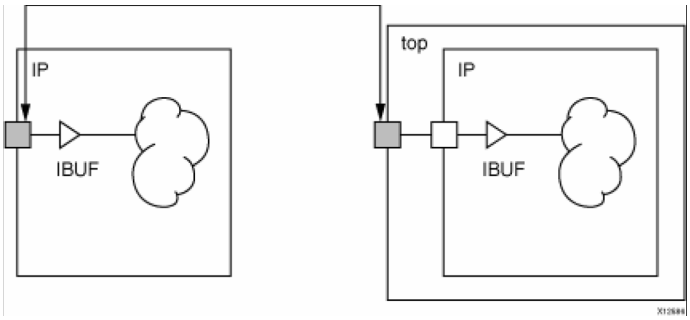

Figure 2-27: **IP Port Migration to the Corresponding Top-level Port**

In Figure 2-28, IP Port Migration to the Corresponding Top-level Port, the IP does not contain an I/O buffer, so the synthesis engine infers one between the IP interface pin and the top-level port. Consequently, the **get_ports** is converted to a **get_pins** of the IP interface pin (for example, a hierarchical pin) when the XDC is applied.

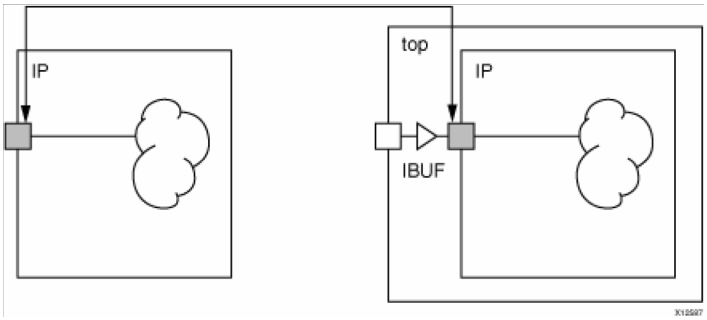

Figure 2-28: **IP Port Migration to a Hierarchical Pin**

This capability is very useful for creating constraints on the interface of an IP or a sub-level module without knowing the names of the top-level design.

If the scoped XDC file includes constraints that can only be applied to top-level ports but the IP instance is not directly connected to top-level ports, the Vivado XDC reader will return errors. For example, the following constraints can only be applied to top-level ports, and not hierarchical pins of your design:

- set_input_delay/set_output_delay
- set_property IOSTANDARD

IP and Sub-module Constraining with XDC

When using Package IP to create IP and use it from the Vivado IP catalog, XDC constraints can also be packaged for inclusion. Any IP in the Vivado Design Suite is plug-and-play, that is, the IP does not require a sample project from which you must cut and paste constraints to complete your top-level design constraints. Instead, the IP can be packaged with an XDC

file that was developed for the IP as if it were a stand alone, top-level design. The Vivado tools take care of reading the constraints appropriately when the IP is instantiated in the project using the IP catalog.

Similarly, you can develop constraints for a sub-module of your design, and use the same scoping mechanism as IPs by setting the SCOPED_TO_REF/SCOPED_TO_CELLS XDC file properties appropriately in a project flow, or use the **read_xdc –ref/-cells** command in a Non-Project flow.

Scoped Queries Guidelines

For this flow to work smoothly, the XDC constraints must be written so that the effects of the constraints stay local to the IP or sub-module instance. The Vivado tools can set the scope of queries to a specific level of the hierarchy as seen previously in Constraints Scoping. When developing constraints for an IP or a sub-level module, you must understand the behavior of the query commands:

- Cell/net/pin objects queries are limited to the scoped instance and its sub-levels:
  - **get_cells/get_nets/get_pins <name pattern>**
  - The NAME property of the object shows the full hierarchical path of the object relative to the top-level and not just the scoped instance. If you use the **-filter** option of the **get_*** commands on the NAME property, you must use the glob string match operator and provide a pattern which starts with a *****. For example:

```
get_nets -hierarchical -filter {NAME =~ *clk}
```

- **get_ports** returns a top-level port or a hierarchical pin
- Netlist helper commands are also scoped:
  - `all_ffs`, `all_latches`, `all_rams`, `all_registers`, `all_dsps`, `all_hsios` return only instances included in the current instance.
- IO helper commands *cannot* be used at all in a scoped XDC:
  - `all_inputs`, `all_outputs`
- Clock commands are *not* scoped and will return all timing clocks of your design.
  - get_clocks, all_clocks
- Top-level and local clock objects can be queried by probing the netlist with **get_clocks -of_objects**.
  - Retrieve a clock entering the current instance by using **get_clocks -of_objects [get_ports <interfacePinName>]**
  - Retrieve a clock automatically generated inside the current instance by using **get_clocks -of_objects [get_pins <instName/outPin>]**, where **instName** is a clock generator instance.

- Querying any object in the design is possible using the **-of_objects** option:
  - Example: `get_pins -leaf -of_objects [get_nets local_net]`
- Queries are supported for top-level ports connected to the current instance interface nets:
  - get_ports -of_objects [get_nets <scoped_instance_net>]
- Queries of IP/sub-module interface pins are not allowed:
  - "`get_pins clk`" returns an error.
- Path tracing commands are also scoped:
  - all_fanin/all_fanout traverses the scoped design and stops at its boundary.
- Use **get_cells/get_pins/get_nets** with the most specific pattern instead of using the **all_registers** command with the **–clock** option to query all the cells connected to a particular clock. The returned list can be very large while only a few objects need to be constrained. This can impact the runtime negatively.

Scoped Timing Constraints Guidelines

To avoid negatively impacting the top-level design, it is important to make sure that timing constraints written for the IP or sub-module do not propagate beyond its boundary, except for clock definition in some cases.

For example, consider the case in which a false path constraint is defined in the IP XDC between two clocks that come into the IP. The IP includes proper circuitry for asynchronous clock boundaries, but perhaps not for the rest of the design. This is a problem if the two clocks are related and must be timed together in the rest of the design in order to have proper hardware functionality.

Also, as discussed in Chapter 7, XDC Precedence, a timing exception defined in the IP XDC file can have higher precedence than top-level constraints and can override them, which is undesired. To avoid this situation, Xilinx recommends that you apply the constraints to netlist objects local to the IP. In the case of a false path between two global clocks, the false path must be applied from a group of startpoint cells inside the IP to another group of endpoint cells inside the IP as well. This technique is referred to as point-to-point exceptions instead of global exceptions.

Recommended constraints of IP/sub-module XDC:

- Create clocks inside the core XDC only if they are:
  - Defined on a port directly connected to an input buffer instantiated inside the IP.
  - Defined on a driver pin located inside the IP (for example, GTX output).
- Query top-level clocks with the **get_clocks –of_objects** command instead of redefining these clocks locally.

- Specify input and output delay only if the port is directly connected to the top-level port and the I/O buffer is instantiated inside the IP.
- Do not define timing exceptions between two clocks that are not bounded to the IP.

Basics of Timing Checks

Before adding timing constraints to your design, you must understand the fundamentals of timing analysis, and the terminology associated with it. This chapter discusses some of key concepts used by the Vivado® Integrated Design Environment (IDE) timing engine.

Terminology

- The *launch edge* is the active edge of the source clock that launches the data.
- The *capture edge* is the active edge on the destination clock that captures the data.
- The *source clock* is also referred to as the *launch clock*.
- The *destination clock* is also referred to as the *capture clock*.
- The *setup requirement* is the relationship between the launch edge and the capture edge that defines the most restrictive setup constraint.
- The *setup relationship* is the setup check verified by the timing analysis tool.
- The *hold requirement* is the relationship between the launch edge and capture edge that defines the most restrictive hold constraint.
- The *hold relationship* is the hold check verified by the timing analysis tool.

Timing Paths

Timing paths are defined by the connectivity between the instances of the design. In digital designs, timing paths are formed by a pair of sequential elements controlled by the same clock, or by two different clocks.

Common Timing Paths

The most common paths in any design are:

- Path from Input Port to Internal Sequential Cell
- Internal Path from Sequential Cell to Sequential Cell
- Path from Internal Sequential Cell to Output Port
- Path from Input Port to Output Port

Path from Input Port to Internal Sequential Cell

In a *path from an input port to a sequential cell*, the data:

- Is launched outside the device by a clock on the board.
- Reaches the device port after a delay called the input delay (SDC definition).
- Propagates through the device internal logic before reaching a sequential cell clocked by the *destination clock*.

Internal Path from Sequential Cell to Sequential Cell

In an *internal path from sequential cell to sequential cell*, the data:

- Is launched inside the device by a sequential cell, which is clocked by the *source clock*.
- Propagates through some internal logic before reaching a sequential cell clocked by the *destination clock*.

Path from Internal Sequential Cell to Output Port

In a *path from an internal sequential cell to an output port* the data:

- Is launched inside the device by a sequential cell, which is clocked by the *source clock*.
- Propagates through some internal logic before reaching the output port.
- Is captured by a clock on the board after an additional delay called the output delay (SDC definition).

Path from Input Port to Output Port

In a *path from an input port to output port*, the data traverses the device without being latched. This type of path is also commonly called an *in-to-out path*. The input and output delays reference clock can be a *virtual clock* or a *design clock*.

Timing Paths Example

Figure 3-1, Timing Paths Example, shows the paths described above. In this example, the design clock CLK0 can be used as the board clock for both DIN and DOUT delay constraints.

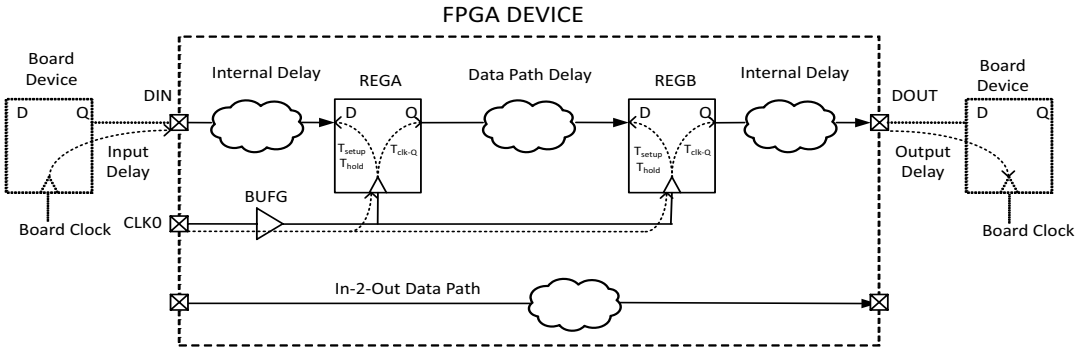

Figure 3-1: **Timing Paths Example**

Timing Path Sections

Each timing path is composed of three sections:

- Source Clock Path
- Data Path
- Destination Clock Path

Source Clock Path

The source clock path is the path followed by the source clock from its source point (typically an input port) to the clock pin of the launching sequential cell. For a timing path starting from an input port, there is no source clock path.

Data Path

The data path is the section of the timing path where the data propagates, between the path startpoint and the path endpoint. The following definitions apply: (1) A path startpoint is a sequential cell clock pin or a data input port; and (2) A path endpoint is a sequential cell data input pin or a data output port.

Destination Clock Path

The destination clock path is the path followed by the destination clock from its source point, typically an input port, to the clock pin of the capturing sequential cell. For a timing

path ending at an output port, there is no destination clock path. Figure 3-2, Typical Timing Path, shows the three sections of a typical timing path.

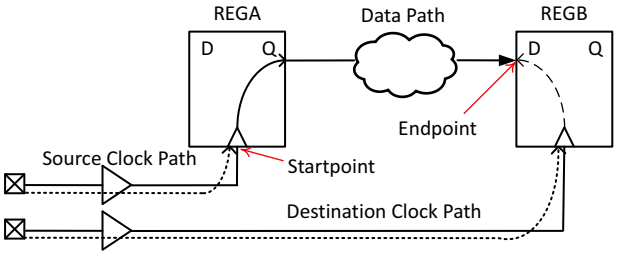

Figure 3-2: **Typical Timing Path**

Launch and Capture Edges

When transferring between sequential cells or ports, the data is:

- Launched by one of the edges of the source clock, which is called the launch edge.
- Captured by one of the edges of the destination clock, which is called the capture edge.

In a typical timing path, the data is transferred between two sequential cells within one clock period. In that case: (1) the launch edge occurs at 0ns; and (2) the capture edge occurs one period after.

The following section explains how the launch and capture edges define the setup and hold relationships used for timing analysis.

Setup and Hold Analysis

The Vivado IDE analyzes and reports slack at the timing path endpoints. The slack is the difference between the data required time and the data arrival timing at the path endpoint. A data is safely transferred between two registers if both the setup and hold relationships are successfully verified on that path. In other words, if both setup and hold slacks are positive, the path is considered functional from a timing point of view.

Setup Check

The setup check is performed only on the most pessimistic setup relationship between two clocks. By default, this corresponds to the smallest positive delta between the launch and capture edges. In order to identify this relationship, and to calculate the corresponding path requirement, the timing engine does the following:

1. Determines the common period between the source and destination clock. The common period is the time after which the source and destination clocks have the same phase alignment as at time 0ns.
2. Determines the smallest positive delta between any two active capture and launch edges found over the common period time. This delta is called the setup path requirement.

IMPORTANT: *If the common period cannot be found over 1000 cycles of both clocks, the worst setup relationship over these 1000 cycles is used for timing analysis. For such case, the two clocks are called unexpandable, or clocks with no common period. The analysis will likely not correspond to the most pessimistic scenario. You must review the paths between these clocks to assess their validity and determine if they can be treated as asynchronous paths instead. For more information, see Clock Groups in Chapter 4.*

Setup Path Requirement Example

Consider a path between two registers which are sensitive to the rising edge of their respective clock. The launch and capture edges of this path are the clock rising edges only. The clocks are defined as follows:

- **clk0** has a period of 6ns
- **clk1** has a period of 4ns

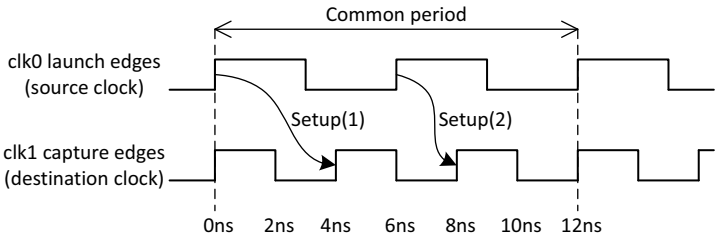

Figure 3-3: **Setup Path Requirement Example**

Figure 3-3 shows that there are two unique source and destination clock edges that qualify for setup analysis: setup(1) and setup(2).

The smallest positive delta from **clk0** to **clk1** is 2 ns, which corresponds to setup(2):

```
Source Clock Launch Edge Time: 0ns + 1 * T(clk0) = 6ns
Destination Clock Capture Edge Time: 0ns + 2 * T(clk1) = 8ns
Setup Path Requirement = capture edge time – launch edge time = 2ns
```

When computing the path requirement, two important considerations are made:

1. The clock edges are ideal, that is, the clock tree insertion delay is not considered yet.
2. The clocks are phase-aligned at time zero by default, unless their waveform definition introduces a phase-shift. Asynchronous clocks do not have a known phase relationship. The timing engine applies the default assumption when analyzing paths between them. For more information on asynchronous clocks, see the following sections.

Data Required Time For Setup Analysis

The data required time for setup analysis is the time before which the data must be stable in order for the destination cell to capture it safely. Its value is based on:

- Destination clock capture edge time
- Destination clock delay
- Source and destination clock uncertainty
- Endpoint setup time

Data Arrival Time For Setup Analysis

The data arrival time for setup analysis is the time it takes for the data to be stable at the path endpoint after being launched by the source clock. Its value is based on:

- Source clock launch edge time
- Source clock delay
- Datapath delay

The datapath delay includes all the cell and net delays, from the startpoint to the endpoint.

In the timing reports, the Vivado IDE considers the setup time as being part of the datapath. Accordingly, the equation for data arrival and required times are:

```
Data Required Time (setup) = capture edge time
                           + destination clock path delay
                           - clock uncertainty
                           - setup time

Data Arrival Time (setup) = launch edge time
                          + source clock path delay
                          + datapath delay
```

The setup slack is the difference between the required time and the arrival time:

```
Slack (setup) = Data Required Time - Data Arrival Time
```

A negative setup slack on a register input data pin means that the register can potentially latch an undesired value, or go to a metastable state.

Hold Check

The hold check (also called hold relationship) is directly connected to the setup relationship. While the setup analysis validates that data can safely be captured under the most pessimistic scenario, the hold relationship ensures that:

- The setup launch edge cannot send a data that can be latched by the active edge before the setup capture edge.
- The next active source clock edge after the setup launch edge cannot send a data that can be latched by the setup capture edge.

During hold analysis, the timing engine reports only the most pessimistic hold relationship between any two clocks. The most pessimistic hold relationship is not always associated with the worst setup relationship. The timing engine must review all possible setup relationships and their corresponding hold relationships to identify the most pessimistic hold relationship.

For each setup relationship, there are two hold relationships that define the following requirements:

- **requirement(a)**: previous capture edge minus launch edge
- **requirement(b)**: capture edge minus next launch edge

Finally, the greatest of all **requirement(a)** and **requirement(b)** values becomes the hold requirement and the corresponding clock edges are used for hold analysis reporting.

Hold Path Requirement Example

Consider the clocks used in Setup Path Requirement Example, page 52. There are only two possible edge combinations for setup analysis:

```
Setup Path Requirement (S1) = 1*T(clk1) - 0*T(clk0) = 4ns
Setup Path Requirement (S2) = 2*T(clk1) - 1*T(clk0) = 2ns
```

The corresponding hold requirements are as follows.

```
For setup S1:
  Hold Path Requirement (H1a) = (1-1)*T(clk1) - 0*T(clk0) = 0ns
  Hold Path Requirement (H1b) = 1*T(clk1) - (0+1)*T(clk0) = -2ns
For setup S2:
  Hold Path Requirement (H2a) = (2-1)*T(clk1) - 1*T(clk0) = -2ns
  Hold Path Requirement (H2b) = 2*T(clk1) - (1+1)*T(clk0) = -4ns
```

The greatest hold requirement is 0ns, which corresponds to the first rising edge of both source and destination clocks.

Hold Path Requirement Example, page 55 shows the setup check edges and their associated hold checks.

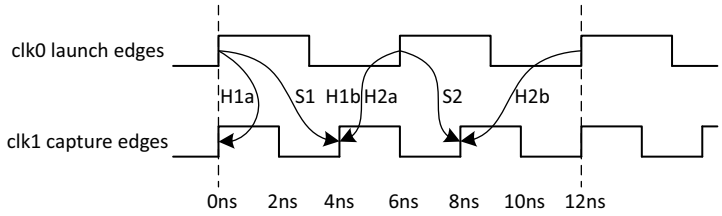

Figure 3-4: **Hold Path Requirement Example**

In this example, the final hold requirement is not derived from the tightest setup requirement. This is because all possible setup edges were considered in order to find the most challenging hold requirement.

As in setup analysis, the data required time and the data arrival time are calculated based on:

- Source clock launch edge time
- Destination clock capture edge time
- Source and destination clock delays
- Clock uncertainty
- Datapath delay
- Endpoint hold time

```
Data Required Time (hold) = destination clock capture edge time
                          + destination clock path delay
                          + clock uncertainty
                          + hold time

Data Arrival Time (hold) = source clock launch edge time
```

```
                                + source clock path delay
                                + datapath delay
```

The hold slack is the difference between the required time and the arrival time:

```
Slack (hold) = Data Arrival Time - Data Required Time
```

A positive hold slack means that the data cannot be captured by the wrong clock edges under the most pessimistic conditions. A negative hold slack means that an undesired data can be captured, or the register can go to a metastable state.

Recovery and Removal Analysis

The recovery and removal timing checks are similar to setup and hold checks, except that they apply to asynchronous pins such as *set* or *clear*.

For a register with an asynchronous reset:

- The recovery time is the minimum time before the next active clock edge after the asynchronous reset signal has toggled to its inactive state in order to safely latch a new data.
- The removal time is the minimum time after an active clock edge before the asynchronous reset signal can be safely toggled to its inactive state.

The following equations describe how the slack is computed for each check.

Recovery Check

The following equations describe how the *recovery* slack is computed :

```
Required Time (recovery) = destination clock edge start time
                                + destination clock path delay
                                - clock uncertainty
                                - recovery time

Arrival Time (recovery) = source clock edge start time
                                + source clock path delay
                                + datapath delay

Slack (recovery) = Required Time - Arrival Time
```

Removal Check

The following equations describe how the *removal* slack is computed:

```
Required Time (removal) = destination clock edge start time
                                + destination clock path delay
                                + clock uncertainty
                                +removal time

Arrival Time (removal) = source clock edge start time
                                + source clock path delay
                                + datapath delay

Slack (removal) = Arrival Time - Required Time
```

A negative recovery slack or removal slack means that the register can go to a metastable state, and propagate an unknown electrical level through the design.

Defining Clocks

About Clocks

In digital designs, clocks represent the time reference for reliably transferring data from register to register. The Vivado® Integrated Design Environment (IDE) timing engine uses the clock characteristics to:

- Compute timing path requirements.
- Report the design timing margin by means of the slack computation.

For more information, see Chapter 3, Basics of Timing Checks.

Clocks must be properly defined in order to get the maximum timing path coverage with the best accuracy. The following characteristics define a clock:

- A clock is defined on the driver pin or port of its tree root, which is called the source point.
- The clock edges are described by the combination of the period and the waveform properties.
- The period is specified in nanoseconds. It corresponds to the time over which the waveform repeats.
- The waveform is the list of rising edge and falling edge absolute times, in nanoseconds, within the clock period. The list must contain an even number of values. The first value always corresponds to the first rising edge. Unless specified otherwise, the duty cycle defaults to 50% and the phase shift to 0ns.

As shown in Figure 4-1, page 59, the clock **Clk0** has a 10ns period, a 50% duty cycle and 0ns phase. The clock **Clk1** has 8ns period, 75% duty cycle and a 2ns phase shift.

```
Clk0: period = 10, waveform = {0 5}
Clk1: period = 8, waveform = {2 8}
```

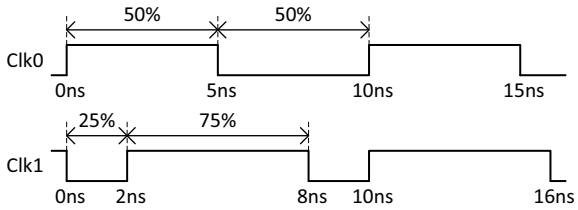

Figure 4-1: **Clock Waveforms Example**

Propagated Clocks

The period and waveform properties represent the ideal characteristics of a clock. When entering the FPGA device and propagating through the clock tree, the clock edges are delayed and become subject to variations induced by noise and hardware behavior. These characteristics are called clock network latency and clock uncertainty.

The clock uncertainty includes:

- Clock jitter
- Phase error
- Any additional uncertainty that you have specified

By default, the Vivado IDE always treats clocks as propagated clocks, that is, non-ideal, in order to provide an accurate slack value which includes clock tree insertion delay and uncertainty.

Dedicated Hardware Resources

The dedicated hardware resources of Xilinx® FPGA devices efficiently support a large number of design clocks. These clocks are usually generated by an external component on the board. They usually enter the device through an input port.

They can also be generated by special primitives called Clock Modifying Blocks, such as:

- MMCM
- PLL
- BUFR

They can also be transformed by regular cells such as LUTs and registers.

The following sections describe how to best define clocks based on where they originate.

Primary Clocks

A primary clock is a board clock that enters the design through:

- An input port, or
- A gigabit transceiver output pin (for example, a recovered clock)

A primary clock can be defined only by the **create_clock** command.

A primary clock must be attached to a netlist object. This netlist object represents the point in the design from which all the clock edges originate and propagate downstream on the clock tree. In other words, the source point of a primary clock defines the time zero used by the Vivado IDE when computing the clock latency and uncertainty used in the slack equation.

IMPORTANT: *The Vivado IDE ignores all clock tree delays coming from cells located upstream from the point at which the primary clock is defined. If you define a primary clock on a pin in the middle of the design, only part of its latency is used for timing analysis. This can be a problem if this clock communicates with other related clocks in the design, since the skew, and consequently the slack, value between the clocks can be inaccurate.*

Primary clocks must be defined first, since other timing constraints often refer to them.

Primary Clocks Examples

As shown in Figure 4-2, the board clock enters the device through the port **sysclk**, then propagates through an input buffer and a clock buffer before reaching the path registers.

- Its period is 10ns.
- Its duty cycle is 50%
- Its phase is not shifted.

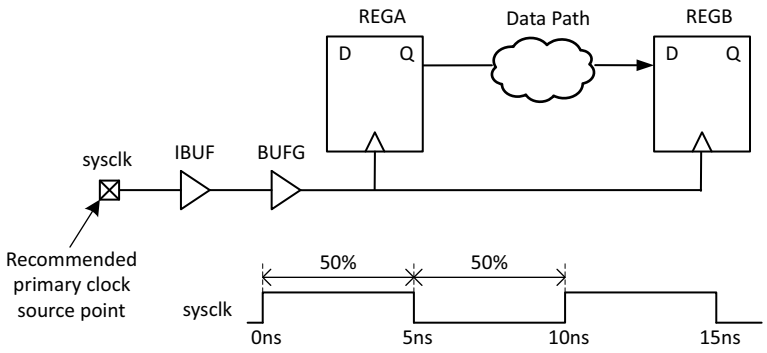

Figure 4-2: **Primary Clock Example**

RECOMMENDED: *Define the board clock on the input port, not on the output of the clock buffer.*

Corresponding XDC:

```
create_clock -period 10 [get_ports sysclk]
```

Similar to **sysclk**, a board clock **devclk** enters the device through the port **ClkIn**.

- Its period is 10ns.
- Its duty cycle is 25%.
- It is phase shifted by 90 degrees.

Corresponding XDC:

```
create_clock -name devclk -period 10 -waveform {2.5 5} [get_ports ClkIn]
```

Figure 4-3 shows a transceiver gt0, which recovers the clock **rxclk** from a high speed link on the board. The clock **rxclk** has a 3.33ns period, a 50% duty cycle and is routed to an MMCM, which generates several compensated clocks for the design.

When defining **rxclk** on the output driver pin of **GT0**, all the generated clocks driven by the MMCM have a common source point, which is **gt0/RXOUTCLK**. The slack computation on paths between them uses the proper clock latency and uncertainty values.

```
create_clock -name rxclk -period 3.33 [get_pins gt0/RXOUTCLK]
```

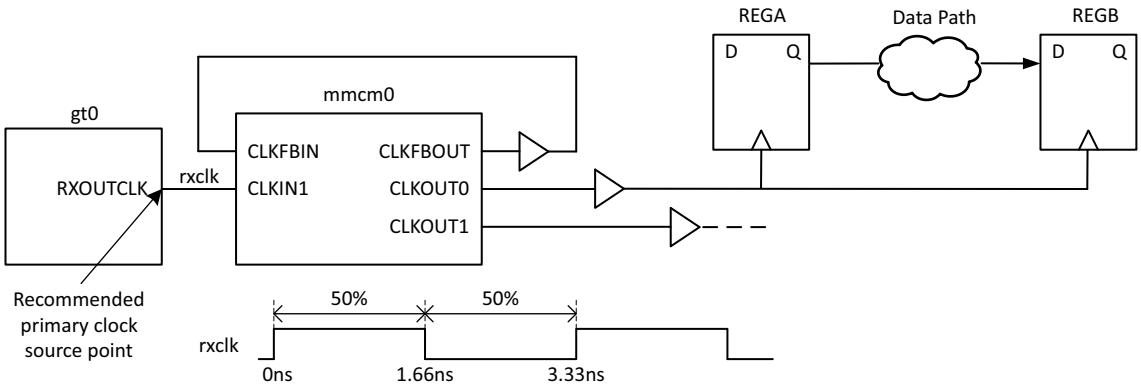

Figure 4-3: **GT Primary Clock Example**

Virtual Clocks

A virtual clock is a clock that is not physically attached to any netlist element in the design.

A virtual clock is defined by means of the **create_clock** command without specifying a source object.

A virtual clock is commonly used to specify input and output delay constraints in one of the following situations:

- The external device I/O reference clock is not one of the design clocks.
- The FPGA I/O paths are related to an internally generated clock that cannot be properly timed against the board clock from which it is derived.

  Note: This happens when the ratio between the two periods is not an integer. which leads to a very tight and unrealistic timing path requirement.
- You want to specify different jitter and latency only for the clock related to the I/O delay constraints without modifying the internal clocks characteristics.

For example, the clock **clk_virt** has a period of 10ns and is not attached to any netlist object. The **[<objects>]** argument is not specified. The **–name** option is mandatory in such cases.

```
create_clock -name clk_virt -period 10
```

The virtual clocks must be defined before being used by the input and output delay constraints.

Generated Clocks

There are two kinds of generated clocks:

- User Defined Generated Clocks
- Automatically Derived Clocks

About Generated Clocks

Generated clocks are driven inside the design by special cells called Clock Modifying Blocks (for example, an MMCM), or by some user logic.

Generated clocks are associated with a master clock. The master clock can be:

- A primary clock
- Another generated clock

Generated clock properties are directly derived from their master clock. Instead of specifying their period or waveform, you must describe how the modifying circuitry transforms the master clock.

The relationship between a master clock and a generated clock can be:

- A simple frequency division
- A simple frequency multiplication
- A combination of a frequency multiplication and division in order to obtain a non-integral ratio (usually done by MMCM and PLL)
- A phase shift or a waveform inversion
- A duty cycle transformation
- A combination of all the above

RECOMMENDED: *Define all primary clocks first. They are needed for defining the generated clocks.*

User Defined Generated Clocks

A user defined generated clock is:

- Defined by the **create_generated_clock** command.
- Attached to a netlist object, preferably the clock tree root pin.

Specify the master clock using the **–source** option. This indicates a pin or port in the design through which the master clock propagates. It is common to use the master clock source point or the input clock pin of generated clock source cell.

IMPORTANT: *The* `-source` *option accepts only a pin or port netlist object. It does not accept clock objects.*

Example One: Simple Division by 2

The primary clock **clkin** has a period of 10ns. It is divided by 2 by the register REGA which drives other registers clock pin. The corresponding generated clock is called **clkdiv2**.

Two equivalent constraints are provided below:

```
create_clock -name clkin -period 10 [get_ports clkin]
```

```
# Option 1: master clock source is the primary clock source point
create_generated_clock -name clkdiv2 -source [get_ports clkin] -divide_by 2 \
  [get_pins REGA/Q]

# Option 2: master clock source is the REGA clock pin
create_generated_clock -name clkdiv2 -source [get_pins REGA/C] -divide_by 2 \
  [get_pins REGA/Q]
```

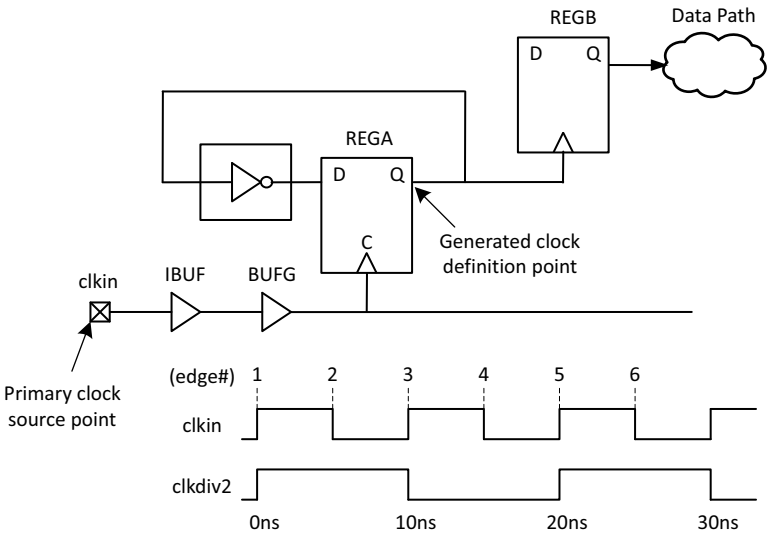

Figure 4-4: **Generated Clock Example One**

Example Two: Division by 2 With the –edges Option

Instead of using the **–divide_by** option, you can use the **–edges** option to directly describe the waveform of the generated clock based on the edges of the master clock. The argument is a list of master clock edge indexes used for defining the position in time of the generated clock edges, starting with the rising clock edge.

The following example is equivalent to the generated clock defined in Example One: Simple Division by 2.

```
# waveform specified with -edges instead of -divide_by
create_generated_clock -name clkdiv2 -source [get_pins REGA/C] -edges {1 3 5} \
  [get_pins REGA/Q]
```

Example Three: Duty Cycle Change and Phase Shift with –edges and –edge_shift Options

Each edge of the generated clock waveform can also be individually shifted by a positive or negative value by using the **–edge_shift** option. Use this option only if a phase shift is needed.

The **–edge_shift** option cannot be used at the same time as any of the following:

- –divide_by
- –multiply_by
- -invert

Consider the master clock **clkin** with a 10ns period and a 50% duty cycle. It reaches the cell **mmcm0** which generates a clock with a 25% duty cycle, shifted by 90 degrees. The generated clock definition refers to the master clock edges 1, 2, and 3. These edges respectively occur at 0ns, 5ns, and 10ns. To obtain the desired waveform, shift the first and the third edges by 2.5ns.

```
create_clock -name clkin -period 10 [get_ports clkin]
create_generated_clock -name clkshift -source [get_pins mmcm0/CLKIN] -edges {1 2 3} \
   -edge_shift {2.5 0 2.5} [get_pins mmcm0/CLKOUT]
# First rising edge:   0ns + 2.5ns = 2.5ns
# Falling edge:        5ns + 0ns   = 5ns
# Second rising edge: 10ns + 2.5ns = 12.5ns
```

Note: The **-edge_shift** values can be positive or negative.

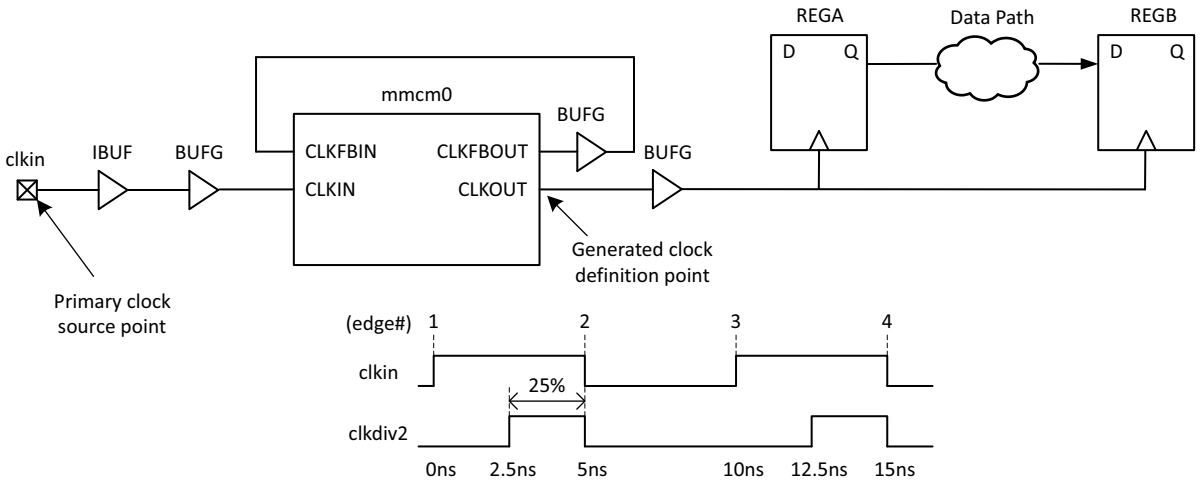

Figure 4-5: **Generated Clock Example Three**

Example Four: Using Both –divide_by and –multiply_by at the Same Time

The Vivado IDE allows you to specify both **–divide_by** and **–multiply_by** at the same time. This is an extension to standard SDC support. This is particularly convenient for manually defining clocks generated by MMCM or PLL instances, although Xilinx recommends that you let the engine create these constraints automatically.

For more information, see Automatically Derived Clocks.

Consider the **mmcm0** cell as in Example Three: Duty Cycle Change and Phase Shift with –edges and –edge_shift Options above, and assume that it multiplies the frequency of the master clock by 4/3. The corresponding generated clock definition is:

```
create_generated_clock -name clk43 -source [get_pins mmcm0/CLKIN] -multiply_by 4 \
   -divide_by 3 [get_pins mmcm0/CLKOUT]
```

If you create a generated clock constraint on the output of an MMCM or PLL, you must verify that the waveform definition matches the configuration of the MMCM or PLL.

Automatically Derived Clocks

Automatically derived clocks are also called auto-generated clocks. Their constraint is automatically created by the Vivado IDE on the output pins of the Clock Modifying Blocks (CMB), provided the associated master clock has already been defined. The CMBs are MMCMx, PLLx or BUFR primitives, including the PHASER_x ones in the MIG IP.

An auto-generated clock is not created if a user-defined clock (primary or generated) is also defined on the same netlist object, that is, on the same definition point (net or pin). The name of the auto-generated clock is based on the name of the net directly connected to the definition point.

Automatically Derived Clock Example

The following automatically derived clock example is a clock generated by an MMCM.

The master clock **clkin** drives the input **CLKIN** of the MMCME2 instance **clkip/mmcm0**. The name of the auto-generated clock is **cpuClk** and its definition point is **clkip/mmcm0/CLKOUT**.

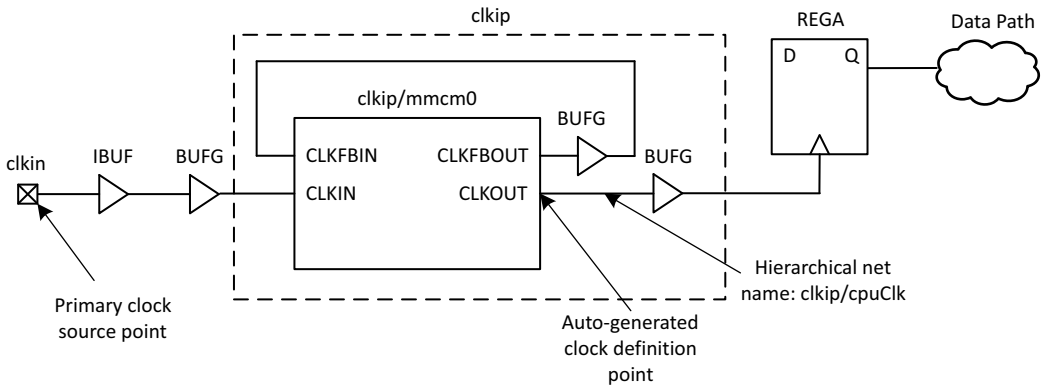

Figure 4-6: **Auto Generated Clock Example**

TIP: *Use the **get_clocks -of_objects <pin/port/net>** command to query an auto-generated clock without knowing its name. This will make your constraint or script independent of the clock name changes.*

Local Net Names

If the CMB instance is located inside the hierarchy of the design, the local net name (that is, the name without its parent cell name) is used for the generated clock name.

For example, for a hierarchical net called **`clkip/cpuClk`**:

- The parent cell name is **`clkip`**.
- The generated clock name is **`cpuClk`**.

Name Conflicts

In case of name conflict between two auto-generated clocks, the Vivado IDE adds unique suffixes to differentiate them, such as:

- usrclk
- usrclk_1
- usrclk_2
- ...

To force the name of the generated clocks:

- Choose unique and relevant net names in the RTL, or
- Use **`create_generated_clock`** to explicitly define the generated clock constraints.

Clock Groups

This section discusses Clock Groups and includes:

About Clock Groups

The Vivado IDE times the paths between all the clocks in your design by default, unless you specify otherwise by using clock groups or false path constraints. The **set_clock_groups** command disables timing analysis between groups of clocks that you identify, and not between the clocks within a same group. Unlike with the **set_false_path** constraint, timing is ignored on both directions between the clocks.

Use the schematic viewer or the Clock Networks Report to visualize the topology of the clock trees, and determine which clocks must not be timed together. You can also use the Clock Interactions Report to review the existing constraints between two clocks, and determine whether they share the same primary clock -- that is, they have a known phase relationship -- or identify the clocks with no common period (unexpandable).

CAUTION! *Ignoring timing analysis between two clocks does not mean that the paths between them will work properly in hardware. In order to prevent metastability, you must verify that these paths have proper re-synchronization circuitry, or asynchronous data transfer protocols.*

Clock Categories

This section discusses the following Clock Categories:

- Synchronous Clocks
- Asynchronous Clocks
- Unexpandable Clocks

Synchronous Clocks

Two clocks are *synchronous* when their relative phase is predictable. This is usually the case when their tree originates from the same root in the netlist, and when they have a common period.

For example, a generated clock and its master clock that have a period ratio of 2 are *synchronous* because they propagate through the same netlist resources up to the generated clock source point, and have a common period of 2 cycles. They can be safely timed together.

Asynchronous Clocks

Two clocks are asynchronous when it is impossible to determine their relative phase.

For example, two clocks generated by separate oscillators on the board and entering the FPGA device by means of different input ports have no known phase relationship. They must therefore be treated as asynchronous. If they were generated by the same oscillator on the board, this would not be true.

In most cases, primary clocks can be treated as asynchronous. When associated with their respective generated clocks, they form asynchronous clock groups.

Unexpandable Clocks

Two clocks are not expandable when the timing engine cannot determine their common period over 1000 cycles. In this case, the worst setup relationship over the 1000 cycles is used during timing analysis, but the timing engine cannot ensure this is the most pessimistic case.

This is typically the case between two clocks with an odd fractional period ratio. For example, consider two clocks, **clk0** and **clk1**, generated by two MMCMs that share the same primary clock:

- **clk0** has a 5.125ns period.
- **clk1** has a 6.666ns period.

Their rising clock edges do not realign within 1000 cycles. The timing engine uses a setup path requirement of 0.01ns on the timing paths between the two clocks. Even if the two clocks have a known phase relationship at their clock tree root, their waveforms do not allow safe timing analysis between them.

As with asynchronous clocks, the slack computation appears normally, but the value cannot be trusted. For this reason, unexpandable clocks are often assimilated to asynchronous clocks. Both clock categories must be treated the same way for constraining and clock-domain crossing circuitry.

Asynchronous Clock Groups

Asynchronous clocks and unexpandable clocks cannot be safely timed. The timing paths between them can be ignored during analysis by using the **set_clock_groups** command.

IMPORTANT: *The **set_clock_groups** command has higher priority over the regular timing exceptions. If you need to constrain and report some paths between asynchronous clocks, you must use the timing exceptions only, and not **set_clock_groups**.*

Asynchronous Clock Groups Examples

- The primary clock **clk0** is defined on an input port and reaches an MMCM which generates the clocks **usrclk** and **itfclk**.
- A second primary clock **clk1** is a recovered clock defined on the output of a GTP instance and reaches a second MMCM which generates the clocks **gtclkrx** and **gtclktx**.

Creating Asynchronous Clock Groups

Use the **–asynchronous** option to create asynchronous groups.

```
set_clock_groups -name async_clk0_clk1 -asynchronous -group {clk0 usrclk itfclk} \
  -group {clk1 gtclkrx gtclktx}
```

If the name of the generated clocks cannot be predicted in advance, use **get_clocks –include_generated_clocks** to dynamically retrieve them. The **–include_generated_clocks** option is an SDC extension.

The previous example can also be written as:

```
set_clock_groups -name async_clk0_clk1 -asynchronous \
  -group [get_clocks -include_generated_clocks clk0] \
  -group [get_clocks -include_generated_clocks clk1]
```

Exclusive Clock Groups

Some designs have several operation modes that require the use of different clocks. The selection between the clocks is usually done with:

- A clock multiplexer such as BUFGMUX and BUFGCTRL, or
- A LUT

RECOMMENDED: *Avoid using LUTs in clock trees as much as possible.*

Because these cells are combinatorial cells, the Vivado IDE propagates all incoming clocks to the output. With the Vivado IDE, several timing clocks can exist on a clock tree at the same time, which is convenient for reporting on all the operation modes at once, but is not possible in hardware.

Such clocks are called *exclusive clocks*. Constrain them as such by using the options of **set_clock_groups**:

- -logically_exclusive, or
- –physically_exclusive

Exclusive Clock Groups Example

An MMCM instance generates **clk0** and **clk1** which are connected to the BUFGMUX instance **clkmux**. The output of **clkmux** drives the design clock tree.

By default, the Vivado IDE analyzes paths between **clk0** and **clk1** even though both clocks share the same clock tree and cannot exist at the same time.

You must enter the following constraint to disable the analysis between the two clocks:

```
set_clock_groups -name exclusive_clk0_clk1 -physically_exclusive \
  -group clk0 -group clk1
```

The following options are equivalent in the context of Xilinx FPGA devices:

- –physically_exclusive
- –logically_exclusive

The physically and logically labels refer to various signal integrity analysis (crosstalk) modes in ASIC technologies which is not needed for Xilinx FPGA devices.

Clock Latency, Jitter, and Uncertainty

In addition to defining the clock waveforms, you must specify predictable and random variations related to the operating conditions and environment.

Clock Latency

After propagating on the board and inside the FPGA device, the clock edges arrive at their destination with a certain delay. This delay is typically represented by:

- The source latency (delay before the clock source point, usually, outside the device)
- The network latency

The delay introduced by the network latency (also called insertion delay) is either:

- Automatically estimated (pre-route design), or
- Accurately computed (post-route design)

Many non-Xilinx timing engines require the SDC command **set_propagated_clock** to trigger the computation of propagation delay along the clock trees. The Vivado tool does not require this command. Instead, it computes the clock propagation delay by default:

- All clocks are considered propagated clocks.
- A generated clock latency includes the insertion delay of its master clock plus its own network latency.

For Xilinx FPGA devices, use the **set_clock_latency** command primarily to specify the clock latency outside the device.

set_clock_latency Example

```
# Minimum source latency value for clock sysClk (for both Slow and Fast corners)
```

```
set_clock_latency -source -early 0.2 [get_clocks sysClk]
# Maximum source latency value for clock sysClk (for both Slow and Fast corners)
set_clock_latency -source -late 0.5 [get_clocks sysClk]
```

Clock Jitter and Clock Uncertainty

For ASIC devices, clock jitter is usually represented with the clock uncertainty characteristic. However, for Xilinx FPGA devices, the jitter properties are predictable. They can be automatically computed by the timing analysis engine, or be specified separately.

Input Jitter

Input jitter is the difference between successive clock edges with respect to variation from the nominal or ideal clock arrival times.

Use the **set_input_jitter** command to specify input jitter for each primary clock individually. You cannot specify the input jitter on a generated clock directly. The Vivado timing engine automatically computes the jitter that a generated clock inherits from its master clock.

- For the case in which the generated clock is driven by a MMCM or a PLL, the input jitter is replaced with a computed discrete jitter.
- For the case the generated clock is created by a combinatorial or sequential cell, the generated clock jitter is the same as its master clock jitter.

System Jitter

System jitter is the overall jitter due to:

- Power supply noise
- Board noise
- Any extra jitter of the system

Use the **set_system_jitter** command to set only one value for the whole design, that is, all the clocks.

Additional Clock Uncertainty

Use the **set_clock_uncertainty** command to define additional clock uncertainty for different corner, delay, or particular clock relationships as needed. This is a convenient way to add extra margin to a portion of the design from a timing perspective.

Constraining I/O Delay

About Constraining I/O Delay

To accurately model the external timing context in your design, you must give timing information for the input and output ports. Because the Vivado® IDE recognizes timing only within the boundaries of the FPGA device, you must use the following commands to specify delay values that exist beyond these boundaries:

- set_input_delay
- set_output_delay

Input Delay

The **set_input_delay** command specifies the input path delay on an input port relative to a clock edge at the interface of the design. When considering the application board, this delay represents the phase difference between:

a. The data propagating from an external chip through the board to an input package pin of the FPGA device, and

b. The relative reference board clock.

Consequently, the input delay value can be positive or negative, depending on the clock and data relative phase at the interface of the device.

Using Input Delay Options

Although the **-clock** option is optional in the SDC standard, it is required by the Vivado IDE. The relative clock can be either a design clock or a virtual clock.

RECOMMENDED: *When using a virtual clock, use the same waveform as the design clock related to the input ports inside the design. This way, the timing path requirement is realistic. Using a virtual clock is convenient for modeling different jitter or source latency scenarios without modifying the design clock.*

The Input Delay command options are:

- Min and Max Input Delay Command Options
- Clock Fall Input Delay Command Option
- Add Delay Input Delay Command Option

Min and Max Input Delay Command Options

The **-min** and **-max** options specify different values for:

- Min delay analysis (hold/removal)
- Max delay analysis (setup/recovery).

If neither is used, the input delay value applies to both min and max.

Clock Fall Input Delay Command Option

The **-clock_fall** option specifies that the input delay constraint applies to timing paths launched by the falling clock edge of the relative clock. Without this option, the Vivado IDE assumes only the rising edge of the relative clock.

Do not confuse the **-clock_fall** option with the **-rise** and **-fall** options. These options refer to the *data* edge and not to the *clock* edge.

Add Delay Input Delay Command Option

The **-add_delay** option must be used if:

- A max (or min) input delay constraint exists, and
- You want to specify a second max (or min) input delay constraint on the same port.

This option is commonly used to constrain an input port relative to more than one clock edge, as, for example, DDR interfaces.

You can apply an input delay constraint only to input or bi-directional ports, excluding clock input ports, which are automatically ignored. You cannot apply an input delay constraint to an internal pin.

Input Delay Example One

This example defines an input delay relative to a previously defined **sysClk** for both **min** and **max** analysis.

```
> create_clock -name sysClk -period 10 [get_ports CLK0]
> set_input_delay -clock sysClk 2 [get_ports DIN]
```

Input Delay Example Two

This example defines an input delay relative to a previously defined virtual clock.

```
> create_clock -name clk_port_virt -period 10
> set_input_delay -clock clk_port_virt 2 [get_ports DIN]
```

Input Delay Example Three

This example defines a different input delay value for min analysis and max analysis relative to **sysClk**.

```
> create_clock -name sysClk -period 10 [get_ports CLK0]
> set_input_delay -clock sysClk -max 4 [get_ports DIN]
> set_input_delay -clock sysClk -min 1 [get_ports DIN]
```

Input Delay Example Four

This example specifies input delay value relative to a DDR clock.

```
> create_clock -name clk_ddr -period 6 [get_ports DDR_CLK_IN]
> set_input_delay -clock clk_ddr -max 2.1 [get_ports DDR_IN]
> set_input_delay -clock clk_ddr -max 1.9 [get_ports DDR_IN] -clock_fall -add_delay
> set_input_delay -clock clk_ddr -min 0.9 [get_ports DDR_IN]
> set_input_delay -clock clk_ddr -min 1.1 [get_ports DDR_IN] -clock_fall -add_delay
```

This example creates constraints from data launched by both rising and falling edges of the **clk_ddr** clock outside the device to the data input of the internal flip-flop that is sensitive to both rising and falling clock edges.

Output Delay

The **set_output_delay** command specifies the output path delay of an output port relative to a clock edge at the interface of the design.

When considering the application board, this delay represents the phase difference between:

a. The data propagating from the output package pin of the FPGA device, through the board to another device, and

b. The relative reference board clock.

The output delay value can be positive or negative, depending on the clock and data relative phase outside the FPGA device.

Using Output Delay Options

Although the **-clock** option is *optional* in the SDC standard, it is *required* by the Vivado IDE.

The relative clock can either be a design clock or a virtual clock.

RECOMMENDED: *When using a virtual clock, use the same waveform as the design clock related to the output ports inside the design. This way, the timing path requirement is realistic. Using a virtual clock is convenient for modeling different jitter or source latency scenarios without modifying the design clock.*

The Output Delay command options are:

- Min and Max Output Delay Command Options
- Clock Fall Output Delay Command Option
- Add Delay Output Delay Command Option

Min and Max Output Delay Command Options

The **-min** and **-max** options specify different values for min delay analysis (hold/removal) and max delay analysis (setup/recovery). If neither is used, the output delay value applies to both min and max.

Clock Fall Output Delay Command Option

The -**clock_fall** option specifies that the output delay constraint applies to timing paths captured by a falling clock edge of the relative clock. Without this option, the Vivado IDE assumes only the rising edge of the relative clock (outside the device) by default.

Do not confuse the -**clock_fall** option with the **-rise** and **-fall** options. These options refer to the *data* edge, not the *clock* edge.

Add Delay Output Delay Command Option

You must use the **-add_delay** option if:

- A max output delay constraint already exists, and
- You want to specify a second max output delay constraint on the same port.

The same is true for a min output delay constraint. This option is commonly used to constrain an output port relative to more than one clock edge, as, for example, rising and falling edges in DDR interfaces, or when the output port is connected to several devices that use different clocks.

IMPORTANT: *You can apply an output delay constraint only to output or bi-directional ports. You cannot apply an output delay constraint to an internal pin.*

Output Delay Example One

This example defines an output delay relative to a previously defined **sysClk** for both **min** and **max** analysis.

```
> create_clock -name sysClk -period 10 [get_ports CLK0]
> set_output_delay -clock sysClk 6 [get_ports DOUT]
```

Output Delay Example Two

This example defines an output delay relative to a previously defined virtual clock.

```
> create_clock -name clk_port_virt -period 10
> set_output_delay -clock clk_port_virt 6 [get_ports DOUT]
```

Output Delay Example Three

This example specifies output delay value relative to a DDR clock with different values for **min** (hold) and **max** (setup) analysis.

```
> create_clock -name clk_ddr -period 6 [get_ports DDR_CLK_IN]
> set_output_delay -clock clk_ddr -max 2.1 [get_ports DDR_OUT]
> set_output_delay -clock clk_ddr -max 1.9 [get_ports DDR_OUT] -clock_fall
-add_delay
> set_output_delay -clock clk_ddr -min 0.9 [get_ports DDR_OUT]
> set_output_delay -clock clk_ddr -min 1.1 [get_ports DDR_OUT] -clock_fall
-add_delay
```

This example creates constraints from data launched by both rising and falling edges of the **clk_ddr** clock outside the device to the data output of the internal flip-flop sensitive to both rising and falling clock edges.

Timing Exceptions

About Timing Exceptions

A timing exception is needed when the logic behaves in a way that is not timed correctly by default. You must use a timing exception command any time you want the timing handled differently (for example, for logic that only has the result captured every other clock cycle by design).

The Vivado® Integrated Design Environment (IDE) supports the timing exceptions commands shown in Table 6-1, Timing Exceptions Commands.

Table 6-1: **Timing Exceptions Commands**

Command	Function
set_multicycle_path	Indicates the number of clock cycles required to propagate data from the start to the end of a path.
set_false_path	Indicates that a logic path in the design should not be analyzed.
set_max_delay set_min_delay	Sets the minimum and maximum path delay value. This overrides the default setup and hold constraints with user specified maximum and minimum delay values.
set_case_analysis	Performs timing analysis using logic constants or logic transitions on ports or pins to restrict the signals propagated through the design.

Multicycle Paths

The Multicycle Path constraint allows you to modify the setup and hold relationships determined by the timer, based on the design clock waveforms. By default, the Xilinx® Vivado™ Design Suite timing engine performs a single-cycle analysis. This analysis can be too restrictive, and can be inappropriate for certain logic paths.

The most common example is the logical path that requires more than one clock cycle for the data to stabilize at the endpoint. If the control circuitry of the path startpoint and endpoint allows it, Xilinx recommends that you use the Multicycle Path constraint to relax the setup requirement.

The hold requirement may still maintain the original relationship, depending on your intent. This helps the timing-driven algorithms to focus on other paths that have tighter requirements and that are challenging. It can also help in reducing runtime.

Setting the Path Multipliers and Clock Edges

The **set_multicycle_path** command is used to modify the path requirement multipliers (for setup analysis, hold analysis, or both) with respect to the source clock or the destination clock.

set_multicycle_path Syntax

The syntax of the **set_multicycle_path** command with the basic options is:

```
set_multicycle_path <path_multiplier> [-setup|-hold] [-start|-end]
  [-from <startpoints>] [-to <endpoints>] [-through <pins|cells|nets>]
```

You must specify the **<path_multiplier>**. The default values used by the timer are:

- **1** for setup analysis (or recovery)
- **0** for hold analysis (or removal)

The hold relationship is tied to the setup relationship. Use the following formula to retrieve the number of hold cycles for most common cases:

```
Hold cycles = <setup path multiplier> - 1 - <hold path multiplier>
```

- By default, the *setup* path multiplier is defined with respect to the *destination* clock. To modify the setup requirement with respect to the source clock, use the **-start** option.
- Similarly, the *hold* path multiplier is defined with respect to the *source* clock. To modify the hold requirement with respect to the destination clock, use the **-end** option.

Note: For a definition of the relevant terms, see Terminology, page 48.

IMPORTANT: *There are two hold relationships for each setup relationship. (1) The first hold relationship ensures that the setup launch edge is not captured by the edge arriving before the active capture edge. (2) The second hold relationship ensures that the edge after the active launch edge is not*

captured by the active capture edge. The timing analysis tool calculates both hold relationships but only the most restrictive is kept during analysis and reporting.

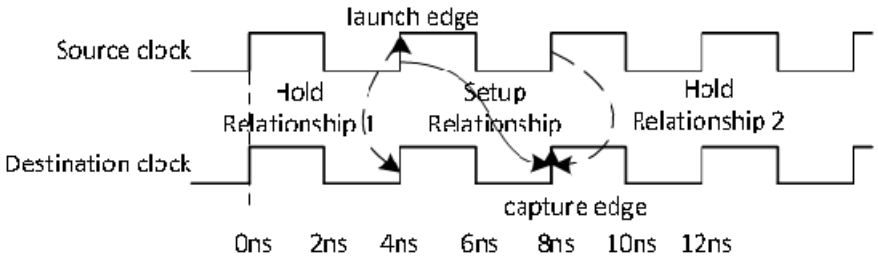

Figure 6-1: **Example of Setup and Hold Relationships for a Path**

IMPORTANT: *The* **-start** *and* **-end** *options have no apparent effect when applying a Multicycle Path constraint on paths clocked by the same clock or clocked by two identical clocks (that is, when the clocks have the same waveform with or without a phase shift).*

Table 6-2, Active Launch and Capture Edges, summarizes how the active launch and capture edges are affected by the **-end** and **-start** options.

Table 6-2: **Active Launch and Capture Edges**

	Source Clock (-start) Moves the launch edge	Destination Clock (-end) Moves the capture edge
Setup	<---- (backward)	----> (forward) (default)
Hold	----> (forward) (default)	<---- (backward)

IMPORTANT: *The* **-setup option** *of the* **set_multicycle_path** *command does not only modify the setup relationship. It also affects the hold relationships which are always tied to the setup relationships. If the hold relationship is to be restored back to its original position, another* **set_multicycle_path** *specification would be needed with* **-hold.**

Note: A Multicycle constraint can be set on a single path, on multiple paths, or even between two clocks.

The following sections cover the common Multicycle Path constraint scenarios and illustrate the impact of the setup and hold multipliers and the **-start** and **-end** options on the timing path requirement.

Multicycles in Single Clock Domain

A Multicycle constraint defined within the same clock domain or between two clocks with the same waveform (no phase-shift) work the same way. See Figure 6-2, Multicycle Constraint in Single Clock Domain.

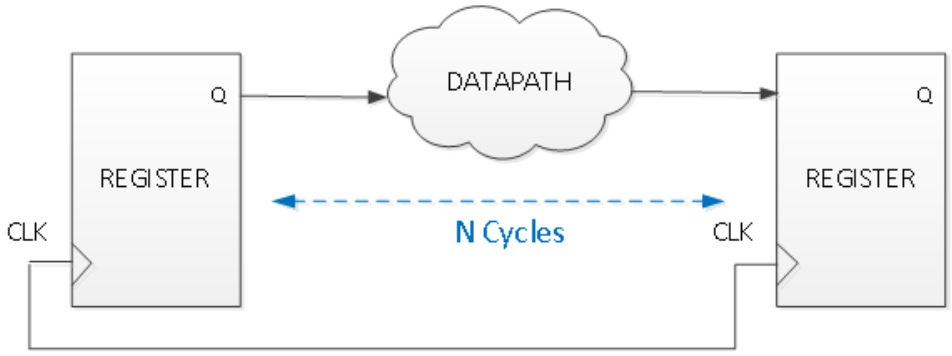

Figure 6-2: **Multicycle Constraint in Single Clock Domain**

The default Setup and Hold relationships that are resolved by the Static Timing Analysis (STA) tool are shown in Figure 6-3, Default Setup and Hold Relationships.

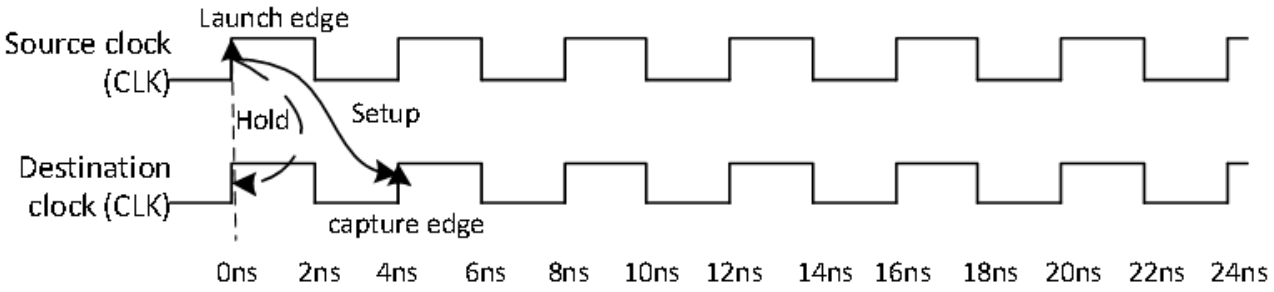

Figure 6-3: **Default Setup and Hold Relationships**

The Setup and Hold timing requirements are:

- Setup check

$$T_{Datapath(max)} < TCLK_{(t=Period)} - T_{Setup}$$

- Hold check:

$$T_{Datapath(min)} > TCLK_{(t=0)} + T_{Hold}$$

Relaxing Setup While Maintaining Hold

Figure 6-4, Registers Enabled Every Two Cycles, shows a path between two flip-flops that are enabled every two cycles. It is safe to define a Multicycle Path constraint on this path to indicate that: (1) the first edge of the destination clock is not active; and (2) only the second edge of the destination clock will capture a new data.

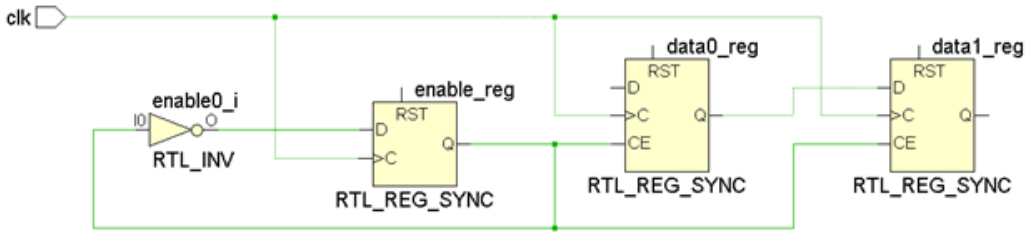

Figure 6-4: **Registers Enabled Every Two Cycles**

The following constraint establishes a new setup relationship:

```
set_multicycle_path 2 -setup -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
```

Chapter 3, Basics of Timing Checks, describes how the hold relationships are derived from the setup relationships. When modifying the setup relationship, the hold relationships are also modified to follow the changes in the setup launch and capture edges.

IMPORTANT: *If the new hold requirements become too aggressive, it will likely result in difficult timing closure. It is the your responsibility to relax the hold requirement assuming it is safe for the design.*

In the same example as Figure 6-4, Registers Enabled Every Two Cycles, after moving the setup check to the second capture edge, the hold check is automatically moved to the first capture edge (that is, one clock period before the setup check).

Figure 6-5, Multicycle Path: Relaxing Setup Only, shows how both the setup and hold relationships have changed when only the setup path multiplier has been defined with the Multicycle Path constraint.

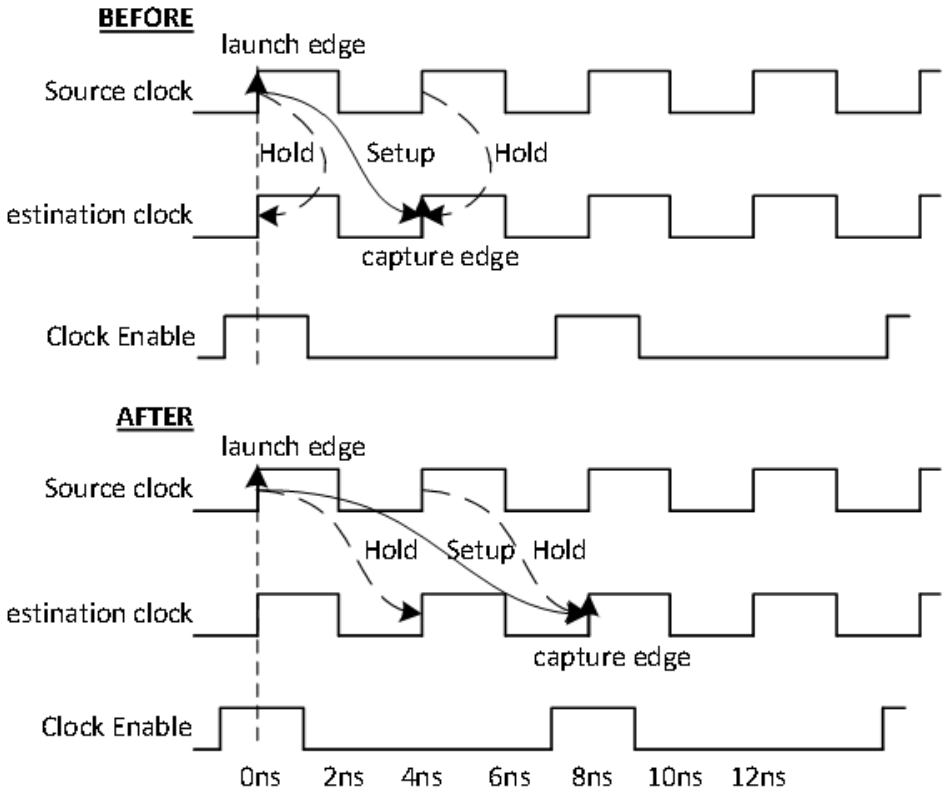

Figure 6-5: **Multicycle Path: Relaxing Setup Only**

Holding the data in the **data0_reg** for one cycle is not needed for this path to be functional due to the clock enable. In this case, Xilinx recommends changing the hold relationship back to the original, which is between the same launch and capture edges. To do so, you must add a second Multicycle Path constraint that modifies the hold check only:

```
set_multicycle_path 1 -hold -end -from [get_pins data0_reg/C] \
    -to [get_pins data1_reg/D]
```

The **-end** option is used with **set_multicycle -hold** command because the edges of the capture clock must be moved backward.

Note: Because the launch and capture clocks have the same waveforms, the **-end** option is optional. Moving the capture edges backward result in the same hold relationship as moving the launch edges forward. To simplify the expressions, the **-end** option has been removed from the next two examples.

Figure 6-6, Multicycle Path: Relaxing Setup and Hold, shows the updated setup and hold relationships after applying both Multicycle Path constraints.

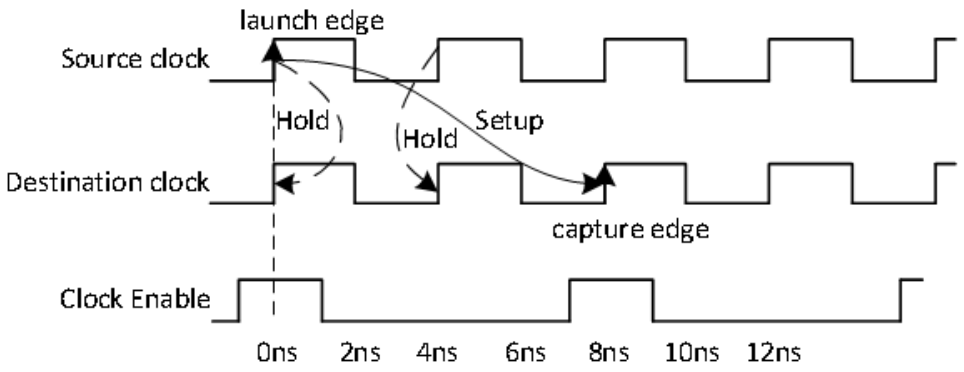

Figure 6-6: **Multicycle Path: Relaxing Setup and Hold**

To summarize this example, the following constraints were necessary to properly define a multicycle path of two (2) between **data0_reg/Q** and **data1_reg/D**:

```
set_multicycle_path 2 -setup -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
set_multicycle_path 1 -hold -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
```

For a multicycle with a setup multiplier of four (4), the constraints are:

```
set_multicycle_path 4 -setup -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
set_multicycle_path 3 -hold -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
```

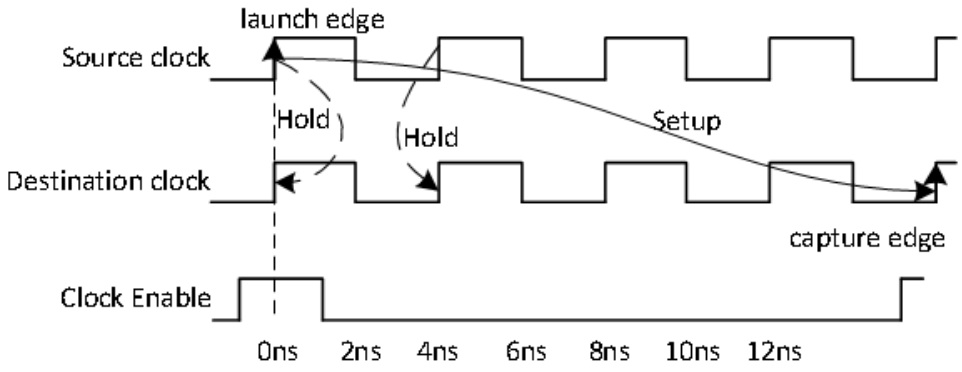

Figure 6-7: **Multicycle Path with Setup Multiplier of Four (4)**

Moving the Setup

The following examples show the results of moving the setup:

- Example One: Setup=5 / Hold Moved Accordingly
- Example Two: Setup=5 / Hold=4

Example One: Setup=5 / Hold Moved Accordingly

Let's assume that the setup path multiplier is set to five (5). Because the hold path multiplier is not specified, the hold relationship is derived from the setup launch and capture edges:

```
set_multicycle_path 5 -setup -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
```

By default, the setup multiplier is applied against the capture clock. This results in moving the edge on the capture clock forward. The setup capture edge comes after five clock periods instead of just one. Because no hold multiplier has been specified, the edge of the capture clock used for the hold check stays the edge that arrives one cycle before the active edge used for the setup check.

The edges on the launch clock do not change for the setup and hold relationships.

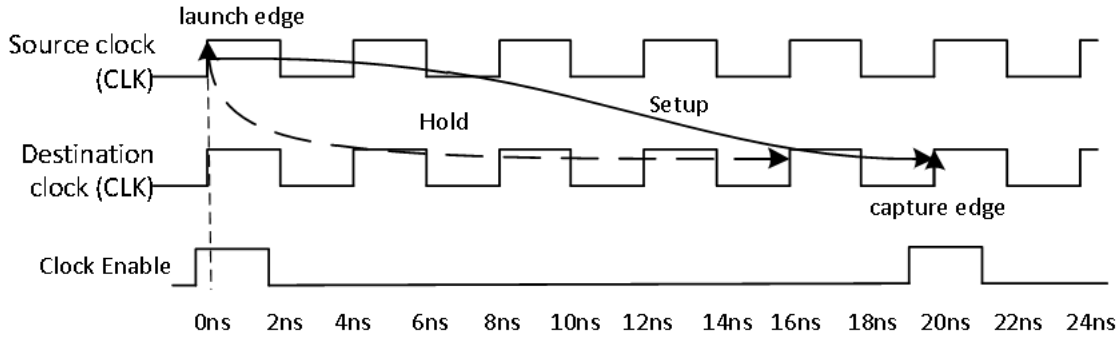

Figure 6-8: **Setup=5, Hold Moved Accordingly**

With a four-cycle hold requirement, the timing-driven implementation tools usually have to insert a large amount of delay in the datapath in order to meet hold timing in both Slow and Fast timing corners. This results in unnecessary area and power consumption. For this reason, it is important to relax the hold requirement when possible.

In this example design, the clock enable signal provides the safety to not have to hold the data in the **data0_reg** for four cycles without risking metastability. Example Two: Setup=5 / Hold=4 describes how the hold requirement can be relaxed.

Example Two: Setup=5 / Hold=4

This example assumes that the following are defined:

- A setup multiplier of five (5)
- A hold multiplier of four (4) (that is, 5-1)

This corresponds to a transfer between two sequential cells when a new data is launched and captured every five (5) cycles.

```
set_multicycle_path 5 -setup -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
set_multicycle_path 4 -hold -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
```

By default, the setup multiplier is applied against the destination clock, which in this case results in moving the capture edge forward to the fifth cycle instead of the first cycle. Accordingly, by default, the hold check follows the setup check.

On specifying the second command, the hold multiplier is applied against the source clock, which in this case results in moving the launch edge forward to the fourth cycle.

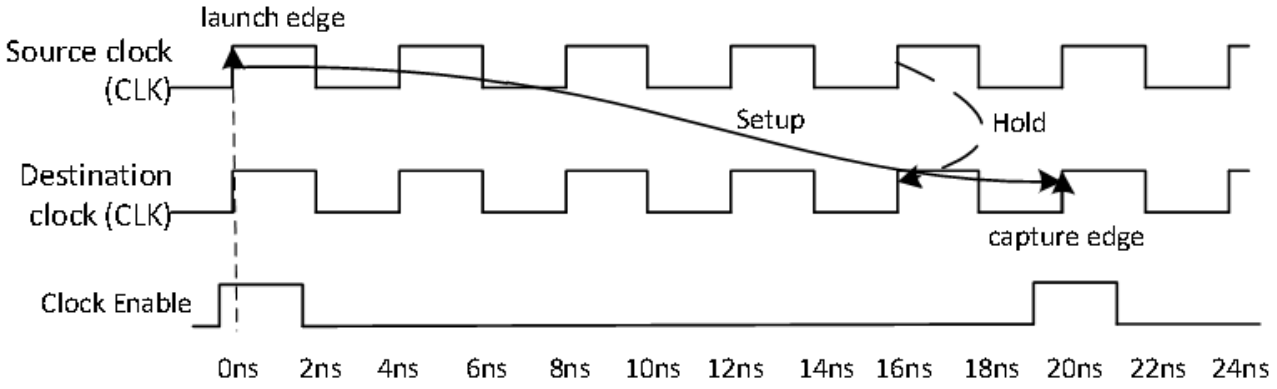

Figure 6-9: **Setup=5, Hold=4**

Because both source and destination clocks have the same waveforms, and are phase-aligned, Figure 6-9, Setup=5, Hold=4, is equivalent to See Figure 6-10, Setup=5, Hold=4.

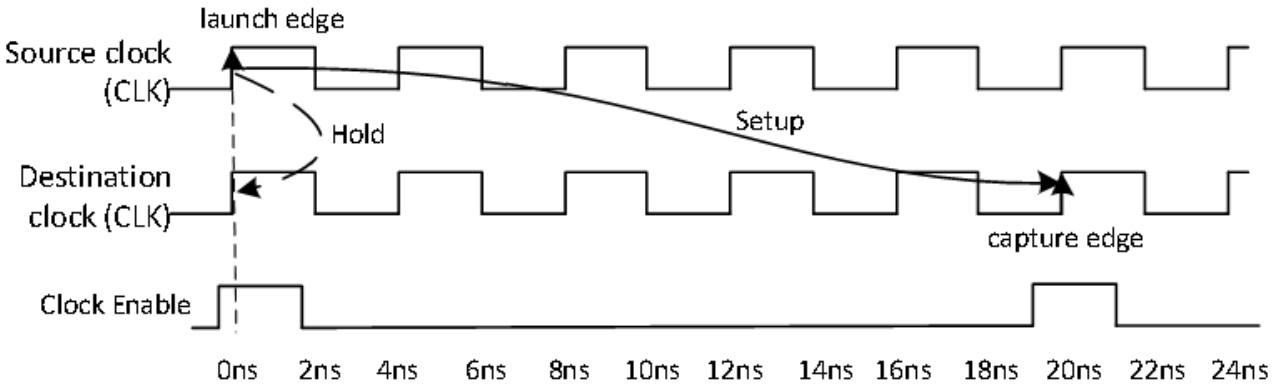

Figure 6-10: **Setup=5, Hold=4**

IMPORTANT: *In general, within a clock domain or between two clocks with the same waveform, when a setup multiplier of **N** is defined, define a hold multiplier of **N-1** (most common case) as shown below:*

```
set_multicycle_path N -setup -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
set_multicycle_path N-1 -hold -from [get_pins data0_reg/C] -to [get_pins data1_reg/D]
```

Multicycle Paths and Clock Phase-Shift

Sometimes a timing constraint must be defined between two clock domains that have: (1) the same clock period; but (2) a phase-shift between the two clocks. In those cases, it is critical to understand the default setup and hold relationships used by the timing engine. If

not carefully adjusted, the phase-shift between two clocks might result in over constraining the logic between the two clock domains.

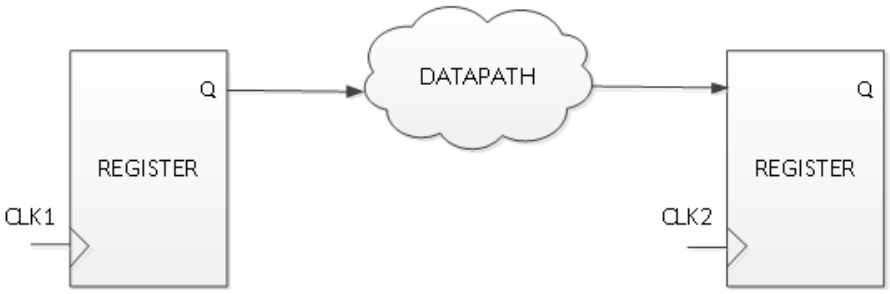

Figure 6-11: **Multicycle Paths and Clock Phase-Shift**

For example, assume that: (1) the two clocks **CLK1** and **CLK2** have the same waveform; and (2) **CLK2** is shifted by +0.3ns.

The setup relationship is calculated by the timing engine by: (1) looking at all the edges on both waveforms; and (2) selecting the two edges on the launch and capture clocks that result in the stricter constraint.

Because of the clocks phase-shift, the setup and hold relationships used by the timing engine might not be those expected. See Figure 6-12, Default Scenario of Phase-Shift Without Multicycle Path.

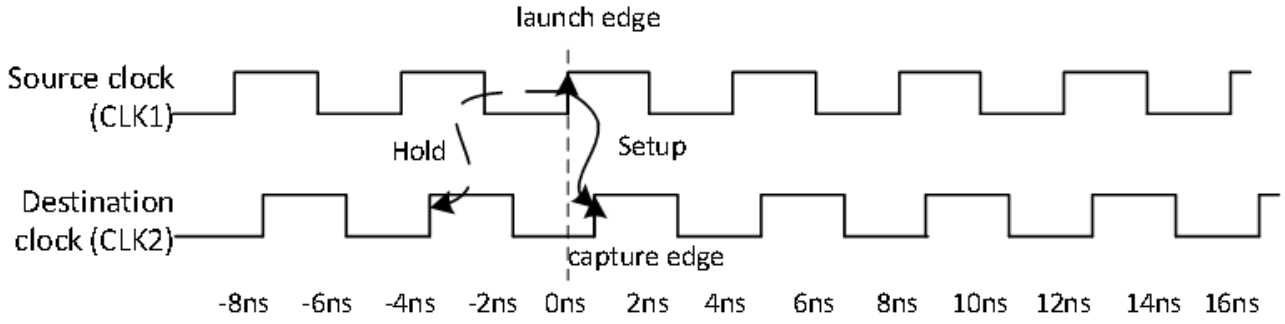

Figure 6-12: **Default Scenario of Phase-Shift Without Multicycle Path**

In this example, the setup constraint due to the phase-shift is 0.3ns. This makes it almost impossible to achieve timing closure. On the other hand, the hold check is -3.7ns, which is too lenient.

The setup and hold edges must be adjusted to match your intent. This is done by adding a Multicycle constraint with a setup multiplier of two (2):

```
set_multicycle_path 2 -setup -from [get_clocks CLK1] -to [get_clocks CLK2]
```

This results in moving the capture edge for the setup requirement forward by one cycle. The default edge for the hold is derived from the setup requirement. It does not need to be specified.

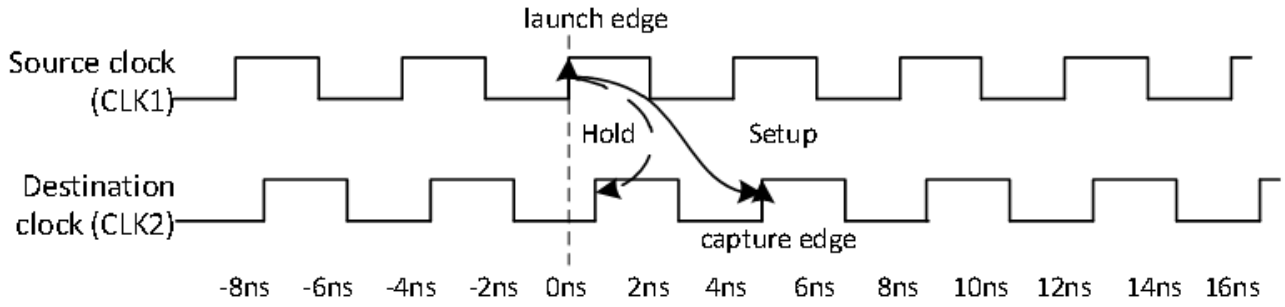

Figure 6-13: **Default Scenario of Positive Phase-Shift: Setup 2 (*-end)*, Hold Moved Accordingly**

In the case of negative phase-shift (**CLK1** ahead of **CLK2**) between the two clock domains, the launch and capture edges used for the setup and hold checks are similar to those from the previous section (single clock domain, no phase-shift).

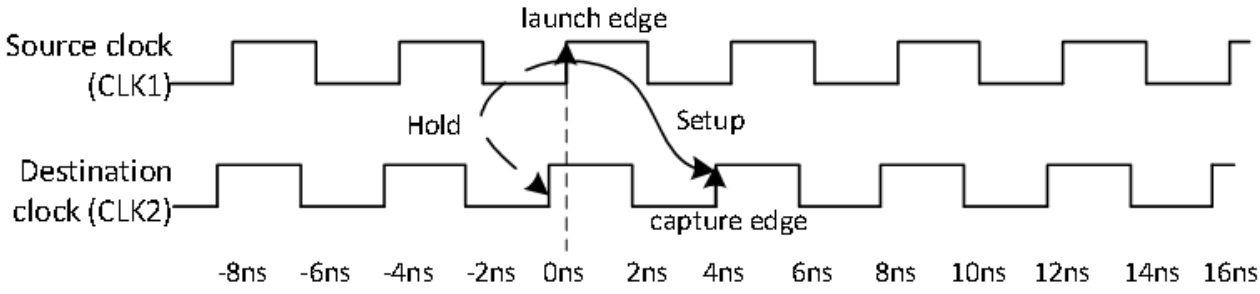

Figure 6-14: **Default Scenario of Negative Phase-Shift**

For a negative phase-shift, a Multicycle constraint is typically not needed to counter-balance the effect of the phase-shift. An exception occurs if the phase-shift is so large that the clock launch or capture edges must be adjusted to keep realistic setup and hold requirements.

Multicycles Between SLOW-to-FAST Clocks

In this scenario, the launch clock **CLK1** is the slow clock; the capture clock **CLK2** is the fast clock. See Figure 6-15, Multicycles Between SLOW-to-FAST Clocks.

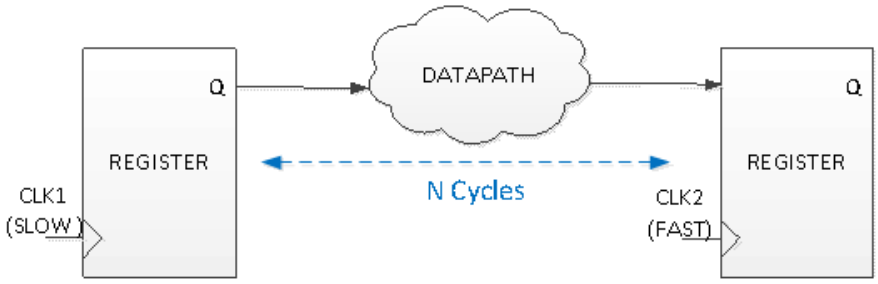

Figure 6-15: **Multicycles Between SLOW-to-FAST Clocks**

For example, assume that: (1) **CLK2** is three times the frequency of **CLK1**; and (2) a clock enable signal on the receiving registers allows a Multicycle constraint to be set between both clocks. See Figure 6-16, Multicycles Between SLOW-to-FAST Clocks.

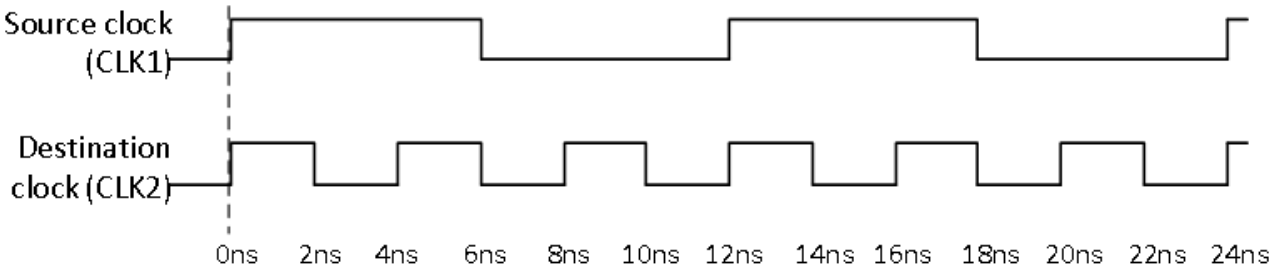

Figure 6-16: **Multicycles Between SLOW-to-FAST Clocks**

The setup and hold relationships that are resolved by the STA tool when no multicycle is applied are shown in Figure 6-17, Default Setup and Hold Relationships.

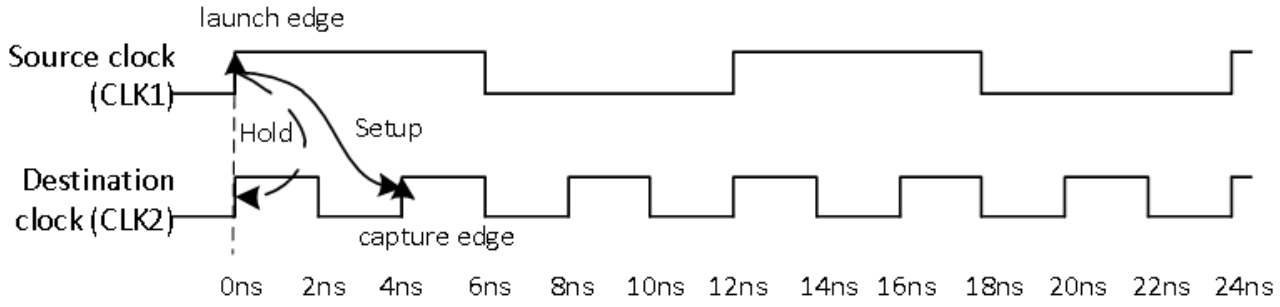

Figure 6-17: **Default Setup and Hold Relationships**

Example One: Setup=3 / Hold Moved Accordingly

For example, assume that only a setup multiplier of three (3) is defined.

```
set_multicycle_path 3 -setup -from [get_clocks CLK1] -to [get_clocks CLK2]
```

The consequence of the setup multiplier is to move the edge of the capture clock used for setup check forward by two (2) cycles (that is, 3-1 cycles). Because no hold multiplier has been specified, the hold relationship is derived by the tool from the setup launch and capture edges. The launch clock active edge is not modified by the Multicycle constraint.

The setup and hold relationships after the multicycle are shown in Figure 6-18, Setup=3, Hold Moved Accordingly.

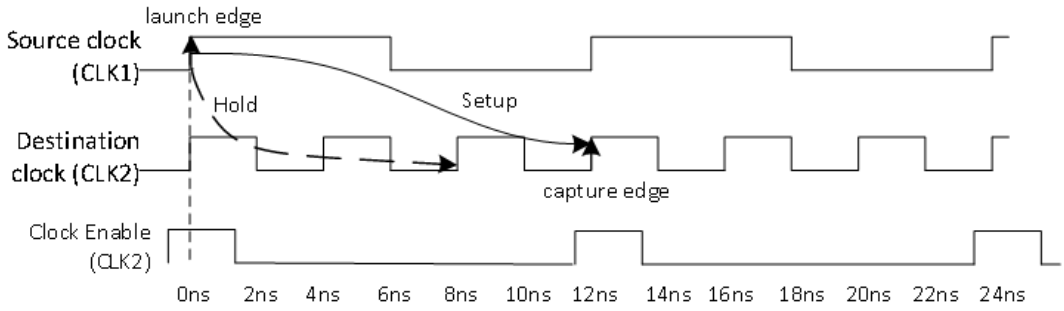

Figure 6-18: **Setup=3, Hold Moved Accordingly**

There is no need to hold the data in the launch registers for one cycle of **CLK2** for this path to be functional. Doing so adds unnecessary logic, which increases area and consumes power.

Because the receiving registers have a clock enable signal, it is safe to relax the hold requirement without risks of metastability.

Example Two: Setup=3 / Hold=2 (-end)

To relax the hold multiplier for the previous example, the capture clock edge for the hold relationship must be moved backward by two (2) clock cycles. This is done by specifying the **-end** option with the **set_multicycle_path -hold** command:

```
set_multicycle_path 3 -setup -from [get_clocks CLK1] -to [get_clocks CLK2]
set_multicycle_path 2 -hold -end -from [get_clocks CLK1] -to [get_clocks CLK2]
```

TIP: *If* **-end** *is not specified with* **set_multicycle_path -hold**, *then the launch clock edge is instead moved forward. This does not result in the intended hold requirement.*

As in the Example One: Setup=3 / Hold Moved Accordingly, the setup multiplier moves the edge of the capture clock used for setup check forward by two (2) cycles (that is, 3-1 cycles).

The setup and hold relationships after the two Multicycle constraints are shown in Figure 6-19, Setup=3, Hold=2 (-end).

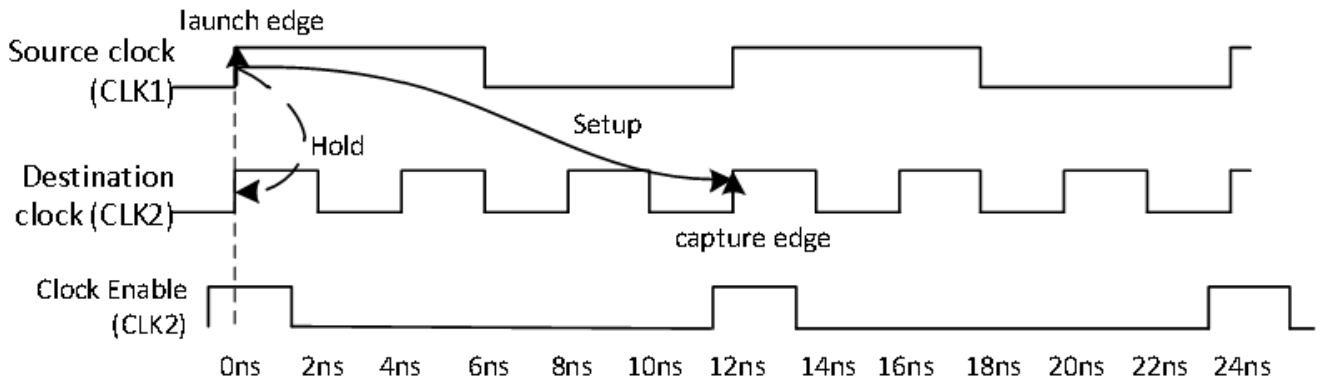

Figure 6-19: **Setup=3, Hold=2 (-end)**

IMPORTANT: *For a SLOW-to-FAST clock domain crossing, when a setup multiplier of* ***N*** *is defined, define a hold multiplier of* ***N-1*** *against the capture clock (****-end)*** *(most common case) as shown in the following code example:*

```
set_multicycle_path N -setup -from [get_clocks CLK1] -to [get_clocks CLK2]
set_multicycle_path N-1 -hold -end -from [get_clocks CLK1] -to [get_clocks CLK2]
```

Multicycles Between FAST-to-SLOW Clocks

In the following scenario, the launch clock **CLK1** is the fast clock and the capture clock **CLK2** is the slow clock. See Figure 6-20, Multicycles Between FAST-to-SLOW Clocks.

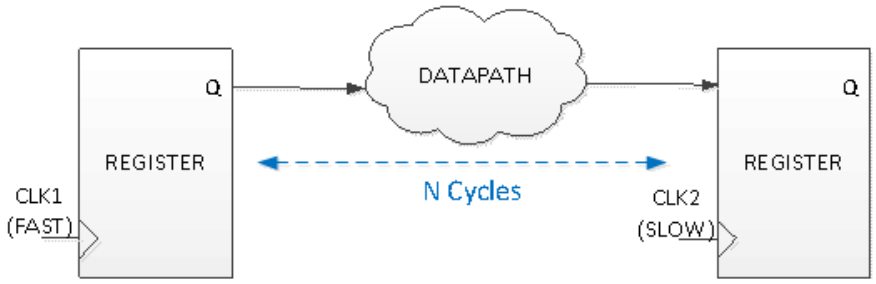

Figure 6-20: **Multicycles Between FAST-to-SLOW Clocks**

In the next example, the launch clock **CLK1** is the fast clock. The capture clock **CLK2** is the slow clock. Assume that **CLK1** is three (3) times the frequency of **CLK2**. See Figure 6-21, Multicycles Between FAST-to-SLOW Clocks .

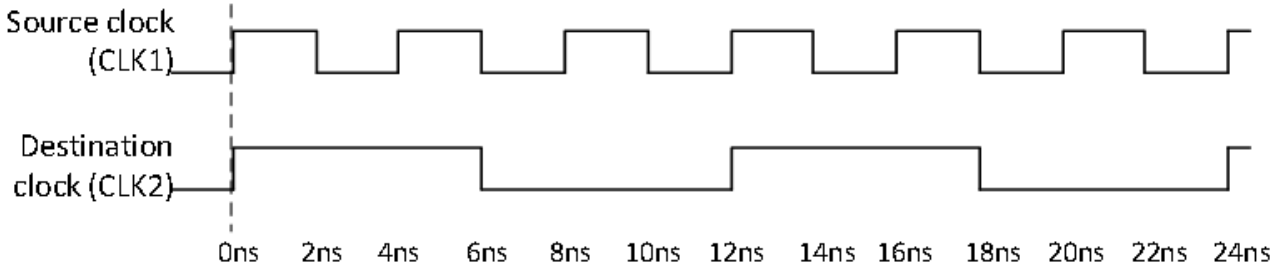

Figure 6-21: **Multicycles Between FAST-to-SLOW Clocks**

The setup and hold relationships that are resolved by the STA tool when no multicycle is applied are shown in Figure 6-22, Default Setup and Hold Relationships.

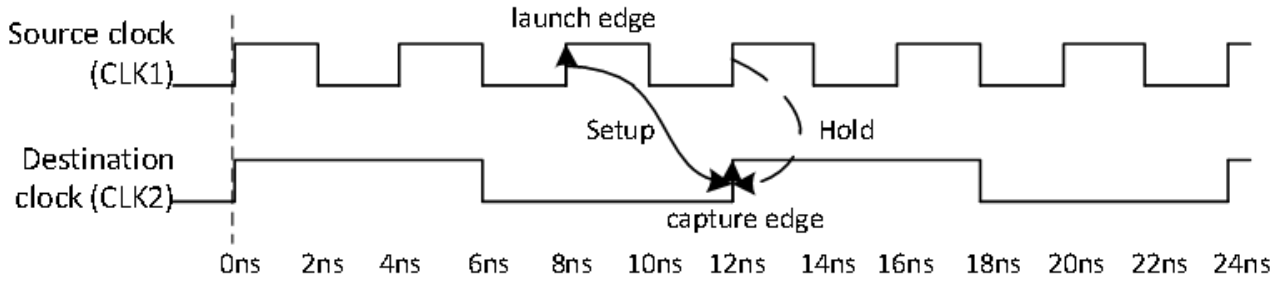

Figure 6-22: **Default Setup and Hold Relationships**

Example: Setup=3 (-start) / Hold=2

Assume that: (1) a setup multiplier of three (3) is defined against the launch clock (**-start**) and; (2) a hold multiplier of one (1) is defined.

```
set_multicycle_path 3 -setup -start -from [get_clocks CLK1] -to [get_clocks CLK2]
set_multicycle_path 2 -hold -from [get_clocks CLK1] -to [get_clocks CLK2]
```

The consequence of the defining the setup multiplier against the launch clock **(-start**) is to move the edge of the launch clock used for setup check backward by two (2) cycles (that is, 3-1 cycles). However, because a hold multiplier is defined against the launch clock (default **-start** option with **-hold**) the edge of the launch clock that is used for the hold relationship is moved forward by two (2) cycles.

For both setup and hold checks, the capture clock edge does not change. See Figure 6-23, Setup=3 (-start), Hold=2.

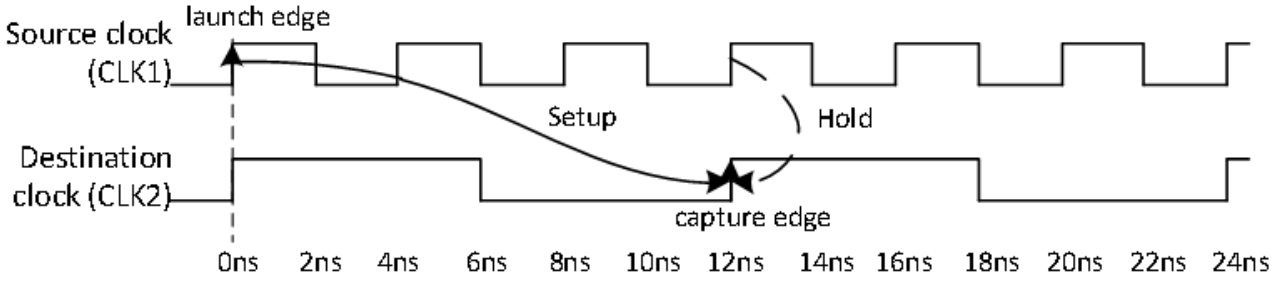

Figure 6-23: **Setup=3 (-start), Hold=2**

IMPORTANT: *For a FAST-to-SLOW clock domain crossing, define a setup multiplier of **N** against the launch clock (**-start)** with a hold multiplier of **N-1** (most common case). See the following example*:

```
set_multicycle_path N -setup -start -from [get_clocks CLK1] -to [get_clocks CLK2]
set_multicycle_path N-1 -hold -from [get_clocks CLK1] -to [get_clocks CLK2]
```

Table 6-3 summarizes the previous results.

Table 6-3: To define a multicycle path with a Setup of N ...

Scenario	Multicycle Constraints
Same clock domain or between synchronous clock domains with same period and no phase-shift	set_multicycle_path N –setup –from CLK1 –to CLK2 set_multicycle_path N-1 –hold –from CLK1 –to CLK2
Between SLOW-to FAST synchronous clock domains	set_multicycle_path N –setup –from CLK1 –to CLK2 set_multicycle_path N-1 –hold -end –from CLK1 –to CLK2
Between FAST-to SLOW synchronous clock domains	set_multicycle_path N –setup -start –from CLK1 –to CLK2 set_multicycle_path N-1 –hold –from CLK1 –to CLK2

Note: The **get_clocks** command has been omitted in Table 6-3 to simplify the expressions.

False Paths

A false path is a path that topologically exists in the design but either: (1) is not functional; or (2) does not need to be timed. Consequently, the false paths should be ignored during timing analysis.

Examples of false paths include:

- Clock domain crossings in which double synchronizer logic has been added
- Registers that might be written once at power up
- Reset or test logic

Figure 6-24, Non-Functional Path Example, shows an example of a non-functional path. Because both multiplexers are driven by the same select signal, the path from **Q-to-D** does not exist, and should be defined as a false path.

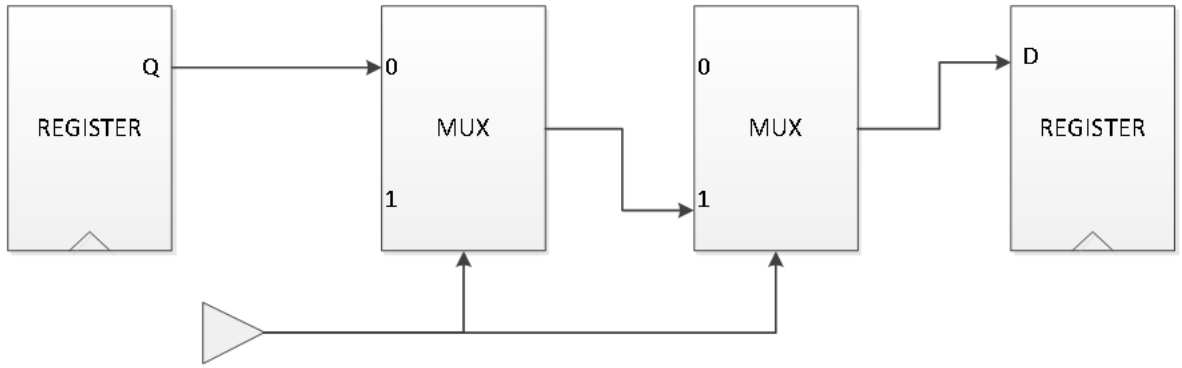

Figure 6-24: **Non-Functional Path Example**

TIP: *Use a Multicycle constraint in place of a False Path constraint when: (1) your intent is only to relax the timing requirements on a synchronous path; but (2) the path still must be timed, verified and optimized.*

Reasons to remove false paths from the timing analysis include:

- **Decrease Runtime**

  When false paths have been removed from the timing analysis, the tool does not need to time or optimize those non-functional paths. Having non-functional paths visible to the timing and optimization engines can result in a large runtime penalty.

- **Enhance Quality of Results (QOR)**

  Removing false paths can greatly enhance the Quality of Results (QOR). The quality of the synthesized, placed, and optimized design is greatly impacted by the timing issues that the tool tries to solve.

  If some non-functional paths have timing violations, the tool might try to fix those paths instead of working on the real functional paths. Not only might the design unnecessarily increase in size (such as logic cloning), but the tool might skip fixing real issues because non-functional paths have larger violations that overshadow other real violations. The best results are always achieved with a realistic set of constraints.

False paths are defined inside the tool with the XDC command **set_false_path**:

```
set_false_path [-setup] [-hold] [-from <node_list>] [-to <node_list>] \
    [-through <node_list>]
```

There are additional options to the command to fine tune the path specification. For detailed information about all supported command line options, see the *Vivado Design Suite Tcl Command Reference Guide (UG835)* [Ref 6].

- The list of nodes for the **-from** option should be a list of valid startpoints. A valid startpoint is a clock, an input (or inout) port or an instance output pin. Multiple elements can be provided.
- The list of nodes for the **-to** option should be a list of valid endpoints. A valid endpoint is a clock, an output (or inout) port or an instance input pin. Multiple elements can be provided.
- The list of nodes for the **-through** option should be a list of valid pins or ports. Multiple elements can be provided.

CAUTION! *Be careful when using* **-through** *option without* **-from** *and* **-to** *because it removes from timing analysis any path going through this list of pins or ports. Be especially careful when the timing constraints are designed for an IP or a sub-block, but then used in a different context or a larger project. Many more paths than expected could be removed when* **-through** *is used alone.*

The order of the **-through** option is important. See the following examples.

For example:

```
set_false_path -through cell1/pin1 -through cell2/pin2
```

is different from:

```
set_false_path -through cell2/pin2 -through cell1/pin1
```

The following example removes the timing paths from the *reset* port to all the registers:

```
set_false_path -from [get_port reset] -to [all_registers]
```

The following example disables the timing paths between two asynchronous clock domains (for example, from clock **CLKA** to clock **CLKB**):

```
set_false_path -from [get_clocks CLKA] -to [get_clocks CLKB]
```

The previous example disables the paths from clock **CLKA** to clock **CLKB**. Paths from clock **CLKB** to clock **CLKA** are not disabled. Accordingly, disabling all the paths between the two clock domains in either direction requires two **set_false_path** commands:

```
set_false_path -from [get_clocks CLKA] -to [get_clocks CLKB]
set_false_path -from [get_clocks CLKB] -to [get_clocks CLKA]
```

IMPORTANT: *Although the previous two* ***set_false_path*** *examples perform what is intended, when two or more clock domains are asynchronous and the paths between those clock domains should be disabled in either direction, Xilinx recommends using the* ***set_clock_groups*** *command instead:*

```
set_clock_groups -group CLKA -group CLKB
```

In the non-functional path example shown in Figure 6-24, Non-Functional Path Example, the false path can be set using the **-through** option instead of using the **-from** or **-to** option. See Figure 6-25, Non-Functional Path Example.

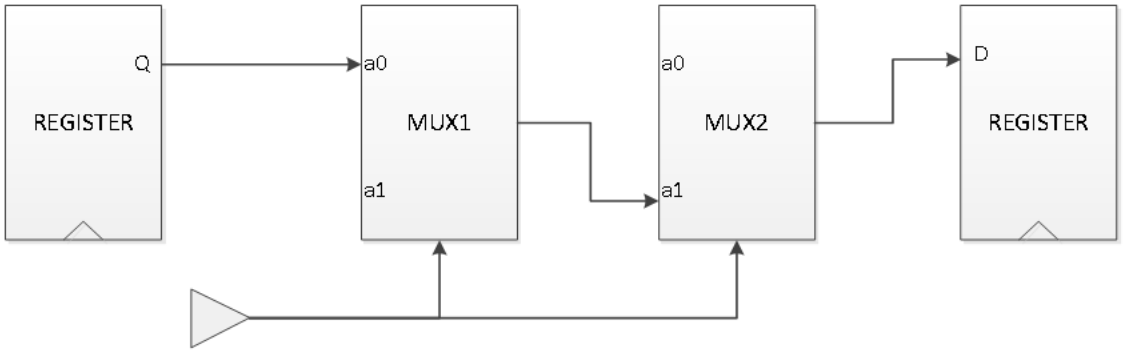

Figure 6-25: **Non-Functional Path Example**

This ensures that all the paths going through the path shown above are selected without needing to find specific patterns for the startpoints and endpoints.

```
set_false_path -through [get_pins MUX1/a0] -through [get_pins MUX2/a1]
```

Note: The order of the **-through** option is important. In the above example , the order ensures that the false paths go through pin **MUX1/a0** first and then pin **MUX2/a1**.

Min/Max Delays

You can override a maximum delay or a minimum delay for a path:

- Use the Maximum Delay constraint to override the default setup (or recovery) requirement on a path.
- Use the Minimum Delay constraint to override the default hold (or removal) requirement.

Setting Maximum Delay and Minimum Delay Constraints

The Maximum Delay constraint and the Minimum Delay constraint are set by two different XDC commands. These commands accept similar options.

Maximum Delay Constraint Syntax

```
set_max_delay <delay> [-datapath_only] [-from <node_list>]
                      [-to <node_list>] [-through <node_list>]
```

Minimum Delay Constraint Syntax

```
set_min_delay <delay> [-from <node_list>]
                      [-to <node_list>] [-through <node_list>]
```

Additional command options are available to fine tune the path specification. For more information about the supported command line options, see the *Vivado Design Suite Tcl Command Reference Guide (UG835)* [Ref 6].

List of Nodes for the -from Option

- The list of nodes for the **-from** option should preferably be a list of valid startpoints. A valid startpoint is a clock, an input (or inout) port, or the clock pin of a sequential element.
- Using a node that is not a valid startpoint results in path segmentation. The path segmentation is covered in the next section.
- Multiple elements can be provided.

List of Nodes for the -to Option

- The list of nodes for the **-to** option should preferably be a list of valid endpoints. A valid endpoint is a clock, an output (or inout) port or the data pin of a sequential cell.
- Using a node that is not a valid endpoint results in path segmentation. For more information, see Path Segmentation, page 101.
- Multiple elements can be provided.

List of Nodes for the -through Option

- The list of nodes for the **-through** option should be a list of valid pins, ports, or nets.
- Multiple elements can be provided.

By default, the timing engine includes the clock skew inside the slack computation.

The **-datapath_only** option can be used to remove the clock skew from the slack computation. The **-datapath_only** option is supported only by the **set_max_delay** command, and requires the **-from** option.

Table 6-4, Information Used for Path Delay Calculation, summarizes the information used for the path delay calculation.

Table 6-4: **Information Used for Path Delay Calculation**

Startpoint	Endpoint	-datapath_only Option Used	Path Delay Calculation
Clock pin of sequential element		No	Clock skew included
Input port with input delay specified		No	Input delay included
	Data pin of sequential element	No	Clock skew and data pin setup time included
	Output port with output delay specified	No	Output delay included
Clock pin of sequential element		Yes	Clock skew **not** included
Input port with input delay specified		Yes	Input delay included
	Data pin of sequential element	Yes	Data pin setup time included but clock skew **not** included
	Output port with output delay specified	Yes	Output delay included

Consequences of Setting Maximum Delay or Minimum Delay Constraints on a Path

Setting a Maximum Delay constraint on a path does not modify the minimum requirement on that path. The hold (or removal) check on that path remains the default.

Similarly, setting a Minimum Delay constraint on a path does not modify the default setup (or recovery) check.

If a path has only, for example, a max delay requirement, the path can be constrained with a combination of **set_max_delay** and **set_false_path** commands. See the following example:

```
set_max_delay 5 -from [get_pins FD1/C] -to [get_pins FD2/D]
set_false_path -hold -from [get_pins FD1/C] -to [get_pins FD2/D]
```

The above example sets a 5ns setup requirement for the path starting on **FD1/C** and ending on **FD2/D**. There is no minimum requirement due to the **set_false_path** command.

Constraining Input or Output Logic

The **set_max_delay** command and the **set_min_delay** command are not typically used to constrain the input or output logic. The input logic between the input ports and the first level of registers is typically constrained with the **set_input_delay** command. This command provides the option to associate a clock with the input ports.

For the same reason, the output logic between the last level of registers and the output ports is typically constrained with the **set_output_delay** command. However, the **set_max_delay** command and the **set_min_delay** command are typically used to constrain pure combinational path between primary input ports and primary output port (in-to-out I/O paths).

Constraining Asynchronous Signals

The **set_max_delay** command and the **set_min_delay** command can also be used to constrain asynchronous signals that: (1) do not have a clock relationship; but which (2) require maximum delays, minimum delays, or both.

For example, timing paths between two asynchronous clock domains can be disabled with the **set_clock_groups** command (recommended) or the **set_false_path** command (not recommended). This assumes that you have properly designed the inter-clock domains with, for instance, a double registers synchronizer or a FIFO. However, you must still ensure that the path delay between the two clock domains is not unnecessarily high. See the following example:

```
set_max_delay <delay> -from <startpoints_source_clock_domain> \
    -to <endpoints_destination_clock_domain>>
```

Path Segmentation

Unlike other XDC constraints, the **set_max_delay** command and the **set_min_delay** command can accept, in the case of **-from** and **-to** options, a list of invalid startpoints or endpoints respectively.

When an invalid startpoint is specified, the timing engine breaks the timing arcs going through the node so that the node does become a valid startpoint.

In the following example, the only valid startpoint is **FD1/C**:

```
set_max_delay 5 -from [get_pins FD1/C]
```

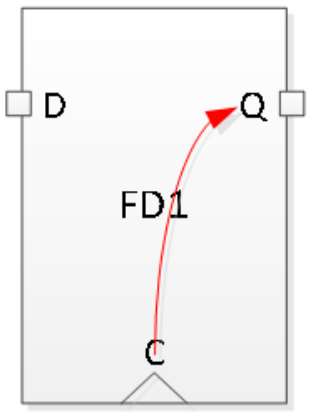

Figure 6-26: **Original Timing Arc**

If the constraint is applied to **FD1/Q**, the timing engine breaks the timing arc **C->Q** to make the pin **Q** a valid startpoint:

```
set_max_delay 5 -from [get_pins FD1/Q]
```

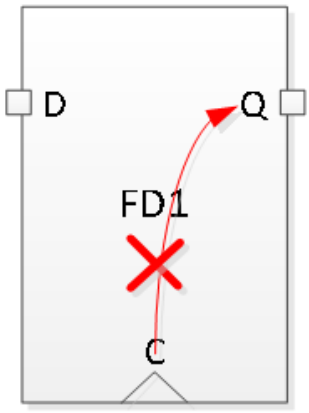

Figure 6-27: **Timing Arc Broken after Path Segmentation**

The process of breaking a timing arc to create a valid startpoint is called *path segmentation*. Path segmentation affects both max and min delay analysis. Because the timing arc is broken for the timing engine, path segmentation also affects any timing constraint going through those nodes (**FD1/C** and **FD1/Q**).

Note: Because of Path Segmentation, no clock insertion delay is used for the launch clock for paths starting from **FD1/Q.** This can potentially result in large skew because the clock skew of the endpoints is still taken into account. See Figure 6-28, Path Segmentation Result in Large Skew.

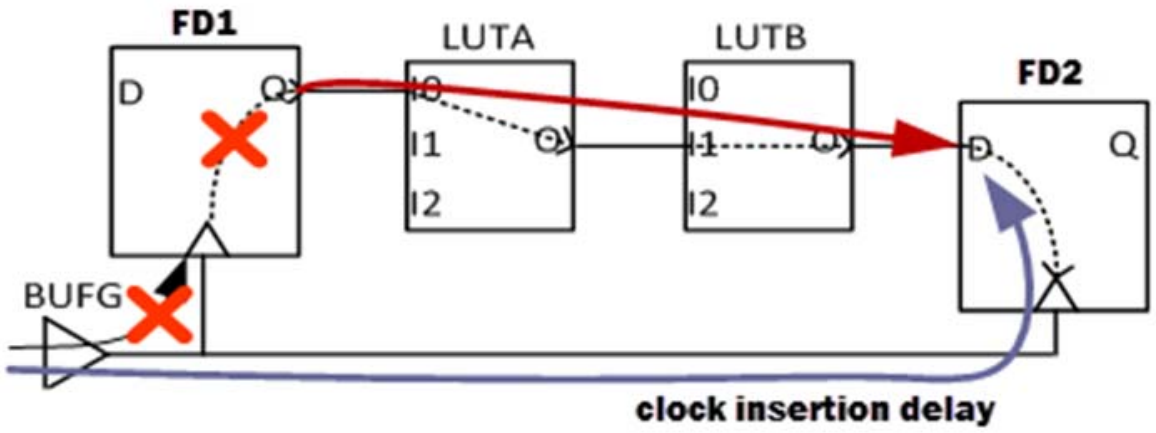

Figure 6-28: **Path Segmentation Result in Large Skew**

CAUTION! *Path segmentation can have unexpected consequences. Avoid path segmentation altogether, or use it very carefully.*

After path segmentation, there is no default hold requirement on the path. Use the **set_min_delay** command to set a hold requirement on the path if necessary.

Because of the risks, a critical warning is issued when a path segmentation occurs.

If you targeted the output **FD1/Q** as the startpoint in order to avoid taking the clock skew into account, Xilinx recommends using the **-datapath_only** option. Instead, see the following example:

```
set_max_delay 5 -from [get_pins FD1/C] -datapath_only
```

In the same way, when an invalid endpoint is specified, the timing engine breaks the timing arcs after the node so that the node does become a valid endpoint.

In the following example, the max delay is specified on **LUTA/O**, which is not a valid endpoint:

```
set_max_delay 5 -from [get_pins LUTA/O]
```

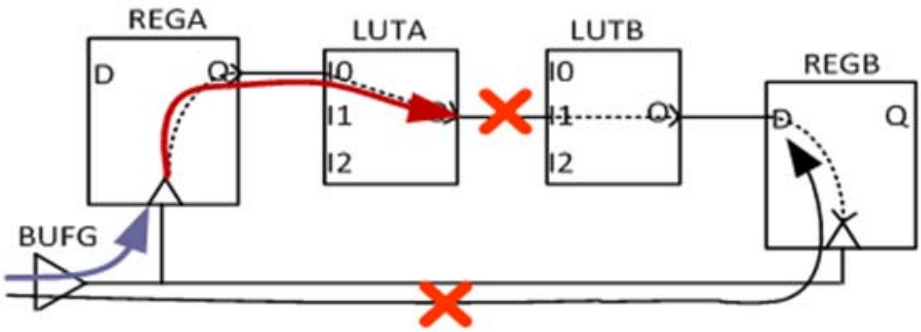

Figure 6-29: **Path Segmentation When an Invalid Endpoint is Specified**

To make **LUTA/O** an endpoint, the timing arc after **LUTA/O** is broken. As a result, all timing paths going through **LUTA/O** are impacted for both setup and hold. For the path starting on **FD1/C** and ending on **LUTA/O**, only the insertion delay of the launch clock is taken into account. This can result in very large skew.

Because path segmentation breaks timing arcs in the design, it can have unexpected consequences. The broken timing arcs impact all the timing paths going through those nodes.

In the following example, a max delay has been set between **LUTA/O** and **REGB/D:**

```
set_max_delay 6 -from [get_pins LUTA/O] -to [get_pins REGB/D]
```

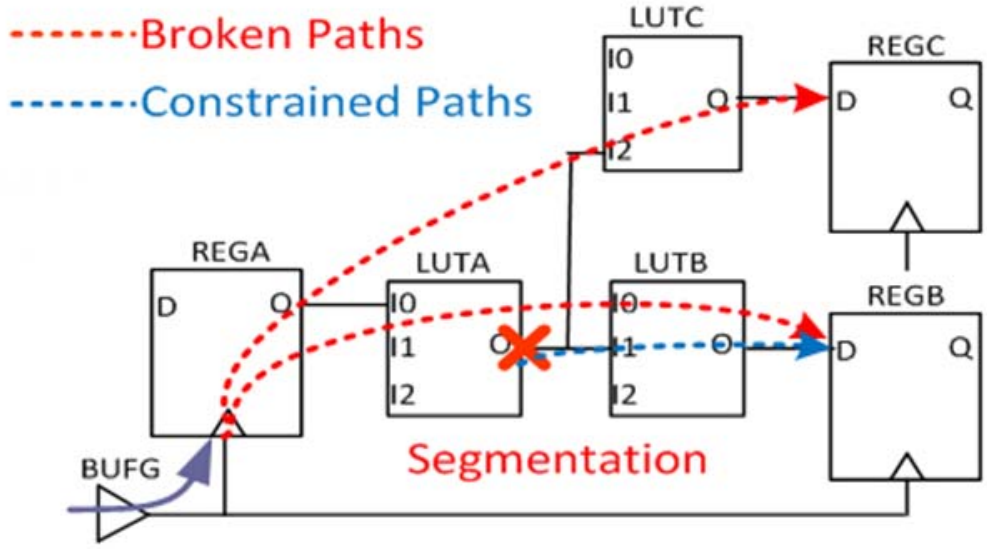

Figure 6-30: **Path Segmentation Breaking Multiple Paths**

Because the pin **LUTA/O** is not a valid startpoint: (1) a path segmentation occurs; and (2) the timing arcs from **LUTA/I*** and **LUTA/O** are disabled. Even though the **set_max_delay** constraint was set between **LUTA/O** and **REGB/D** only, other paths such as the path between **REGA/C** and **REGC/D** are also broken.

XDC Precedence

About XDC Precedence

The precedence rules for Xilinx®Design Constraints (XDC) are inherited from Synopsys Design Constraints (SDC). This chapter discusses how constraint conflicts or overlaps are resolved.

XDC Constraints Order

XDC constraints are commands interpreted sequentially. For equivalent constraints, the last constraint takes precedence.

Constraints Order Example

```
> create_clock –name clk1 –period 10 [get_ports clk_in1]
> create_clock –name clk2 –period 11 [get_ports clk_in1]
```

In this example, the second clock definition overrides the first clock definition because:

- They are both attached to the same input port.
- The **create_clock –add** option was not used.

Exceptions Priority

If constraints overlap (for example, if several timing exceptions are applied to the same path), the priority from highest to lowest is:

1. Clock Groups (**set_clock_groups**)
2. False Path (**set_false_path**)
3. Maximum Delay Path (**set_max_delay)** and Minimum Delay Path (**set_min_delay**)
4. Multicycle Paths (**set_multicycle_path**)

In addition, for the same type of exception, the more specific the constraint, the higher the precedence. Depending on the filtering options and the type of objects used in the constraint, you can modify the specificity of a constraint.

The priority rule for the objects is:

1. Ports, pins, and cells

   Note: Pins of a cell are used instead of the cell itself.

2. Clocks

The precedence rule for the filters is:

1. -from -through -to
2. -from -to
3. -from -through
4. -from
5. -through -to
6. -to
7. -through

Exceptions Priority Example

```
> set_max_delay 12 –from [get_clocks clk1] –to [get_clocks clk2]
> set_max_delay 15 –from [get_clocks clk1]
```

In this example, the first constraint overrides the second constraint for the paths from **clk1** to **clk2**.

The number of **-through** options used in an exception does not affect the precedence. The timing engine uses the tightest constraint.

Exceptions Priority with Multiple -through Options Example

```
> set_max_delay 4 -through [get_pins inst0/I0]
> set_max_delay 5 -through [get_pins inst0/I0] -through [get_pins inst1/I3]
```

Both exceptions are kept by the timing engine. The more challenging constraint is used for timing analysis. In this example, the 4ns max delay constraint will be used even for paths going through the pin **inst1/I3**.

RECOMMENDED: *You must avoid using several timing exceptions on the same paths, so that the timing analysis results are not dependent on priority rules, and it is easier to validate the effect of your constraints.*

If a string instead of an object is passed to the constraint, the Tcl interpreter uses the following sequence to determine which object matches the string:

1. port
2. pin
3. cell
4. net

The search is not exhaustive. As soon as objects of a certain type match the string pattern, they are returned, even though objects of another type down the list might also match the same pattern.

Physical Constraints

About Physical Constraints

The Xilinx® Vivado™ Integrated Design Environment (IDE) enables design objects to be physically constrained by setting values of object properties. Examples include:

- IO constraints such as location and IO standard
- Placement constraints such as cell locations
- Routing constraints such as fixed routing
- Configuration constraints such as the configuration mode

Similar to timing constraints, physical constraints must be saved in an XDC file or a Tcl script so that they can be loaded with the netlist when you open a design. Once the design is loaded in memory, you can interactively enter new constraints using the Tcl console, or by using one the Vivado Design Suite IDE editing tools.

Most physical constraints are defined by means of properties on an object:

```
set_property <property> <value> <object list>
```

The exception is for area constraints which use Pblock commands.

Critical Warning

Critical Warnings are issued for invalid constraints in XDC files, including those applied to objects that cannot be found in the design.

RECOMMENDED: *Xilinx highly recommends that you review all Critical Warnings to ensure that the design is properly constrained. Invalid constraints result in errors when applied interactively.*

For constraint definition and usage, see the *Vivado Design Suite Properties Reference Guide (UG912)* [Ref 8].

Netlist Constraints

Netlist constraints are set on netlist objects such as ports, pins, nets or cells, to require the compilation tool to handle them in special way.

- CLOCK_DEDICATED_ROUTE

  Set CLOCK_DEDICATED_ROUTE on a net to indicate how the clock signal is expected to be routed.

- MARK_DEBUG

  Set MARK_DEBUG on a net in the RTL to preserve it and make it visible in the netlist. This allows it to be connected to the logic debug tools at any point in the compilation flow.

- DONT_TOUCH

  Set DONT_TOUCH on a cell or a hierarchical instance to preserve it during netlist optimizations.

IO Constraints

IO constraints configure:

- Ports
- Cells connected to ports

Typical constraints include:

- IO standard
- IO location

The Vivado Integrated Design Environment (IDE) supports many of the same IO constraints as the Integrated Software Environment (ISE®) Design Suite. The following list of IO properties is not exhaustive. For a complete list, and for more information on IO port and IO cell properties, see the *Vivado Design Suite Properties Reference Guide (UG912)* [Ref 8].

- DRIVE

  Sets the output buffer drive strength (in mA), available with certain IO standards only.

- IOSTANDARD

  Sets an IO Standard to an I/O buffer instance.

- SLEW

  Sets the slew rate (rate of transition) behavior of a device output.

- IN_TERM

  Sets the configuration of the input termination resistance for an input port

- OUT_TERM

  Sets the configuration of the output termination resistance for an output port

- DIFF_TERM

  Turns on or off the 100 ohm differential termination for primitives such as IBUFDS_DIFF_OUT.

- KEEPER

  Applies a weak driver on an tri-stateable output or bidirectional port to preserve its value when not being driven.

- PULLDOWN

  Applies a weak logic low level on a tri-stateable output or bidirectional port to prevent it from floating.

- PULLUP

  Applies a weak logic high level on a tri-stateable output or bidirection port to prevent it from floating.

- DCI_VALUE

  Determines which buffer behavioral models are associated with the IOB elements when generating the IBIS file.

- DCI_CASCADE

  Defines a set of master and slave banks. The DCI reference voltage is chained from the master bank to the slaves.

- INTERNAL_VREF

  Frees the Vref pins of an I/O Bank and uses an internally generated Vref instead.

- IODELAY_GROUP

  Groups a set of IDELAY and IODELAY cells with an IDELAYCTRL to enable automatic replication and placement of IDELAYCTRL in a design.

- IOB

  Tells the placer to try to place FFs in I/O Logic instead of the fabric slice.

Placement Constraints

Placement constraints are applied to cells to control their locations within the device. The Vivado Integrated Design Environment (IDE) supports many of the same placement constraints as the Integrated Software Environment (ISE) Design Suite and the PlanAhead™ tool.

- LUTNM

  A unique string name applied to two LUTs to control their placement on a single LUT site.

- HLUTNM

  A unique string name applied to two LUTs in the same hierarchy to control their placement on a single LUT site.

- PROHIBIT

  Disallows placement to a site.

- PBLOCK

  Attached to logical blocks to constrain them to a physical region in the FPGA.

- PACKAGE_PIN

  Specifies the location of a design port on a pin of the target device package.

- LOC

  Places a logical element from the netlist to a site on the device.

- BEL

  Places a logical element from the netlist to a specific BEL within a slice on the device.

For more information, see Chapter 9, Defining Relatively Placed Macros.

Placement Types

There are two types of placement in the tools:

- Fixed Placement
- Unfixed Placement

Fixed Placement

Fixed placement is placement specified by the user through:

- Hand placement, or
- An XDC constraint
- Using either of the following on a cell object of the design loaded in memory:
  - IS_LOC_FIXED
  - IS_BEL_FIXED

Unfixed Placement

Unfixed placement is a placement performed by the implementation tools. By setting the placement as fixed, the implementation cannot move the constrained cells during the next iteration or during an incremental run. A fixed placement is saved in the XDC file, where it appears as a simple LOC or BEL constraint.

- IS_LOC_FIXED

  Promotes a LOC constraint from unfixed to fixed.

- IS_BEL_FIXED

  Promotes a BEL constraint from unfixed to fixed.

Placement Constraint Example One

Locate a block RAM at RAMB18_X0Y10 and fix its location.

```
% set_property LOC RAMB18_X0Y10 [get_cells u_ctrl0/ram0]
```

Placement Constraint Example Two

Place a LUT in the C5LUT BEL position within a slice and fix its BEL assignment.

```
% set_property BEL C5LUT [get_cells u_ctrl0/lut0]
```

Placement Constraint Example Three

Locate input bus registers in ILOGIC cells for shorter input delay.

```
% set_property IOB TRUE [get_cells mData_reg*]
```

Placement Constraint Example Four

Combine two small LUTs into a single LUT6_2 that uses both O5 and O6 outputs.

```
% set_property LUTNM L0 [get_cells {u_ctrl0/dmux0 u_ctrl0/dmux1}]
```

Placement Constraint Example Five

Prevent the placer from using the first column of block RAMs.

```
% set_property PROHIBIT TRUE [get_sites {RAMB18_X0Y* RAMB36_X0Y*}]
```

Routing Constraints

Routing constraints are applied to net objects to control their routing resources.

Pin Locking

LOCK_PINS is a cell property used to specify the mapping between logical LUT inputs (I0, I1, I2, ...) and LUT physical input pins (A6, A5, A4, ...).

A common use is to force timing-critical LUT inputs to be mapped to the fastest A6 and A5 physical LUT inputs.

LOCK_PINS Constraint Example One

Map I1 to A6 and I0 to A5 (swap the default mapping).

```
% set myLUT2  [get_cells u0/u1/i_365]
% set_property LOCK_PINS {I0:A5 I1:A6} $myLUT2
# Which you can verify by typing the following line in the Tcl Console:
% get_property LOCK_PINS $myLUT2
```

LOCK_PINS Constraint Example Two

Map I0 to A6 for a LUT6, mapping of I1 through I5 are dont-cares.

```
% set_property LOCK_PINS I0:A6 [get_cell u0/u1/i_768]
```

Fixed Routing

Fixed Routing is the mechanism for locking down routing, similar to Directed Routing in ISE®. Locking down a net routing resources involves three net properties. See Table 8-1, Net Properties.

Table 8-1: **Net Properties**

Property	Function
ROUTE	Read-only net property
IS_ROUTE_FIXED	Flag to mark the whole route as fixed
FIXED_ROUTE	A net's fixed route portion

To guarantee that a net routing can be fixed, all of its cells must also be fixed in advance.

Following is an example of a fully-fixed route. The example takes the design in Figure 8-1, Simple Design to Illustrate Routing Constraints, and creates the constraints to fix the routing of the net **netA** (selected in blue).

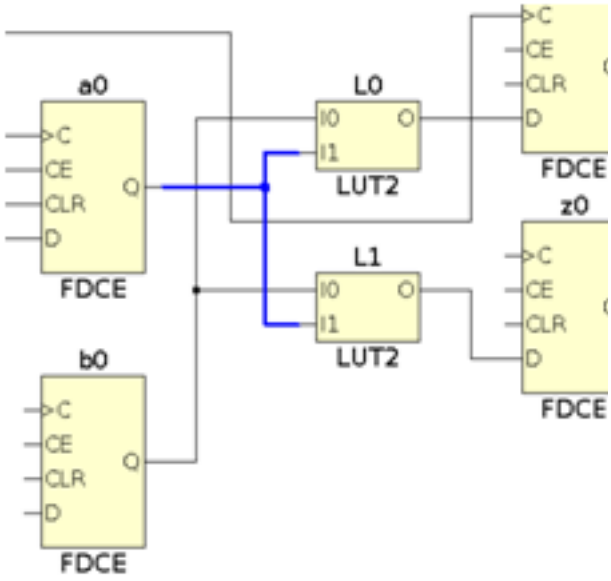

Figure 8-1: **Simple Design to Illustrate Routing Constraints**

You can query the routing information of any net after loading the implemented design in memory:

```
% set net [get_nets netA]
% get_property ROUTE $net
{ CLBLL_LL_CQ CLBLL_LOGIC_OUTS6 FAN_ALT5 FAN_BOUNCE5  { IMUX_L17 CLBLL_LL_B3 }  IMUX_L11
CLBLL_LL_A4 }
```

The routing is defined as a series of relative routing node names with fanout denoted using embedded curly braces. The routing is fixed by setting the following property on the net:

```
% set_property IS_ROUTE_FIXED TRUE $net
```

To back-annotate the constraints in your XDC file for future runs, the placement of all the cells connected to the fixed net must also be preserved. You can query this information by selecting the cells in the schematics or device view, and look at their LOC/BEL property values in the Properties window. Or you can query those values directly from the Tcl console:

```
% get_property LOC [get_cells {a0 L0 L1}]
SLICE_X0Y47 SLICE_X0Y47 SLICE_X0Y47
% get_property BEL [get_cells {a0 L0 L1}]
SLICEL.CFF SLICEL.A6LUT SLICEL.B6LUT
```

Because fixed routes are often timing-critical, LUT pins mapping must also be captured in the LOCK_PINS property of the LUT to prevent the router from swapping pins. Again, you can query the site pin of each logical pin from the Tcl console:

```
% get_site_pins -of [get_pins {L0/I1 L0/I0}]
SLICE_X0Y47/A4 SLICE_X0Y47/A2
% get_site_pins -of [get_pins {L1/I1 L1/I0}]
SLICE_X0Y47/B3 SLICE_X0Y47/B2
```

The complete XDC constraints required to fix the routing of net **netA** are:

```
set_property LOC SLICE_X0Y47 [get_cells {a0 L0 L1}]
set_property BEL CFF [get_cells a0]
set_property BEL A6LUT [get_cells L0]
set_property BEL B6LUT [get_cells L1]
set_property LOCK_PINS {I1:A4 I0:A2} [get_cells L0]
set_property LOCK_PINS {I1:A3 I0:A2} [get_cells L1]
set_property FIXED_ROUTE { CLBLL_LL_CQ CLBLL_LOGIC_OUTS6 FAN_ALT5 FAN_BOUNCE5  { IMUX_L17
CLBLL_LL_B3 }  IMUX_L11 CLBLL_LL_A4 } [get_nets netA]
```

If you are using interactive Tcl commands instead of XDC, several placement constraints can be specified at once with the **place_cell** command, as shown below:

```
place_cell a0 SLICE_X0Y47/CFF L0 SLICE_X0Y47/A6LUT L1 SLICE_X0Y47/B6LUT
```

For more information on **place_cell,** see the *Vivado Design Suite Tcl Command Reference Guide (UG835)* [Ref 6].

Configuration Constraints

Configuration constraints are global constraints for bitstream generation that are applied to the current design. This includes constraints such as the configuration mode.

Configuration Constraint Example One

Set the CONFIG_MODE to M_SELECTMAP.

```
% set_property CONFIG_MODE M_SELECTMAP [current_design]
```

Configuration Constraint Example Two

Set device pins E11 and F11 to be voltage reference pins.

```
% set_property VREF {E11 F11} [current_design]
```

Configuration Constraint Example Three

Disable CRC checking.

```
% set_property BITSTREAM.GENERAL.CRC Disable [current_design]
```

For a list of bitstream generation properties and definitions, see the *Vivado Design Suite Tcl Command Reference Guide (UG835)* [Ref 6].

Defining Relatively Placed Macros

About Relatively Placed Macros

A Relatively Placed Macro (RPM) is a list of logic elements grouped into a set. Examples of logic elements include:

- FF
- LUT
- DSP
- RAM

RPMs are primarily used to place small groups of logic close together in order to:

- Improve resource efficiency.
- Enable faster interconnections.

Defining Sets of Design Elements

Define sets of design elements with U Set (U_SET) or HU Set (HU_SET) constraints.

- Each element of the set is placed in relation to the other elements of the set by Relative Location (RLOC) constraints.
- Logic elements with RLOC constraints and common set names are associated in an RPM.

U_SET, HU_SET, and RLOC constraints:

- Must be defined as properties in the HDL design files.
- Are not supported in Xilinx Design Constraints format (XDC).

For more information on U_SET, HU_SET, and RLOC constraints, see the *Xilinx Constraints Guide (UG625)* [Ref 9].

Creating an RPM

To create an RPM:

1. Group cells into a set.
2. Define relative locations for cells in the RPM set.
3. Specify an RLOC_ORIGIN constraint or a LOC constraint on an RPM cell to fix placement of the RPM on the target device.

   Note: This step is optional.

Assigning Cells to RPM Sets

Design elements in a hierarchical module that are assigned RLOC constraints are automatically grouped into an RPM set.

The grouping occurs by using an H_SET constraint that is implicitly defined by the combination of the design hierarchy and the RLOC constraint.

All design elements with RLOC constraints in a single block of the design hierarchy are considered to be in the same H_SET *unless* they are tagged with another set constraint, such as U_SET or HU_SET.

Explicitly Grouping Design Elements

While H_SET is implied based on the design hierarchy and the presence of the RLOC constraint, you can also explicitly group design elements into RPM sets using the U_SET and HU_SET constraints.

Explicitly Grouping Design Elements With U_SET

U_SET lets you group cells regardless of hierarchy or where they appear in the design. All cells with the same **set_name** are members of the same RPM set.

Design elements tagged with a U_SET constraint can be primitive or non-primitive symbols.

When attached to non-primitive symbols, the U_SET constraint propagates downward through the hierarchy to all the primitive symbols below it that are assigned RLOC constraints.

Explicitly Grouping Design Elements With HU_SET

HU_SET has an explicit user-defined and hierarchically qualified name for the set. This lets you create hierarchical RPMs in which RLOC constraints can be placed on cells at different levels of the hierarchy.

All cells with the same hierarchically qualified *set_name* are members of the same set.

Syntax for Defining RPM Sets in VHDL

The syntax for defining RPM sets as attributes in VHDL is:

```
attribute U_SET : string;
attribute HU_SET : string;
...
attribute U_SET of my_reg : label  is "uset0";
attribute HU_SET of other_reg : label is "huset0";
```

Syntax for Defining RPM Sets in Verilog

The syntax for defining RPM sets as attributes in Verilog is as follows.

U_SET Example

```
(* U_SET = "uset0", RLOC = "X0Y0" *) my_reg FD (.C(clk), .D(d0), .Q(q0));
```

HU_SET Example

```
(* HU_SET = "huset0", RLOC = "X0Y0" *) other_reg FD (.C(clk), .D(d1), .Q(q1));
```

RPM Definition in the Physical Constraints Window

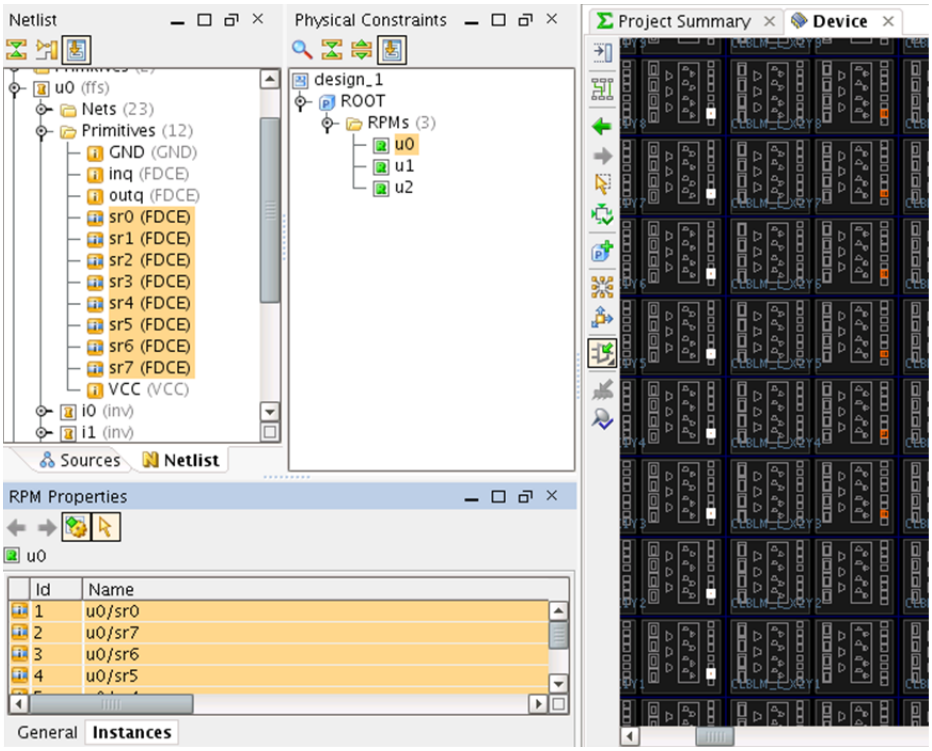

Figure 9-1: **RPM Definition in the Physical Constraints Window**

RPM sets must be embedded as properties in HDL source files. After synthesis, RPM related properties appear on netlist objects as read only properties for use by the Vivado® placer.

Viewing RPM Definitions

View RPM definitions in the Physical Constraints window. See Figure 9-1, RPM Definition in the Physical Constraints Window.

To view RPM definitions:

1. Expand the RPM folder to display a list of RPMs.
2. Select an RPM to view its properties or to select related cells.

TIP: *RPMs can be placed and locked down by dragging from the Physical Constraints to the Device window. The RPMs are moved as a single shape instead of cell-by-cell.*

Assigning Relative Locations

Use the RLOC property to assign relative locations to design objects. The RLOC property specifies relative X-Y coordinates for each cell in the RPM set.

To specify the RLOC property, use either of two different grid coordinate systems:

- Relative Slice-Based Coordinates
- Absolute RPM Grid-Based Coordinates

Use the following syntax:

```
RLOC=XmYn
```

where

- *m* is an integer representing the relative or absolute X coordinate of the object.
- *n* is an integer representing the relative or absolute Y coordinate of the object.

Relative Slice-Based Coordinates

The relative grid system:

- Is also known as the standard grid.
- Is sufficient for most RPMs.
- Is used for homogeneous RPMs in which all cells in an RPM belong to the same site type (such as slices, block RAM, and DSP).

  Note: Objects are positioned in relation to other objects in the same RPM set.

The relative grid is a standard rectangular grid in which each grid element is the same size. For example, the following Verilog code example results in an eight-slice-high column with an FD cell in each slice:

```
(* RLOC = "X0Y0" *) FD sr0 (.C(clk), .D(d[0]), .Q(y[0]));
(* RLOC = "X0Y1" *) FD sr1 (.C(clk), .D(d[1]), .Q(y[1]));
(* RLOC = "X0Y2" *) FD sr2 (.C(clk), .D(d[2]), .Q(y[2]));
(* RLOC = "X0Y3" *) FD sr3 (.C(clk), .D(d[3]), .Q(y[3]));
(* RLOC = "X0Y4" *) FD sr4 (.C(clk), .D(d[4]), .Q(y[4]));
(* RLOC = "X0Y5" *) FD sr5 (.C(clk), .D(d[5]), .Q(y[5]));
(* RLOC = "X0Y6" *) FD sr6 (.C(clk), .D(d[6]), .Q(y[6]));
(* RLOC = "X0Y7" *) FD sr7 (.C(clk), .D(d[7]), .Q(y[7]));
```

Absolute RPM Grid-Based Coordinates

The RPM_GRID system is used for heterogeneous RPMs in which cells in an RPM belong to different site types (such as a combination of slices, block RAM, and DSP). This is an absolute coordinate system that is mapped to a specific Xilinx device.

Because the cells may occupy sites of various sizes, the RPM_GRID system uses absolute RPM_GRID coordinates. The RPM_GRID values are visible in the Site Properties window of the Vivado Integrated Design Environment (IDE) when a specific site is selected. The coordinates can also be queried with Tcl commands using the RPM_X and RPM_Y site properties.

RPM_GRID Coordinates VHDL Example

The following VHDL example defines RLOC constraints using RPM_GRID coordinates.

- Two shift registers are placed relative to a block RAM.
- Four stages connect the input.
- Four stages connect the output.

```
attribute RLOC : string;
attribute RPM_GRID : string;
attribute RLOC of di_reg3 : label is "X25Y0";
attribute RLOC of di_reg2 : label is "X27Y0";
attribute RLOC of di_reg1: label is "X29Y0";
attribute RLOC of di_reg0 : label is "X31Y0";
attribute RLOC of ram0 : label is "X34Y0";
attribute RLOC of out_reg3 : label is "X37Y0";
attribute RLOC of out_reg2 : label is "X39Y0";
attribute RLOC of out_reg1 : label is "X41Y0";
attribute RLOC of out_reg0 : label is "X43Y0";
```

Setting a Property to Invoke the RPM_GRID System

To use the RPM_GRID system, set a property on any cell in the RPM set:

```
attribute RPM_GRID of ram0 : label is "GRID";
```

As long as at least one cell has the RPM_GRID property equal to GRID, the RPM_GRID coordinate system is used.

Although the RPM_GRID coordinates are absolute based on the target device, they define the relative placement of the elements of an RPM set.

During implementation, the RPM set can be placed at any suitable location on the device.

RPM_GRID Coordinate Values

The RPM_GRID coordinate values differ significantly from the coordinate values of the SLICEs on the FPGA device. These coordinates:

- Are stored as RPM_X and RPM_Y properties on device sites in the Vivado tool.
- Can be queried using **get_property**.

The following example:

- Gets the RPM coordinates from a selected SLICE.
- Uses **join** to output both the X and Y coordinates in the required format.

```
join "X[get_property RPM_X [get_selected_objects]]Y[get_property RPM_Y
[get_selected_objects]]"
X25Y394
```

Defining RLOC Properties Directly in the RTL Source File

Because the standard grid is simple and relative, you can define the RLOC properties for an RPM directly in the RTL source file.

Because the RPM_GRID coordinates must be extracted from the target device, you will probably need to:

- Iterate on the design to find the right RPM_GRID values after synthesis.
- Add the coordinates as properties in the RTL source files.
- Resynthesize the netlist before placement.

Assigning a Fixed Location to an RPM

Optionally use an RLOC_ORIGIN or LOC constraint to place and fix the location of an RPM on the device. In the Vivado IDE, these properties fix the RPM origin, or the lower-left corner of the RPM. Each remaining cell in the RPM set is placed by using the relative location (RLOC) to offset from the origin.

Figure 9-2: **RPM Placement by RLOC_ORIGIN**

The following example shows a hierarchical RPM that is fixed using RLOC_ORIGIN. RLOC constraints are assigned to the RPM register cells to create a two-up-by-three-across placement pattern.

In Verilog:

```
(* RLOC = "X0Y0" *) FDC sr0...
(* RLOC = "X1Y0" *) FDC sr1...
(* RLOC = "X2Y0" *) FDC sr2...
(* RLOC = "X0Y1" *) FDC sr3...
(* RLOC = "X1Y1" *) FDC sr4...
(* RLOC = "X2Y1" *) FDC sr5...
```

The RPM is instantiated into the design three times with an RLOC on each cell:

```
(* RLOC = "X0Y0" *) ffs u0...
(* RLOC = "X3Y2" *) ffs u1...
(* RLOC = "X6Y4" *) ffs u2...
```

Finally, an RLOC_ORIGIN of `X74Y15` is assigned to cell `u0` resulting in the placement shown in Figure 9-2, RPM Placement by RLOC_ORIGIN. The highlighting in the figure is shown in Table 9-1, Cell Highlighting.

Table 9-1: **Cell Highlighting**

Cell	Highlight Color
u0	yellow
u1	green
u2	red

TIP: *Although RPMs control the relative placement of logic elements, they do not insure that specific routing resources are used to connect the logic from one implementation to the next.*

For more information on controlling the routing used, see *Routing Constraints* in the *Vivado Design Suite User Guide: Using Constraints (UG903)* [Ref 4].

XDC Macros

XDC macros enable assignment of relative placement to cells after synthesis. Macros have many characteristics similar to RPMs, but are design objects that can be modified interactively using XDC and Tcl. Macros are created from leaf cells that are grouped together with relative placement constraints.

While RPMs are managed in HDL code, macros are managed using XDC constraints. RPMs cannot be automatically converted to macros. Similarly, macros cannot be automatically annotated to HDL code. Unlike macros, RPMs are not objects, and the XDC macro commands cannot be used on RPMs.

Table 9-2: **Comparison of RPMs and Macros**

	RPMs	Macros
Definition	HDL Attributes	XDC constraints
Post-Synthesis Access	Read-only	Read-write
Hierarchical	Yes (H_SET/HU_SET)	No
RLOC Targets	Non-leaf and leaf cells	Leaf cells only
Site Type Mixing Allowed	Yes, using RPM_GRID attribute	Yes, using update_macro -absolute_grid
Accessible as objects	No	Yes
Where stored	In netlist	In XDC or Tcl scripts

Specifying Macros

Use the following XDC Tcl commands to specify macros:

- create_macro
- update_macro
- delete_macros
- get_macros

Each command is supported by **undo** and **redo**.

Following are descriptions of each command.

create_macro

The **create_macro** command creates a new macro object.

Macro names must be unique. Attempting to create a macro with the same name as an existing macro generates an error.

create_macro Syntax

```
create_macro <name>
```

create_macro Example

```
create_macro m0
```

Creates a macro object called **m0**.

update_macro

The **update_macro** command adds leaf cells and relative placements (RLOCs) to the macro.

The RLOC has identical syntax and functionality as the RPM RLOC attribute. All cells must be specified at once. No partial or incremental definition is allowed.

update_macro Syntax

```
update_macro  [-absolute_grid] <macro name>  <cell-RLOC list>
```

where

- **-absolute_grid**: A switch to choose the Absolute Grid for mixing slice and non-slice sites.
  - The X-Y values are the site properties RPM_X and RPM_Y.
  - The Absolute Grid values are identical to those of RPM_GRID.

- **macro name**: The name of the macro to be updated.
- **cell-RLOC list**: A Tcl list of cells and RLOC pairs:

  `{cell0 RLOC(cell0) cell1 RLOC(cell1) … cellN RLOC(cellN)}.`

  - All macro cells and RLOCs must be specified at once. It is not possible to build a macro in steps.
  - If you need to update an existing macro, you must re-create it first.

update_macro Example One

```
update_macro m1 {u2/sr0 X0Y0 u2/sr1 X0Y1}
```

- Adds **u2/sr0** and **u2/sr1** to macro **m1**
- Assigns **u2/sr0** an RLOC of **X0Y0**
- Assigns **u2/sr1** an RLOC of **X0Y1**

The following (update_macro Example Two) does the same, with slightly different syntax.

update_macro Example Two

```
set rlocs [list u2/sr0 X0Y0 u2/sr1 X0Y1]
update_macro m1 $rlocs
```

update_macro Example Three

This example uses the absolute grid:

```
set rlocs {ireg X2Y38 q1reg X17Y40 q2reg X17Y40}
update_macro -absolute_grid m2 $rlocs
```

delete_macros

The **delete_macros** command deletes the specified macros.

delete_macros Syntax

```
delete_macros <pattern>
```

delete_macros Example

```
delete_macros m1
```

get_macros

The **get_macros** command returns macro objects in a design.

get_macros Syntax

```
get_macros [pattern]
```

With no arguments, the **get_macros** command returns all macros in the design. When macro names are specified, the command returns the corresponding macro objects.

get_macros Examples

The **get_macros** command can be used with other object commands. Examples:

```
% create_macro m1
% update_macro m1 {u2/sr0 X0Y0 u2/sr1 X0Y1}
% get_cells -of [get_macros m1]
u2/sr0 u2/sr1
% get_macros -of [get_cells u2]
m1
```

The following command returns all macros that are fully contained within the cells.

```
get_macros -of [get_cells $cells]
```

Using **get_cells**, other indirect combinations are possible such as:

```
get_macros -of [get_cells -of [get_pblocks pb0]]
```

This command returns the macros contained within Pblock **pb0**.

Managing Macros

Macros are stored as XDC constraints. By definition, they are Tcl commands. This allows the macros to be used in both XDC constraint files and Tcl scripts, and used interactively.

Macros are written using the **write_xdc** command. Macros are read using the **read_xdc** command. The **-cell** option can be used to limit scope to particular cells.

The **-cell** option is particularly useful for applying a relative placement from one macro to similar instances in different hierarchies.

Managing Macros Example One

Write all XDC constraints in memory, including macros:

```
% write_xdc constrs.xdc
```

Managing Macros Example Two

A design contains three instances of a cell: inst_0, inst_1, and inst_2.

A macro is created inside u0:

```
% create_macro m0
% update_macro m0 {reg0 X0Y0 reg1 X0Y1}
% write_xdc -cell inst_0 inst_0.xdc
```

Managing Macros Example Three

Write all XDC constraints including macro m0, for the cell inst_0:

```
% write_xdc -cell inst_0 inst_0.xdc
```

Managing Macros Example Four

Read the XDC constraints including the macro m0 from cell inst_0, and apply it to inst_1 and inst_2:

```
% read_xdc inst_0 -cell {inst_1 inst_2}
% get_macros
m0 inst_1_m0 inst_2_m0
```

Note that when a macro is read and applied to another cell using the -cell option, the new macro name must be unique. The cell name is applied as a prefix to the macro name to create a unique macro name. In the example two new unique macros were created: inst_1_m0 and inst_2_m0.

Macro Properties

Macro objects have the following properties:

- ABSOLUTE_GRID
- CLASS
- NAME
- RLOCS

Macro Properties Example

```
% report_property [get_macros m1]
Property       Type     Read-only  Visible  Value
ABSOLUTE_GRID  bool     true       true     0
CLASS          string   true       true     macro
NAME           string   true       true     m1
RLOCS          string*  true       true     u2/sr0 X0Y0 u2/sr1 X0Y1
```

Following are descriptions of the properties:

ABSOLUTE_GRID

Boolean property that reflects whether or not the RLOCs are using the default grid system or the Absolute Grid system.

The default is false. If **update_macro** is used with **-absolute_grid**, then the property is true.

The Absolute Grid uses coordinates that align with site RPM_X and RPM_Y properties to allow creating macros from cells placed at different site types.

CLASS

Identifies the object as a macro.

NAME

Name of the macro object, either the name used by **create_macro**, or the macro name prefixed by the cell hierarchy when using **read_xdc -cell**.

RLOCS

String containing the list of macro cells and their RLOC properties in the same format used by the **update_macro** command.

Macro cells have these additional properties:

- RLOC: The relative location property (RLOC) value of the cell.
- MACRO_NAME: The name of the macro to which the cell belongs.

RLOCS Example

Using the previous example for macro properties:

```
% get_property RLOC [get_cells {u2/sr0 u2/sr1}]
X0Y0 X0Y1
% get_property MACRO_NAME [get_cells {u2/sr0 u2/sr1}]
m1 m1
```

Appendix A

Additional Resources

Xilinx Resources

For support resources such as Answers, Documentation, Downloads, and Forums, see the Xilinx® Support website at:

www.xilinx.com/support

For a glossary of technical terms used in Xilinx documentation, see:

www.xilinx.com/company/terms.htm

Solution Centers

See the Xilinx Solution Centers for support on devices, software tools, and intellectual property at all stages of the design cycle. Topics include design assistance, advisories, and troubleshooting tips.

References

Vivado® Design Suite User Guides

1. *Vivado Design Suite User Guide: System-Level Design Entry (UG895)*
2. *Vivado Design Suite User Guide: I/O and Clock Planning (UG899)*
3. *Vivado Design Suite User Guide: Synthesis (UG901)*
4. *Vivado Design Suite User Guide: Using Constraints (UG903)*
5. *Vivado Design Suite User Guide: Design Analysis and Closure Techniques (UG906)*

Other Vivado Design Suite Documents

6. *Vivado Design Suite Tcl Command Reference Guide (UG835)*
7. *Vivado Design Suite Migration Methodology Guide (UG911)*
8. *Vivado Design Suite Properties Reference Guide (UG912)*

Other Xilinx Documents

9. *Constraints Guide (UG625)*

Vivado Design Suite Video Tutorials

10. *Vivado Design Suite Video Tutorials (http://www.xilinx.com/training/vivado/index.htm)*

Vivado Design Suite Documentation

11. *Vivado Design Suite Documentation (www.xilinx.com/support/documentation/dt_vivado2013-1.htm)*

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Appendix B

Supported XDC and SDC Commands

About Supported XDC and SDC Commands

This Appendix discusses supported XDC and SDC commands, and includes the following:

- Valid Commands in an XDC File
- Supported SDC Commands
- Unsupported SDC Commands

Valid Commands in an XDC File

Table B-1: **Valid Commands in an XDC File**

Timing Constraint	Physical Constraint	Netlist Object Query
create_clock create_generated_clock group_path set_clock_groups set_clock_latency set_data_check set_disable_timing set_false_path set_input_delay set_output_delay set_max_delay set_min_delay set_multicycle_path set_case_analysis set_clock_sense set_clock_uncertainty set_input_jitter set_max_time_borrow set_propagated_clock set_system_jitter set_external_delay	add_cells_to_pblock create_pblock delete_pblock remove_cells_from_pblock resize_pblock create_macro delete_macros update_macro	all_cpus all_dsps all_fanin all_fanout all_hsios all_inputs all_outputs all_rams all_registers all_ffs all_latches get_cells get_nets get_pins get_ports get_debug_cores get_debug_ports
	Netlist Constraint	
	set_load set_logic_dc set_logic_one set_logic_zero set_logic_unconnected	
Device Object Query	**Timing Object Query**	**General Purpose**
get_iobanks get_package_pins get_sites get_bel_pins get_bels get_nodes get_pips get_site_pins get_site_pips get_slrs get_tiles get_wires	all_clocks get_path_groups get_clocks get_generated_clocks get_timing_arcs	set expr list filter current_instance get_hierarchy_separator set_hierarchy_separator get_property set_property set_units endgroup startgroup
	Floorplan Object Query	
	get_pblocks get_macros	

Supported SDC Commands

Note: Because *all* Xilinx® Tcl commands support the **-quiet** and **-verbose** options, the following table does not list them.

Table B-2: **Supported SDC Commands**

SDC 1.9	Xilinx SDC	Note
current_instance [*instance_name*]	**current_instance** [*instance_name*]	The Vivado® IDE handles **get_ports** differently when using **read_xdc –cells/-ref** or the **SCOPED_TO_xxx** constraint file property.
expr	**expr**	
list	**list**	In the Vivado IDE, a Tcl list is also used as an objects container.
set	**set**	
set_hierarchy_separator [*separator*]	**set_hierarchy_separator** [*separator*]	
set_units [-capacitance *cap_units*] [-resistance *res_unit*] [-time *time_unit*] [-voltage *voltage_units*] [-current *current_unit*] [-power *power_unit*]	**set_units** [-capacitance *arg*] [-resistance *arg*] [-time *arg*] [-voltage *arg*] [-current *arg*] [-power *arg*] [-suffix arg] [-digits arg]	The **set_units –time** cannot change the timing unit in the Vivado IDE.
all_clocks	**all_clocks**	
all_inputs [-level_sensitive] [-edge_triggered] [-clock *clock_name*]	**all_inputs**	
all_outputs [-level_sensitive] [-edge_triggered] [-clock *clock_name*]	**all_outputs**	

Table B-2: **Supported SDC Commands *(Cont'd)***

SDC 1.9	Xilinx SDC	Note
all_registers [-no_hierarchy] [-clock *clock_name*] [-rise_clock *clock_name*] [-fall_clock *clock_name*] [-cells] [-data_pins] [-clock_pins] [-slave_clock_pins] [-async_pins] [-output_pins] [-level_sensitive] [-edge_triggered] [-master_slave]	**all_registers** [-no_hierarchy] [-clock *args*] [-rise_clock *args*] [-fall_clock *args*] [-cells] [-data_pins] [-clock_pins] [-async_pins] [-output_pins] [-level_sensitive] [-edge_triggered]	
current_design	**current_design**	In the Vivado IDE, the current design refers to the design loaded in memory, and cannot be changed to another module or entity than the top-level one.
get_cells [-hierarchical] [-hsc *separator*] [-regexp] [-nocase] -of_objects *objects* *patterns*	**get_cells** [-hierarchical] [-hsc *arg*] [-regexp] [-nocase] [-of_objects *args*] [*patterns*] [-filter *arg*] [-match_style *arg*]	
get_clocks [-regexp] [-nocase] *patterns*	**get_clocks** [-regexp] [-nocase] [*patterns*] [-filter *arg*] [-of_objects *args*] [-match_style *arg*] [-include_generated_clocks]	The Vivado IDE supports the **–of_objects** option to query the clock object on the clock tree.
get_lib_cells [-hsc *separator*] [-regexp] [-nocase] *patterns*	**get_lib_cells** [-regexp] [-nocase] *patterns* [-filter arg] [-include_unsupported] [-of_objects *args*]	In the Vivado IDE, because only one device library can be loaded for a design, it is not necessary to specify the library name when querying the library cells.

Table B-2: **Supported SDC Commands *(Cont'd)***

SDC 1.9	Xilinx SDC	Note
get_lib_pins [-hsc *separator*] [-regexp] [-nocase] patterns	**get_lib_pins** [-regexp] [-nocase] *patterns* [-filter *arg*] [-of_objects *args*]	
get_libs [-regexp] [-nocase] *patterns*	**get_libs** [-regexp] [-nocase] [*patterns*] [-filter arg]	
get_nets [-hierarchical] [-hsc *separator*] [-regexp] [-nocase] -of_objects *objects* patterns	**get_nets** [-hierarchical] [-hsc *arg*] [-regexp] [-nocase] [-of_objects *args*] [*patterns*] [-filter *arg*] [-match_style *arg*] [-top_net_of_hierarchical_group] [-segments] [-boundary_type *arg*]	
get_pins [-hierarchical] [-hsc *separator*] [-regexp] [-nocase] -of_objects *objects* *patterns*	**get_pins** [-hierarchical] [-hsc *arg*] [-regexp] [-nocase] [-of_objects *args*] [*patterns*] [-leaf] [-filter *arg*] [-match_style *arg*]	
get_ports [-regexp] [-nocase] patterns	**get_ports** [-regexp] [-nocase] [*patterns*] [-filter *arg*] [-of_objects *args*] [-match_style *arg*]	

Table B-2: **Supported SDC Commands *(Cont'd)***

SDC 1.9	Xilinx SDC	Note
create_clock -period *period_value* [-name *clock_name*] [-waveform *edge_list*] [-add] [*source_objects*]	**create_clock** -period *arg* [-name *arg*] [-waveform *args*] [-add] [*objects*]	
create_generated_clock [-name *clock_name*] -source *master_pin* [-edges *edge_list*] [-divide_by *factor*] [-multiply_by *factor*] [-duty_cycle *percent*] [-invert] [-edge_shift *shift_list*] [-add] [-master_clock *clock*] [-combinational] *source_objects*	**create_generated_clock** [-name *arg*] [-source *args*] [-edges *args*] [-divide_by *arg*] [-multiply_by *arg*] [-duty_cycle *arg*] [-edge_shift *args*] [-add] [-master_clock *arg*] [-combinational] objects	
group_path [-name *group_name*] [-default] [-weight *weight_value*] [-from *from_list*] [-rise_from *from_list*] [-fall_from *from_list*] [-to *to_list*] [-rise_to *to_list*] [-fall_to *to_list*] [-through *through_list*] [-rise_through *through_list*] [-fall_through *through_list*]	**group_path** [-name *arg*] [-from *args*] [-to *args*] [-through *args*]	
set_clock_groups [-name *name*] [-logically_exclusive] [-physically_exclusive] [-asynchronous] [-allow_paths] -group *clock_list*	**set_clock_groups** [-name *arg*] [-logically_exclusive] [-physically_exclusive] [-asynchronous] [-group *args*]	

Table B-2: **Supported SDC Commands *(Cont'd)***

SDC 1.9	Xilinx SDC	Note
set_clock_latency [-rise] [-fall] [-min] [-max] [-source] [-late] [-early] [-clock *clock_list*] *delay* *object_list*	**set_clock_latency** [-rise] [-fall] [-min] [-max] [-source] [-late] [-early] [-clock *args*] *latency* *objects*	
set_clock_sense [-positive] [-negative] [-pulse *pulse*] [-stop_propagation] [-clock *clock_list*] *pin_list*	**set_clock_sense** [-positive] [-negative] [-pulse *arg*] [-stop_propagation] [-clocks *args*] *pins*	
set_clock_uncertainty [-from *from_clock*] [-rise_from *rise_from_clock*] [-fall_from *fall_from_clock*] [-to *to_clock*] [-rise_to *rise_to_clock*] [-fall_to *fall_to_clock*] [-rise] [-fall] [-setup] [-hold] uncertainty [*object_list*]	**set_clock_uncertainty** [-from *args*] [-rise_from *args*] [-fall_from *args*] [-to *args*] [-rise_to *args*] [-fall_to *args*] [-setup] [-hold] *uncertainty* [*objects*]	
set_data_check [-from *from_object*] [-to *to_object*] [-rise_from *from_object*] [-fall_from *from_object*] [-rise_to *to_object*] [-fall_to *to_object*] [-setup] [-hold] [-clock *clock_object*] *value*	**set_data_check** [-from *args*] [-to *args*] [-rise_from *args*] [-fall_from *args*] [-rise_to *args*] [-fall_to *args*] [-setup] [-hold] [-clock *args*] *value*	

Table B-2: **Supported SDC Commands *(Cont'd)***

SDC 1.9	Xilinx SDC	Note
set_disable_timing [-from *from_pin_name*] [-to *to_pin_name*] *cell_pin_list*	**set_disable_timing** [-from *arg*] [-to *arg*] *objects*	
set_false_path [-setup] [-hold] [-rise] [-fall] [-from *from_list*] [-to *to_list*] [-through *through_list*] [-rise_from *rise_from_list*] [-rise_to *rise_to_list*] [-rise_through *rise_through_list*] [-fall_from *fall_from_list*] [-fall_to *fall_to_list*] [-fall_through *fall_through_list*]	**set_false_path** [-setup] [-hold] [-rise] [-fall] [-from *args*] [-to *args*] [-through *args*] [-rise_from *args*] [-rise_to *args*] [-rise_through *args*] [-fall_from *args*] [-fall_to *args*] [-fall_through *args*] [-reset_path]	
set_input_delay [-clock *clock_name*] [-clock_fall] [-level_sensitive] [-rise] [-fall] [-max] [-min] [-add_delay] [-network_latency_included] [-source_latency_included] *delay_value* *port_pin_list*	**set_input_delay** [-clock *args*] [-clock_fall] [-rise] [-fall] [-max] [-min] [-add_delay] [-network_latency_included] [-source_latency_included] *delay* *objects* [-reference_pin *args*]	In the Vivado IDE, input delays are not supported on internal pins.

Table B-2: **Supported SDC Commands *(Cont'd)***

SDC 1.9	Xilinx SDC	Note
set_max_delay [-rise] [-fall] [-from *from_list*] [-to *to_list*] [-through *through_list*] [-rise_from *rise_from_list*] [-rise_to *rise_to_list*] [-rise_through *rise_through_list*] [-fall_from *fall_from_list*] [-fall_to *fall_to_list*] [-fall_through *fall_through_list*] *delay_value*	**set_max_delay** [-rise] [-fall] [-from *args*] [-to *args*] [-through *args*] [-rise_from *args*] [-rise_to *args*] [-rise_through *args*] [-fall_from *args*] [-fall_to *args*] [-fall_through *args*] *delay* [-reset_path] [-datapath_only]	
set_max_time_borrow *delay_value* object_list	**set_max_time_borrow** *delay* *objects*	
set_min_delay [-rise] [-fall] [-from *from_list*] [-to *to_list*] [-through *through_list*] [-rise_from *rise_from_list*] [-rise_to *rise_to_list*] [-rise_through *rise_through_list*] [-fall_from *fall_from_list*] [-fall_to *fall_to_list*] [-fall_through *fall_through_list*] *delay_value*	**set_min_delay** [-rise] [-fall] [-from *args*] [-to *args*] [-through *args*] [-rise_from *args*] [-rise_to *args*] [-rise_through *args*] [-fall_to *args*] [-fall_from *args*] [-fall_through *args*] *delay* [-reset_path]	

Table B-2: **Supported SDC Commands *(Cont'd)***

SDC 1.9	Xilinx SDC	Note
set_multicycle_path [-setup] [-hold] [-rise] [-fall] [-start] [-end] [-from *from_list*] [-to *to_list*] [-through *through_list*] [-rise_from *rise_from_list*] [-rise_to *rise_to_list*] [-rise_through *rise_through_list*] [-fall_from *fall_from_list*] [-fall_to *fall_to_list*] [-fall_through *fall_through_list*] path_multiplier	**set_multicycle_path** [-setup] [-hold] [-rise] [-fall] [-start] [-end] [-from *args*] [-to *args*] [-through *args*] [-rise_from *args*] [-rise_to *args*] [-rise_through *args*] [-fall_from *args*] [-fall_to *args*] [-fall_through *args*] *path_multiplier* [-reset_path]	
set_output_delay [-clock *clock_name*] [-clock_fall] [-level_sensitive] [-rise] [-fall] [-max] [-min] [-add_delay] [-network_latency_included] [-source_latency_included] *delay_value* *port_pin_list*	**set_output_delay** [-clock *args*] [-clock_fall] [-rise] [-fall] [-max] [-min] [-add_delay] [-network_latency_included] [-source_latency_included] *delay* *objects* [-reference_pin *args*]	In the Vivado IDE, output delays are not supported on internal pins.
set_propagated_clock *object_list*	**set_propagated_clock** *object*	In the Vivado IDE, all clocks are propagated clocks by default.
set_case_analysis *value* port_or_pin_list	**set_case_analysis** *value* *objects*	

Table B-2: **Supported SDC Commands *(Cont'd)***

SDC 1.9	Xilinx SDC	Note
set_load [-min] [-max] [-subtract_pin_load] [-pin_load] [-wire_load] *value* *objects*	**set_load** [-max] [-min] *capacitance* *objects* [-rise] [-fall]	In the Vivado IDE, the **set_load** command is relevant for power analysis only.
set_logic_dc *port_list*	**set_logic_dc** *objects*	
set_logic_one *port_list*	**set_logic_one** *objects*	
set_logic_zero *port_list*	**set_logic_zero** *objects*	
set_operating_conditions [-library *lib_name*] [-analysis_type *analysis_type*] [-max *max_condition*] [-min *min_condition*] [-max_library *max_lib*] [-min_library *min_lib*] [-object_list *objects*] [*condition*]	**set_operating_conditions** [-voltage *args*] [-grade *arg*] [-process *arg*] [-junction_temp *arg*] [-ambient_temp *arg*] [-thetaja *arg*] [-thetasa *arg*] [-airflow *arg*] [-heatsink *arg*] [-thetajb *arg*] [-board *arg*] [-board_temp *arg*] [-board_layers *arg*]	In the Vivado IDE, the **set_operating_conditions** command: (1) sets the operating conditions for power analysis only; and (2) does not influence the timing reports. The Vivado IDE timing engine is controlled by the **config_timing_analysis** command. For more information on **config_timing_analysis**, see the *Vivado Design Suite Tcl Command Reference Guide (UG835)*[Ref 6].

Unsupported SDC Commands

The following SDC commands are not supported.

- set_clock_gating_check
- set_clock_transition
- set_ideal_latency
- set_ideal_network
- set_ideal_transition
- set_ max_fanout

  Note: Maximum fanout is controlled by the MAX_FANOUT attribute during synthesis.
- set_drive
- set_driving_cell
- set_fanout_load
- set_input_transition
- set_max_area
- set_max_capacitance
- set_max_transition
- set_min_capacitance
- set_port_fanout_number
- set_resistance
- set_timing_derate
- set_voltage
- set_wire_load_min_block_size
- set_wire_load_mode
- set_wire_load_model
- set_wire_load_selection_group
- create_voltage_area
- set_level_shifter_strategy

- set_level_shifter_threshold
- set_max_dynamic_power
- set_max_leakage_power