**ID1000500A**

**CONVOLUTION IP-CORE USER MANUAL**

# DESCRIPTION

The Convolution IP-core is the system representing an algorithm that combines two functions to describe the overlap between the two functions.

After receiving a start command, this Ip-core performs the convolution algorithm of the data stored in the input memories X and Y and saves the resulting data in the output memory Z.

## CONFIGURABLE FEATURES

|  |  |
| --- | --- |
| **Software configurations** | **Description** |
| Processing size | Size of input memories. |

## TYPICAL APPLICATION

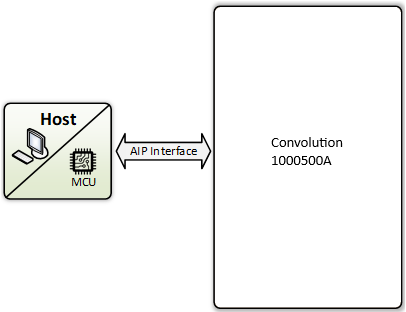


Figure 1.1 IP Convolution connected to a host

# CONTENTS

[1. DESCRIPTION 1](#_Toc167620891)

[1.1. CONFIGURABLE FEATURES 1](#_Toc167620892)

[1.2. TYPICAL APPLICATION 1](#_Toc167620893)

[2. CONTENTS 2](#_Toc167620894)

[2.1. List of figures 3](#_Toc167620895)

[2.2. List of tables 3](#_Toc167620896)

[3. INPUT/OUTPUT SIGNAL DESCRIPTION 4](#_Toc167620897)

[4. THEORY OF OPERATION 5](#_Toc167620898)

[5. AIP interface registers and memories description 6](#_Toc167620899)

[5.1. Status register 6](#_Toc167620900)

[5.2. Configuration delay register 7](#_Toc167620901)

[5.3. Input data memory 7](#_Toc167620902)

[5.4. Output data memory 7](#_Toc167620903)

[6. PYTHON DRIVER 8](#_Toc167620904)

[6.1. Usage example 8](#_Toc167620905)

[6.2. Methods 9](#_Toc167620906)

[6.2.1. Constructor 9](#_Toc167620907)

[6.2.2. writeData 9](#_Toc167620908)

[6.2.3. readData 10](#_Toc167620909)

[6.2.4. startIP 10](#_Toc167620910)

[6.2.5. enableINT 10](#_Toc167620911)

[6.2.6. disableINT 10](#_Toc167620912)

[6.2.7. status 10](#_Toc167620913)

[6.2.8. waitINT 11](#_Toc167620914)

[6.2.9. conv 11](#_Toc167620915)

[7. C DRIVER 11](#_Toc167620916)

[7.1. C driver 11](#_Toc167620917)

[7.2. Driver functions 13](#_Toc167620918)

[7.2.1. id00001001\_init 13](#_Toc167620919)

[7.2.2. id00001001\_writeData 13](#_Toc167620920)

[7.2.3. id00001001\_readData 14](#_Toc167620921)

[7.2.4. id00001001\_startIP 14](#_Toc167620922)

[7.2.5. id00001001\_enableDelay 14](#_Toc167620923)

[7.2.6. id00001001\_disableDelay 14](#_Toc167620924)

[7.2.7. id00001001\_enableINT 15](#_Toc167620925)

[7.2.8. id00001001\_disableINT 15](#_Toc167620926)

[7.2.9. id00001001\_status 15](#_Toc167620927)

[7.2.10. id00001001\_waitINT 15](#_Toc167620928)

## List of figures

[Figure 1.1 IP Convolution connected to a host 1](#_Toc167620943)

[Figure 5.1 IP Convolution status register 6](#_Toc167620944)

[Figure 5.2 Configuration size register. 7](#_Toc167620945)

## List of tables

[Table 1 IP Convolution input/output signal description 4](#_Toc167620950)

# INPUT/OUTPUT SIGNAL DESCRIPTION

Table 1 IP Convolution input/output signal description

|  |  |  |  |
| --- | --- | --- | --- |
| Signal | Bitwidth | Direction | Description |
| **General signals** | | | |
| clk | 1 | Input | System clock |
| rst\_a | 1 | Input | Asynchronous system reset, low active |
| en\_s | 1 | Input | Enables the IP Core functionality |
| **AIP Interface** | | | |
| data\_in | 32 | Input | Input data for configuration and processing |
| data\_out | 32 | Output | Output data for processing results and status |
| conf\_dbus | 5 | Input | Selects the bus configuration to determine the information flow from/to the IP Core |
| write | 1 | Input | Write indication, data from the data\_in bus will be written into the AIP Interface according to the conf\_dbus value |
| read | 1 | Input | Read indication, data from the AIP Interface will be read according to the conf\_dbus value. The data\_out bus shows the new data read. |
| start | 1 | Input | Initializes the IP Core process |
| int\_req | 1 | Output | Interruption request. It notifies certain events according to the configurated interruption bits. |
| **Core signals** | | | |
|  |  |  |  |
|  |  |  |  |

# THEORY OF OPERATION

Introduction to convolution

Convolution is a mathematical operation that combines two functions to describe the overlap between them. Convolution takes two functions, "slides" one over the other, multiplies the values of the functions at all points of overlap, and adds the products to create a new function. This process creates a new function that represents how the two original functions interact with each other.

Formally, the convolution is an integral that expresses the amount of overlap of a function, f(t)

when it is shifted over another function, g(t)

(f∗g)(t)≈def∫∞−∞f(τ)g(t−τ)dr

Depending on the application of convolution, functions can be replaced with signals, images, or other types of data. Convolution and its applications can be implemented in several ways.

Input Matrix:

This is the matrix on which the convolution will be performed. In image processing, this matrix represents the image in the form of pixels.

Kernel (Filter):

A kernel is a small matrix that slides over the input matrix. Each kernel position produces a value in the output matrix based on a dot product operation between the elements of the kernel and the elements of the input matrix it covers.

Output Matrix:

The resulting matrix after applying the convolution operation. Each element of the output matrix is the result of the dot product of the kernel with a submatrix of the input matrix.

# AIP interface registers and memories description

## Status register

Config: STATUS

Size: 32 bits

Mode: Read/Write.

This register is divided in 3 sections, see Figure 5.1:

* **Status Bits**: These bits indicate the current state of the core.
* **Interruption Flags:** These bits are used to generate an interruption request in the *int\_req* signal of the AIP interface.
* **Mask Bits**: Each one of these bits can enable of disable the interruption flags.



Figure 5.1 IP Convolution status register

Bits 31:24 – Reserved, must be kept cleared.

Bits 23:17 – Reserved Mask Bits for future use and must be kept cleared.

Bit 16 – **MSK:** mask bit for the DN (Done) interruption flag. If it is required to enable the DN interruption flag, this bit must be written to 1.

Bits 15:9 – Reserved Status Bits for future use and are read as 0.

Bit 8 – **BSY**: status bit “**Busy**”.

Reading this bit indicates the current IP Dummy state:

0: The IP Dummy is not busy and ready to start a new process.

1: The IP Dummy is busy, and it is not available for a new process.

Bits 7:1 – Reserved Interrupt/clear flags for future use and must be kept cleared.

Bit 0 – **DN**: interrupt/clear flag “**Done**”

Reading this bit indicates if the IP Dummy has generated an interruption:

0: interruption not generated.

1: the IP Dummy has successfully finished its processing.

Writing this bit to 1 will clear the interruption flag DN.

## Configuration delay register

Config: Csize

Size: 32 bits

Mode: Write

This register is used to configure the X and Y memory sizes before the core starts convolving them. See Figure 5.2

Tabla

Descripción generada automáticamente

Figure 5.2 Configuration size register.

Bits 9:5 – **SizeY:** size value. The size value can be any value in the range 0x00001-0xFFFF.

Bit 4:0 – **SizeX:** size value. The size value can be any value in the range 0x00001-0xFFFF.

## Input data memory

Config: MdataX

Size: 32 bits

Mode: Write

This memory is used to store data to be processed by the IP Convolution core.

Config: MdataY

Size: 32 bits

Mode: Write

This memory is used to store data to be processed by the IP Convolution core.

## Output data memory

Config: MdataZ

Size: 64 bits

Mode: Read

This memory is used to store processed data by the IP Convolution. After the IP Convolution completes its processing, the data stored in this memory will be the same as the input data memory.

# PYTHON DRIVER

The file *id00001001.py* contains the convolution class definition. This class is used to control the IP Convolution core for python applications.  
This Python code aims to interact with a hardware device that uses the pyaip protocol to read and write data, start processes, and check their status. Let's see how it accomplishes this in an organized fashion:

The code imports the libraries needed to communicate with the device via the pyaip protocol.

The connection parameters are set, including the port, the network address of the device and the location of a configuration file (possibly device-specific). Initialize communication with the device using the pyaip\_init function. The device is reset using the aip.reset() function.

The device identifier (ID) is read and displayed. The device status (STATUS) is read and displayed.

An example data set (MemX and MemY) is defined. The data is written to the device memory at locations MdataX and MdataY using the aip.writeMem function. The code also displays the written contents.

A sample configuration size (Size) is defined.

The size is written to the device configuration register Csize using the aip.writeConfReg function. The code also displays the written content.

The process is started on the device with the aip.start() function.

The device status (STATUS) is read back and displayed on the screen.

10 bytes of data are read from the device memory at location MdataZ using the aip.readMem function. The code also displays the content read.

## Usage example

In the following code a basic test of the IP Convolution core is presented. First, it is required to create an instance of the convolution object class. The constructor of this class requires the network address and port where the IP Convolution is connected, the communication port, and the path where the configs csv file is located. Thus, the communication with the IP Convolution will be ready. In this code, the inputs memories are written with array X and array Y by using the writeData method. Then the startIP method is used to start core processing. Finally, the waitINT method is used to wait the activation of the DONE flag, and after that, the output data is read with the readData method.

|  |
| --- |
| **import** sys**,** random**,** time**,** os  **from** id00001001 **import** dummy  **from** ipdi.ip.pyaip **import** pyaip**,** pyaip\_init**,** Callback  logging**.**basicConfig**(**level**=**logging**.**INFO**)**  connector = '/dev/ttyACM0'  csv\_file = '/home/a/Documents/HDL/ID1000500A\_AlejandroPardo\_LeonelGallo/config/ID1000500A\_config.csv'  addr **=** 1  port **=** 0  aip\_mem\_size **=** 32  X = [0x00000001, 0x00000002, 0x00000003, 0x00000004, 0x00000003, 0x00000007, 0x00000006, 0x0000000A, 0x00000005, 0x00000008]    Y = [0x00000003, 0x00000003, 0x00000005, 0x00000006, 0x00000007]  **try:**  driver = convolution(connector, addr, port, csv\_file)  logging.info("Test Convolution: Driver created")    driver.status()  **except:**  logging**.**error**(**"Test Dummy: Driver not created"**)**  sys**.exit()**  driver.disableINT()    driver.writeData('MdataX', X)  logging.info(f'TX MemX Data: {[f"{x:08X}" for x in X]}')    driver.writeData('MdataY', Y)  logging.info(f'TX MemY Data: {[f"{x:08X}" for x in Y]}')    driver.startIP()  driver.waitInt()    conv\_result = driver.conv(X,Y)  logging.info(f'Convolution result: {[f"{x:08X}" for x in conv\_result]}')    driver.status()  driver.finish()  logging**.**info**(**"The End"**)** |

## Methods

### Constructor

**def** \_\_init\_\_**(**self**,** connector**,** nic\_addr**,** port, csv\_file**):**

Creates an object to control the IP Convolution in the specified network address.

**Parameters:**

* connector (string): Communications port used by the host.
* nic\_addr (int): Network address where the core is connected.
* port (int): Port where the core is connected.
* csv\_file (string): IP Dummy csv file location.

### writeData

**def** writeData **(self, mem\_name, data):**

Write data in the IP Convolution input memory.

**Parameters:**

* data (List[int]): Data to be written.

**Returns:**

* bool An indication of whether the operation has been completed successfully.

### readData

**def** readData **(self, mem\_name, size) :**

Read data from the IP Convolution output memory.

**Parameters:**

* size (int): Communications port used by the host.

**Returns:**

* List[int] Data read from the output memory.

### startIP

**def** startIP**(**self**):**

Start processing in IP Convolution.

**Returns:**

* bool An indication of whether the operation has been completed successfully.

### enableINT

**def** enableINT**(**self**):**

Enable IP Convolution interruptions (bit DONE of the STATUS register).

**Returns:**

* bool An indication of whether the operation has been completed successfully.

### disableINT

**def** disableINT**(**self**):**

Disable IP Convolution interruptions (bit DONE of the STATUS register).

**Returns:**

* bool An indication of whether the operation has been completed successfully.

### status

**def** status**(**self**):**

Show IP Convolution status.

**Returns:**

* bool An indication of whether the operation has been completed successfully.

### waitINT

**def** waitINT**(**self**):**

Wait for the completion of the process.

**Returns:**

* bool An indication of whether the operation has been completed successfully.

### conv

**def** conv**(**self, X, Y**):**

X and Y convolution processing.

**Parameters:**

* X (List[int]): X data for convolution.
* Y (List[int]): Y data for convolution.

**Returns:**

* Z(List[int]) result of the convolution.

# C DRIVER

In order to use the C driver, it is required to use the files: *id00001001.h, id00001001.c* that contain the driver functions definition and implementation. The functions defined in this library are used to control the IP Dummy core for C applications.

## C driver

In the following code a basic test of the IP Dummy core is presented.

|  |
| --- |
| #include "caip.h"  #include <stdint.h>  #include <stdio.h>  #include <conio.h>  int main(){  const char \*connector = "/dev/ttyACM0";  uint8\_t nic\_addr = 1;  uint8\_t port = 0;  const char \*csv\_file = "/home/a/Documents/HDL/ID1000500A\_AlejandroPardo\_LeonelGallo/config/ID1000500A\_config.csv";  caip\_t \*aip = caip\_init(connector, nic\_addr, port, csv\_file);  aip->reset();  /\*========================================\*/  /\* Code generated with IPAccelerator \*/  uint32\_t ID[1];  aip->getID(ID);  printf("Read ID: %08X\n\n", ID[0]);  uint32\_t STATUS[1];  aip->getStatus(STATUS);  printf("Read STATUS: %08X\n\n", STATUS[0]);  uint32\_t MemX[6] = {0x00000001, 0x00000002, 0x00000003, 0x00000004, 0x00000003, 0x00000007};  uint32\_t MemX\_size = sizeof(MemX) / sizeof(uint32\_t);  printf("Write memory: MdataX\n");  aip->writeMem("MdataX", MemX, 6, 0);  printf("MemX Data: [");  for(int i=0; i<MemX\_size; i++){  printf("0x%08X", MemX[i]);  if(i != MemX\_size-1){  printf(", ");  }  }  printf("]\n\n");  uint32\_t MemY[5] = {0x00000003, 0x00000003, 0x00000005, 0x00000006, 0x00000007};  uint32\_t MemY\_size = sizeof(MemY) / sizeof(uint32\_t);  printf("Write memory: MdataY\n");  aip->writeMem("MdataY", MemY, 5, 0);  printf("MemY Data: [");  for(int i=0; i<MemY\_size; i++){  printf("0x%08X", MemY[i]);  if(i != MemY\_size-1){  printf(", ");  }  }  printf("]\n\n");  uint32\_t Size[1] = {0x000000A6};  uint32\_t Size\_size = sizeof(Size) / sizeof(uint32\_t);  printf("Write configuration register: Csize\n");  aip->writeConfReg("Csize", Size, 1, 0);  printf("Size Data: [");  for(int i=0; i<Size\_size; i++){  printf("0x%08X", Size[i]);  if(i != Size\_size-1){  printf(", ");  }  }  printf("]\n\n");  printf("Start IP\n\n");  aip->start();  aip->getStatus(STATUS);  printf("Read STATUS: %08X\n\n", STATUS[0]);  uint32\_t MemZ[10];  uint32\_t MemZ\_size = sizeof(MemZ) / sizeof(uint32\_t);  printf("Read memory: MdataZ\n");  aip->readMem("MdataZ", MemZ, 10, 0);  printf("MemZ Data: [");  for(int i=0; i<MemZ\_size; i++){  printf("0x%08X", MemZ[i]);  if(i != MemZ\_size-1){  printf(", ");  }  }  printf("]\n\n");  printf("Clear INT: 0\n");  aip->clearINT(0);  aip->getStatus(STATUS);  printf("Read STATUS: %08X\n\n", STATUS[0]);  /\*========================================\*/  aip->finish();  printf("\n\nPress key to close ... ");  getch();  return 0;  } |

## Driver functions

### id00001001\_init

int32\_t id00001001\_init**(**const char \*connector**,** uint\_8 nic\_addr**,** uint\_8 port, const char \*csv\_file**)**

Configure and initialize the connection to control the IP Dummy in the specified network address.

**Parameters:**

* connector: Communications port used by the host.
* nic\_addr: Network address where the core is connected.
* port: Port where the core is connected.
* csv\_file: IP Dummy csv file location.

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_writeData

int32\_t id00001001\_writeData**(**uint32\_t **\***data**,** uint32\_t data\_size, uint\_8 nic\_addr**,** uint\_8 port**)**

Write data in the IP Dummy input memory.

**Parameters:**

* data: Pointer to the first element to be written.
* data\_size: Number of elements to be written.
* nic\_addr: Network address where the core is connected.
* port: Port where the core is connected.

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_readData

int32\_t id00001001\_readData**(**uint32\_t **\***data**,** uint32\_t data\_size, uint\_8 nic\_addr**,** uint\_8 port**)**

Read data from the IP Dummy output memory.

**Parameters:**

* data: Pointer to the first element where the read data will be stored.
* data\_size: Number of elements to be read.
* nic\_addr: Network address where the core is connected.
* port: Port where the core is connected.

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_startIP

int32\_t id00001001\_startIP**(**uint\_8 nic\_addr**,** uint\_8 port**)**

Start processing in IP Dummy.

**Parameters:**

* nic\_addr: Network address where the core is connected.
* port: Port where the core is connected.

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_enableDelay

int32\_t id00001001\_enableDelay**(**uint\_32 msec, int\_8 nic\_addr**,** uint\_8 port**)**

Set and enable delay in IP Dummy processing.

**Parameters:**

* msec: Number of milliseconds of delay.
* nic\_addr: Network address where the core is connected.
* port: Port where the core is connected.

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_disableDelay

int32\_t id00001001\_disableDelay**(**int\_8 nic\_addr**,** uint\_8 port**)**

Disable delay in IP Dummy processing.

**Parameters:**

* nic\_addr: Network address where the core is connected.
* port: Port where the core is connected.

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_enableINT

int32\_t id00001001\_enableINT**(**int\_8 nic\_addr**,** uint\_8 port**)**

Enable IP Dummy interruptions (bit DONE of the STATUS register).

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_disableINT

int32\_t id00001001\_disableINT**(**int\_8 nic\_addr**,** uint\_8 port**)**

Disable IP Dummy interruptions (bit DONE of the STATUS register).

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_status

int32\_t id00001001\_status**(**int\_8 nic\_addr**,** uint\_8 port**)**

Show IP Dummy status.

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.

### id00001001\_waitINT

int32\_t id00001001\_status**(**int\_8 nic\_addr**,** uint\_8 port**)**

Wait for the completion of the process.

**Returns:**

* int32\_t Return 0 whether the function has been completed successfully.