

# **INPUT-OUTPUT ORGANIZATION**

- **Peripheral Devices**
- **Input-Output Interface**
- **Asynchronous Data Transfer**
- **Modes of Transfer**
- **Priority Interrupt**
- **Direct Memory Access**
- **Input-Output Processor**
- **Serial Communication**

# PERIPHERAL DEVICES

## Input Devices

- Keyboard
- Optical input devices
  - Card Reader
  - Paper Tape Reader
  - Bar code reader
  - Digitizer
  - Optical Mark Reader
- Magnetic Input Devices
  - Magnetic Stripe Reader
- Screen Input Devices
  - Touch Screen
  - Light Pen
  - Mouse
- Analog Input Devices

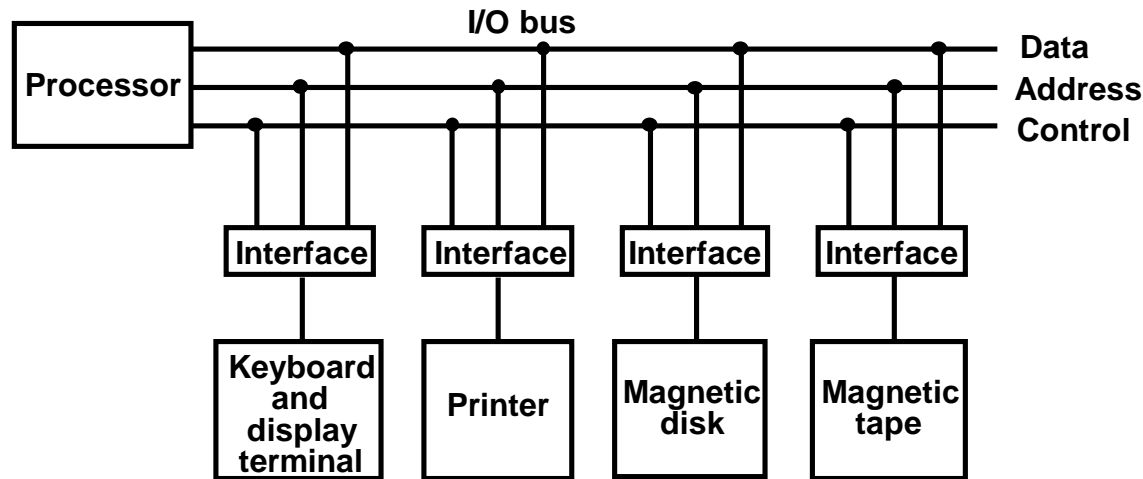
## Output Devices

- Card Puncher, Paper Tape Puncher
- CRT
- Printer (Impact, Ink Jet, Laser, Dot Matrix)
- Plotter
- Analog
- Voice

# INPUT/OUTPUT INTERFACE

- Provides a method for transferring information between internal storage (such as memory and CPU registers) and external I/O devices
- Resolves the *differences* between the computer and peripheral devices
  - Peripherals - Electromechanical Devices
  - CPU or Memory - Electronic Device
  - Data Transfer Rate
    - » Peripherals - Usually slower
    - » CPU or Memory - Usually faster than peripherals
      - Some kinds of Synchronization mechanism may be needed
  - Unit of Information
    - » Peripherals – Byte, Block, ...
    - » CPU or Memory – Word
  - Data representations may differ

# I/O BUS AND INTERFACE MODULES



Each peripheral has an interface module associated with it

## Interface

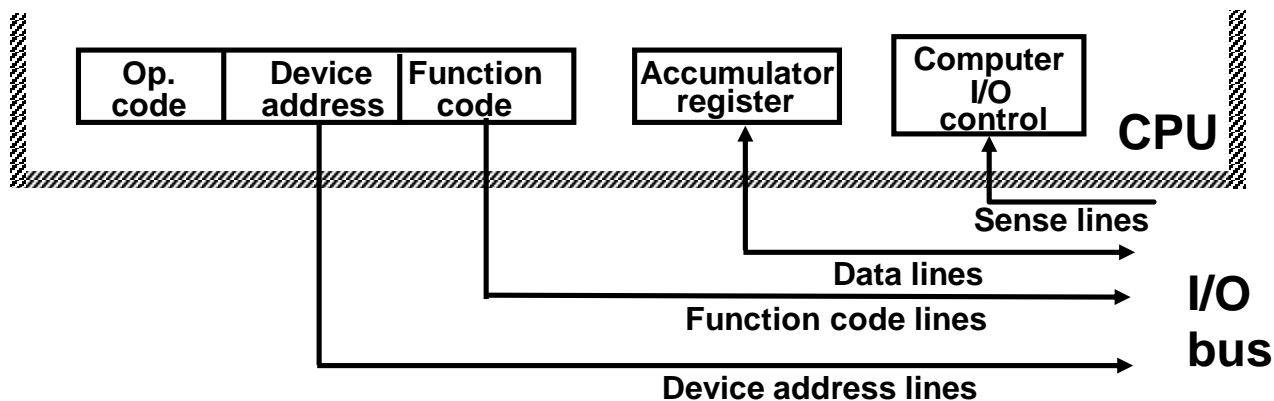
- Decodes the device address (device code)
- Decodes the commands (operation)
- Provides signals for the peripheral controller
- Synchronizes the data flow and supervises the transfer rate between peripheral and CPU or Memory

## Typical I/O instruction

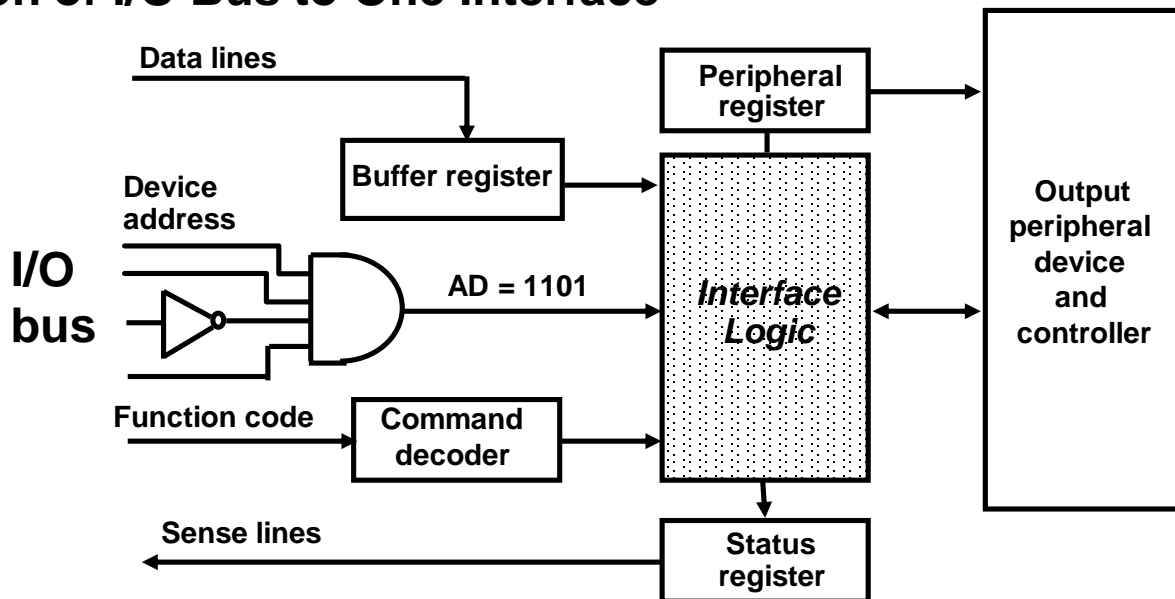


# CONNECTION OF I/O BUS

## Connection of I/O Bus to CPU



## Connection of I/O Bus to One Interface



# I/O BUS AND MEMORY BUS

## Functions of Buses

- \* **MEMORY BUS** is for information transfers between CPU and the MM
- \* **I/O BUS** is for information transfers between CPU and I/O devices through their I/O interface

## Physical Organizations

- \* Many computers use a common single bus system for both memory and I/O interface units
  - Use one common bus but separate control lines for each function
  - Use one common bus with common control lines for both functions
- \* Some computer systems use two separate buses, one to communicate with memory and the other with I/O interfaces

## I/O Bus

- Communication between CPU and all interface units is via a common I/O Bus
- An interface connected to a peripheral device may have a number of *data registers*, a *control register*, and a *status register*
- A command is passed to the peripheral by sending to the appropriate interface register
- Function code and sense lines are not needed (Transfer of data, control, and status information is always via the common I/O Bus)

# ISOLATED vs MEMORY MAPPED I/O

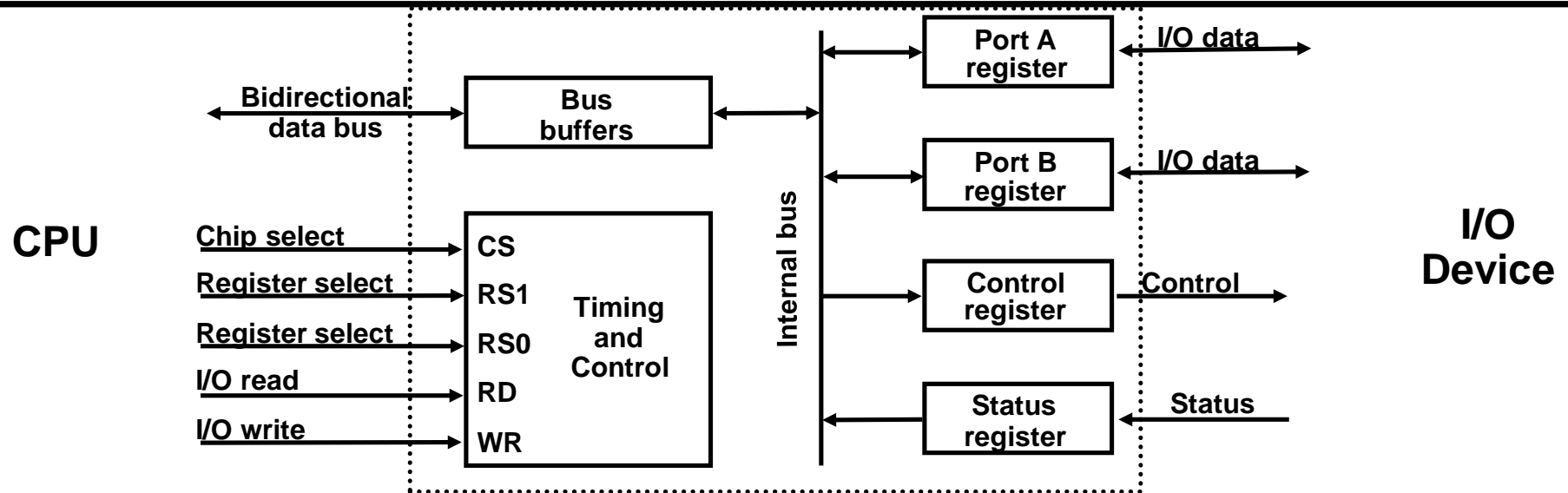
## Isolated I/O

- Separate I/O read/write control lines in addition to memory read/write control lines
- Separate (isolated) memory and I/O address spaces
- Distinct input and output instructions

## Memory-mapped I/O

- A single set of read/write control lines  
(no distinction between memory and I/O transfer)
- Memory and I/O addresses share the common address space
  - > reduces memory address range available
- No specific input or output instruction
  - > The same memory reference instructions can be used for I/O transfers
- Considerable flexibility in handling I/O operations

# I/O INTERFACE



CS	RS1	RS0	Register selected
0	x	x	None - data bus in high-impedance
1	0	0	Port A register
1	0	1	Port B register
1	1	0	Control register
1	1	1	Status register

## Programmable Interface

- Information in each port can be assigned a meaning depending on the mode of operation of the I/O device  
→ **Port A = Data; Port B = Command; Port C = Status**
- CPU initializes(loads) each port by transferring a byte to the Control Register  
→ Allows CPU can define the mode of operation of each port  
→ **Programmable Port:** By changing the bits in the control register, it is possible to change the interface characteristics



# ASYNCHRONOUS DATA TRANSFER

## Synchronous and Asynchronous Operations

**Synchronous** - All devices derive the timing information from common clock line

**Asynchronous** - No common clock

## Asynchronous Data Transfer

Asynchronous data transfer between two independent units requires that *control signals* be transmitted between the communicating units *to indicate the time at which data is being transmitted*

## Two Asynchronous Data Transfer Methods

### Strobe pulse

- A strobe pulse is supplied by one unit to indicate the other unit when the transfer has to occur

### Handshaking

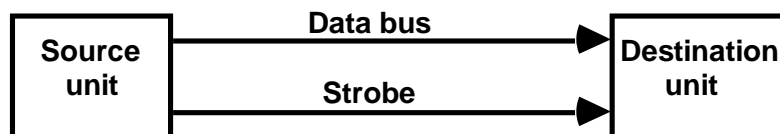
- A control signal is accompanied with each data being transmitted to indicate the presence of data
- The receiving unit responds with another control signal to acknowledge receipt of the data

# STROBE CONTROL

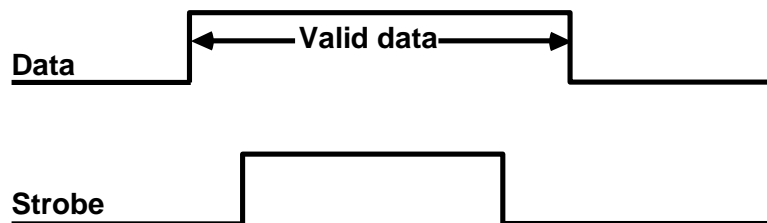
- \* Employs a single control line to time each transfer
- \* The strobe may be activated by either the source or the destination unit

## Source-Initiated Strobe for Data Transfer

### Block Diagram

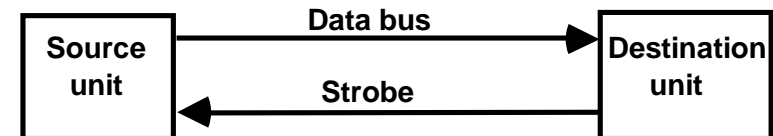


### Timing Diagram

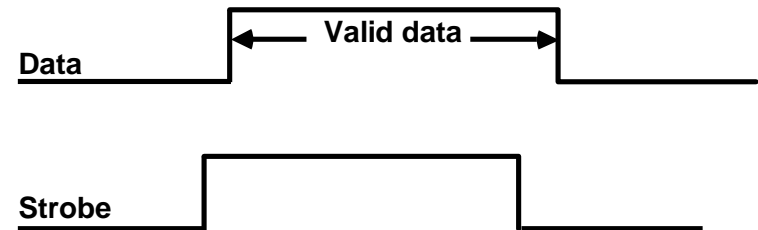


## Destination-Initiated Strobe for Data Transfer

### Block Diagram



### Timing Diagram



# HANDSHAKING

## Strobe Methods

### Source-Initiated

The source unit that initiates the transfer has no way of knowing whether the destination unit has actually received data

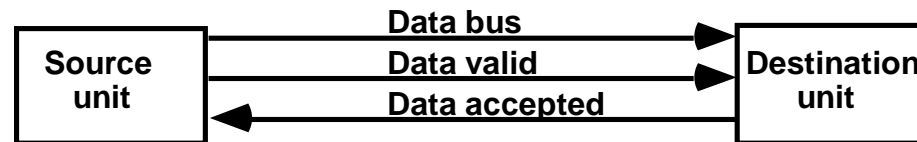
### Destination-Initiated

The destination unit that initiates the transfer has no way of knowing whether the source has actually placed the data on the bus

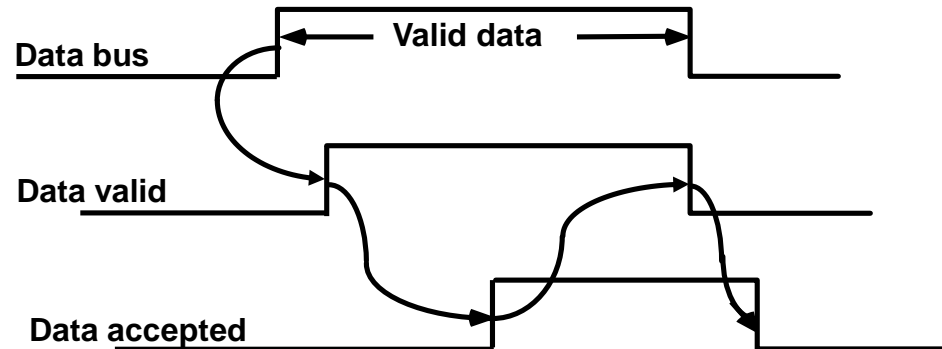
To solve this problem, the *HANDSHAKE* method introduces a second control signal to provide a *Reply* to the unit that initiates the transfer

# SOURCE-INITIATED TRANSFER USING HANDSHAKE

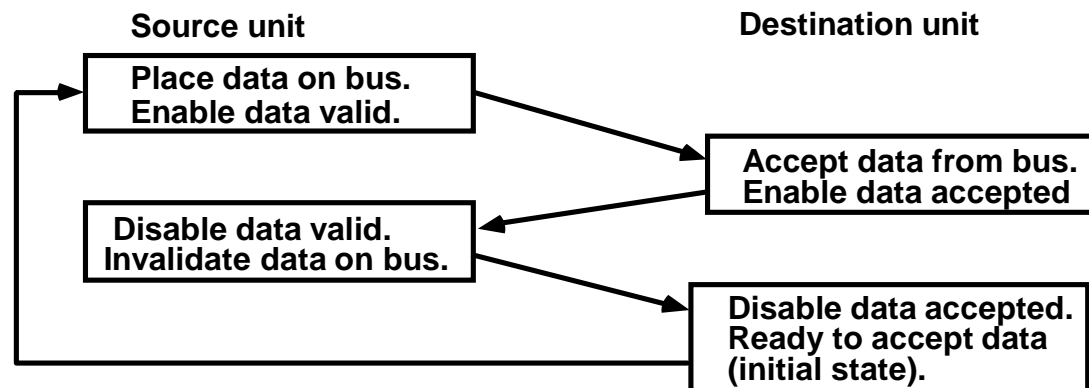
## Block Diagram



## Timing Diagram



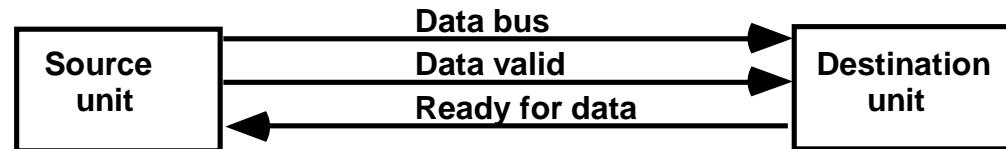
## Sequence of Events



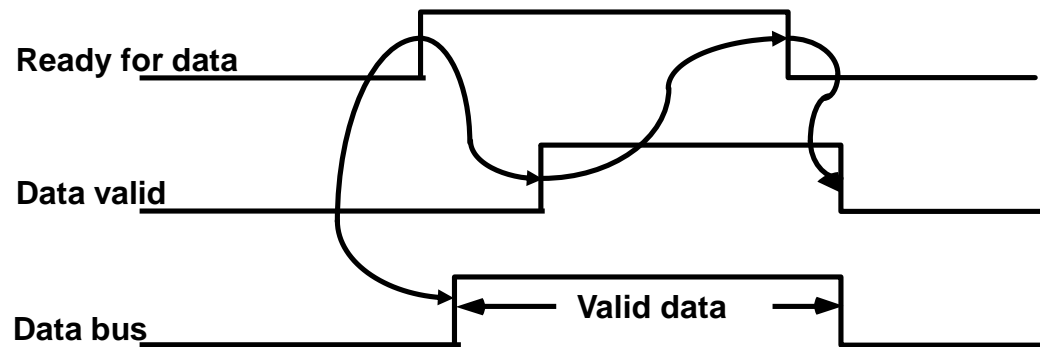
- \* Allows arbitrary delays from one state to the next
- \* Permits each unit to respond at its own data transfer rate
- \* The rate of transfer is determined by the slower unit

# DESTINATION-INITIATED TRANSFER USING HANDSHAKE

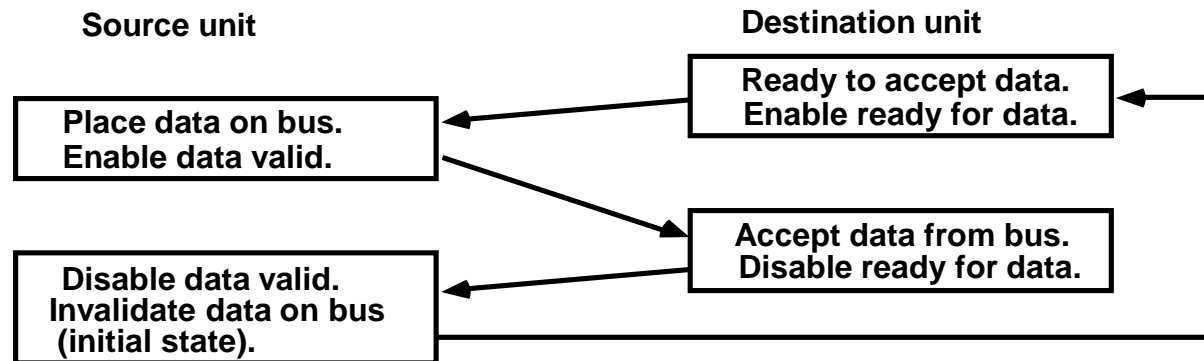
## Block Diagram



## Timing Diagram



## Sequence of Events



- \* Handshaking provides a high degree of flexibility and reliability because the successful completion of a data transfer relies on active participation by both units
- \* If one unit is faulty, data transfer will not be completed  
⇒ Can be detected by means of a *timeout* mechanism

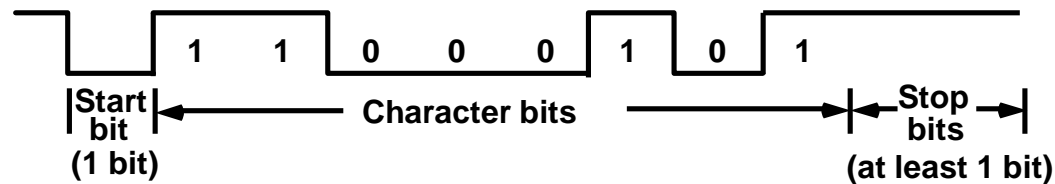
# ASYNCHRONOUS SERIAL TRANSFER

## Four Different Types of Transfer

Asynchronous serial transfer  
Synchronous serial transfer  
Asynchronous parallel transfer  
Synchronous parallel transfer

## Asynchronous Serial Transfer

- Employs special bits which are inserted at both ends of the character code
- Each character consists of three parts; Start bit; Data bits; Stop bits.



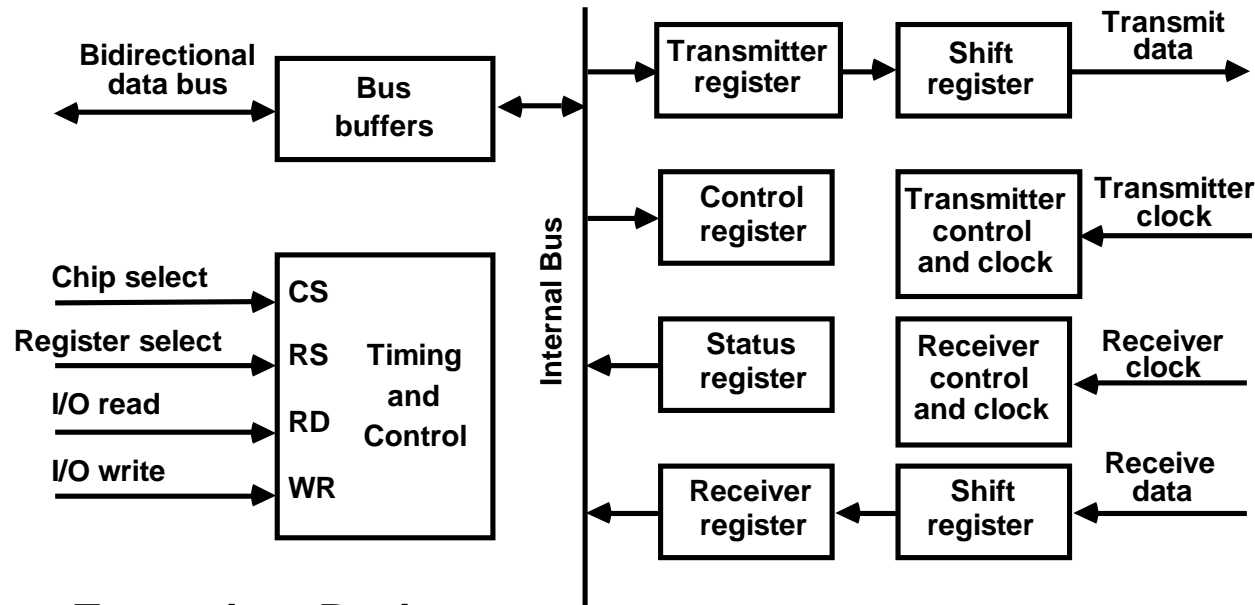
A character can be detected by the receiver from the knowledge of 4 rules;

- When data are not being sent, the line is kept in the 1-state (idle state)
- The initiation of a character transmission is detected by a **Start Bit**, which is always a 0
- The character bits always follow the **Start Bit**
- After the last character, a **Stop Bit** is detected when the line returns to the 1-state for at least 1 bit time

The receiver knows in advance the transfer rate of the bits and the number of information bits to expect

# UNIVERSAL ASYNCHRONOUS RECEIVER-TRANSMITTER - UART -

A typical asynchronous communication interface available as an IC



CS	RS	Oper.	Register selected
0	x	x	None
1	0	WR	Transmitter register
1	1	WR	Control register
1	0	RD	Receiver register
1	1	RD	Status register

## Transmitter Register

- Accepts a data byte (from CPU) through the data bus
- Transferred to a shift register for serial transmission

## Receiver

- Receives serial information into another shift register
- Complete data byte is sent to the receiver register

## Status Register Bits

- Used for I/O flags and for recording errors

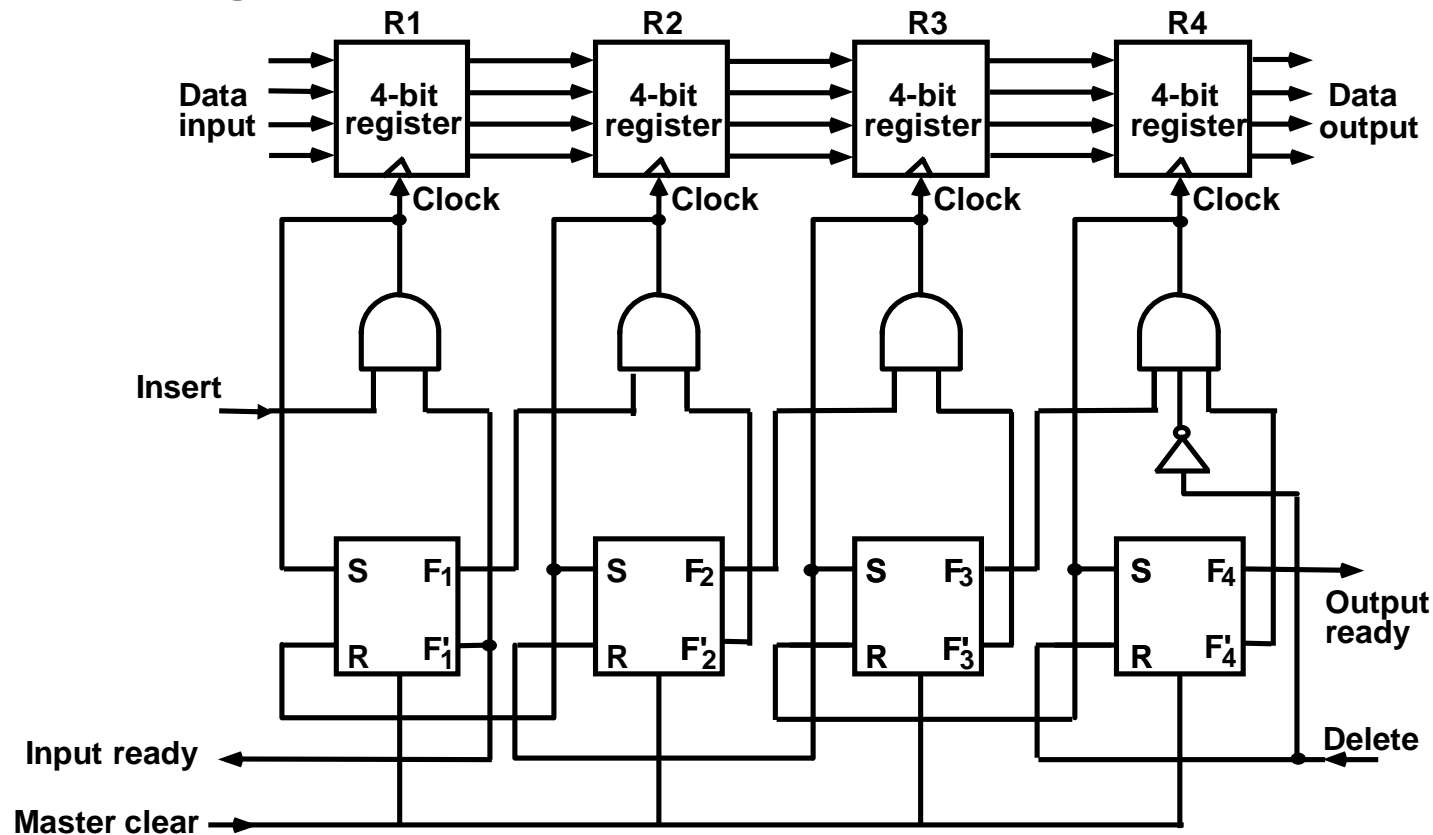
## Control Register Bits

- Define baud rate, no. of bits in each character, whether to generate and check parity, and no. of stop bits

# FIRST-IN-FIRST-OUT(FIFO) BUFFER

- \* Input data and output data at two different rates
- \* Output data are always in the same order in which the data entered the buffer.
- \* Useful in some applications when data is transferred asynchronously

4 x 4 FIFO Buffer (4 4-bit registers  $R_i$ ),  
4 Control Registers(flip-flops  $F_i$ , associated with each  $R_i$ )



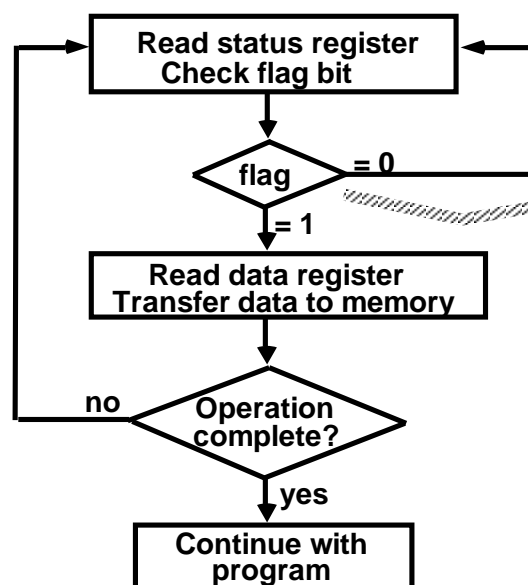
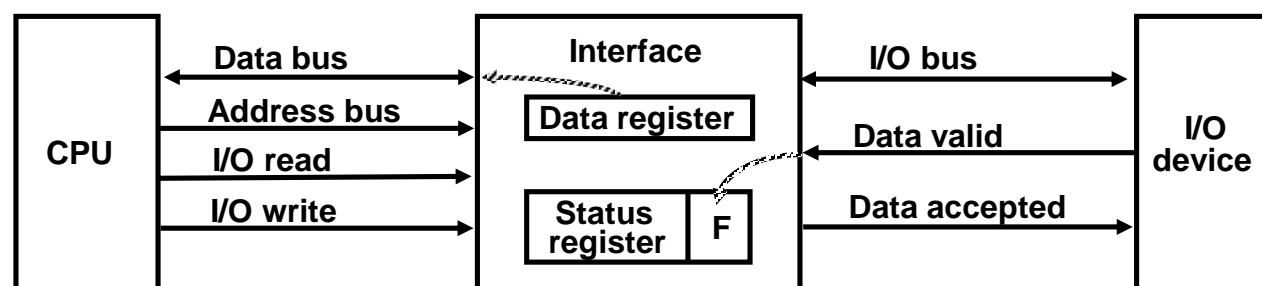


# MODES OF TRANSFER - PROGRAM-CONTROLLED I/O -

3 different Data Transfer Modes between the central computer(CPU or Memory) and peripherals;

Program-Controlled I/O  
Interrupt-Initiated I/O  
Direct Memory Access (DMA)

## Program-Controlled I/O(Input Dev to CPU)



### Polling or Status Checking

- Continuous CPU involvement
- CPU slowed down to I/O speed
- Simple
- Least hardware

## **MODES OF TRANSFER - INTERRUPT INITIATED I/O & DMA**

### **Interrupt Initiated I/O**

- Polling takes valuable CPU time
- Open communication only when some data has to be passed -> *Interrupt*.
- I/O interface, instead of the CPU, monitors the I/O device
- When the interface determines that the I/O device is ready for data transfer, it generates an *Interrupt Request* to the CPU
- Upon detecting an interrupt, CPU stops momentarily the task it is doing, branches to the service routine to process the data transfer, and then returns to the task it was performing

### **DMA (Direct Memory Access)**

- Large blocks of data transferred at a high speed to or from high speed devices, magnetic drums, disks, tapes, etc.
- DMA controller  
Interface that provides I/O transfer of data directly to and from the memory and the I/O device
- CPU initializes the DMA controller by sending a memory address and the number of words to be transferred
- Actual transfer of data is done directly between the device and memory through DMA controller  
-> Freeing CPU for other tasks

# PRIORITY INTERRUPT

## Priority

- Determines which interrupt is to be served first when two or more requests are made simultaneously
- Also determines which interrupts are permitted to interrupt the computer while another is being serviced
- Higher priority interrupts can make requests while servicing a lower priority interrupt

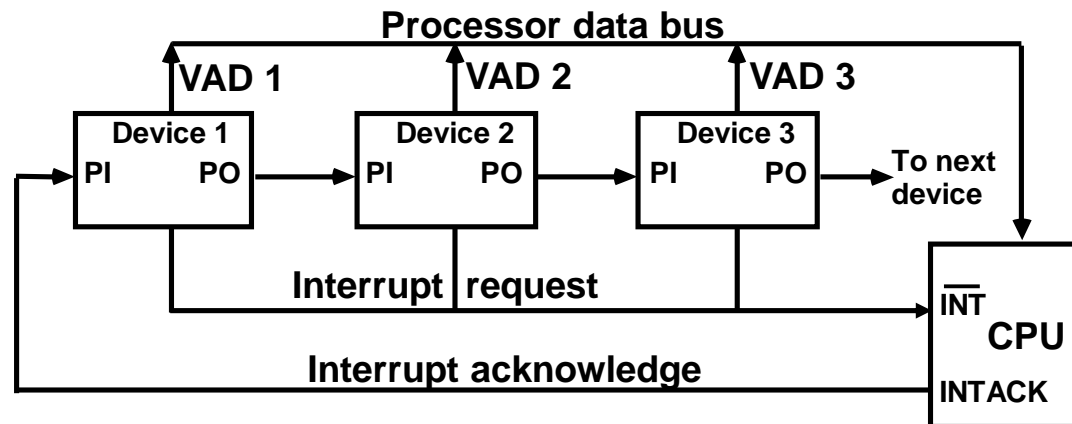
## Priority Interrupt by Software(Polling)

- Priority is established by the order of polling the devices(interrupt sources)
- Flexible since it is established by software
- Low cost since it needs a very little hardware
- Very slow

## Priority Interrupt by Hardware

- Require a priority interrupt manager which accepts all the interrupt requests to determine the highest priority request
- Fast since identification of the highest priority interrupt request is identified by the hardware
- Fast since each interrupt source has its own interrupt vector to access directly to its own service routine

# HARDWARE PRIORITY INTERRUPT - DAISY-CHAIN -



- \* Serial hardware priority function
- \* Interrupt Request Line
  - Single common line
- \* Interrupt Acknowledge Line
  - Daisy-Chain

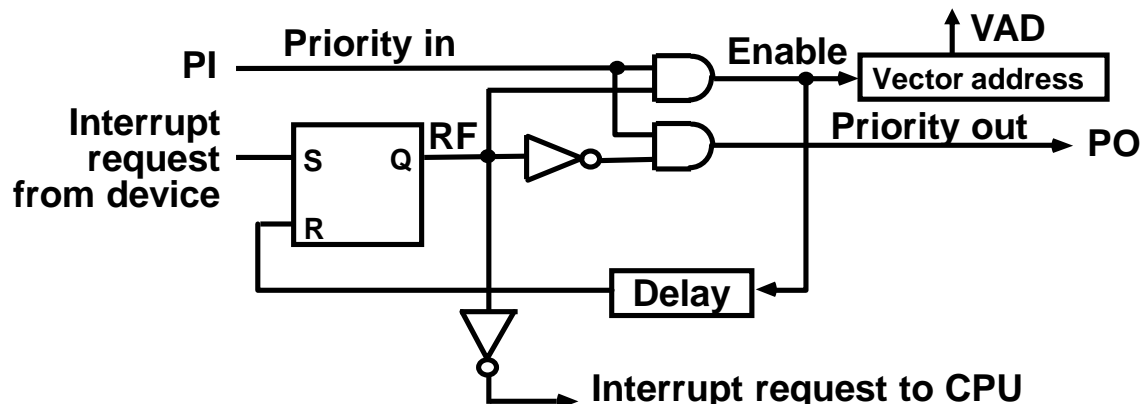
Interrupt Request from any device( $\geq 1$ )

-> CPU responds by INTACK <- 1

-> Any device receives signal(INTACK) 1 at PI puts the VAD on the bus

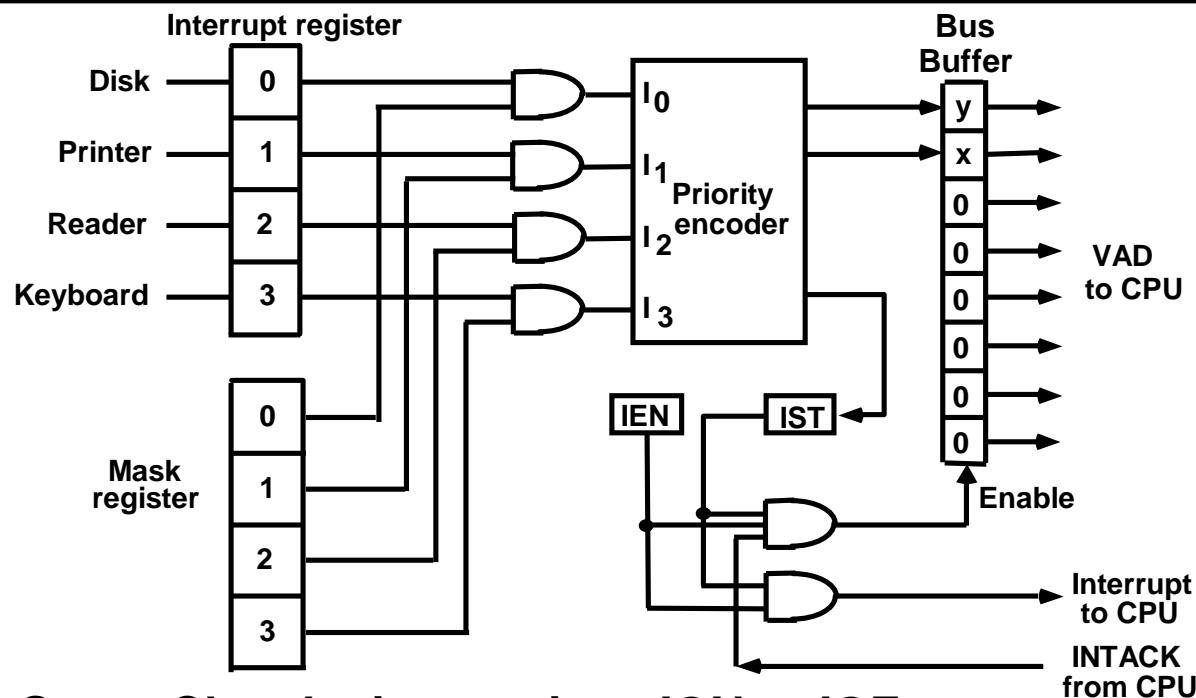
Among interrupt requesting devices the only device which is physically closest to CPU gets INTACK=1, and it blocks INTACK to propagate to the next device

One stage of the daisy chain priority arrangement



PI	RF	PO	Enable
0	0	0	0
0	1	0	0
1	0	1	0
1	1	0	1

# PARALLEL PRIORITY INTERRUPT



**IEN:** Set or Clear by instructions ION or IOF

**IST:** Represents an unmasked interrupt has occurred. INTACK enables tristate Bus Buffer to load VAD generated by the Priority Logic

**Interrupt Register:**

- Each bit is associated with an Interrupt Request from different Interrupt Source - different priority level
- Each bit can be cleared by a program instruction

**Mask Register:**

- Mask Register is associated with Interrupt Register
- Each bit can be set or cleared by an Instruction

# INTERRUPT PRIORITY ENCODER

Determines the highest priority interrupt when more than one interrupts take place

Priority Encoder Truth table

Inputs				Outputs			Boolean functions
$I_0$	$I_1$	$I_2$	$I_3$	x	y	IST	
1	d	d	d	0	0	1	$x = I_0' \cdot I_1'$ $y = I_0' \cdot I_1 + I_0' \cdot I_2'$ $(IST) = I_0 + I_1 + I_2 + I_3$
0	1	d	d	0	1	1	
0	0	1	d	1	0	1	
0	0	0	1	1	1	1	
0	0	0	0	d	d	0	

# INTERRUPT CYCLE

**At the end of each Instruction cycle**

- CPU checks IEN and IST**
- If  $IEN \bullet IST = 1$ , CPU  $\rightarrow$  Interrupt Cycle**

<b><math>SP \leftarrow SP - 1</math></b>	<b>Decrement stack pointer</b>
<b><math>M[SP] \leftarrow PC</math></b>	<b>Push PC into stack</b>
<b><math>INTACK \leftarrow 1</math></b>	<b>Enable interrupt acknowledge</b>
<b><math>PC \leftarrow VAD</math></b>	<b>Transfer vector address to PC</b>
<b><math>IEN \leftarrow 0</math></b>	<b>Disable further interrupts</b>
<b>Go To Fetch</b>	<b>to execute the first instruction in the interrupt service routine</b>

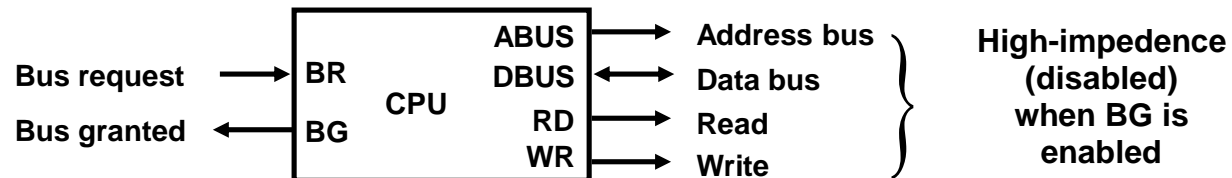




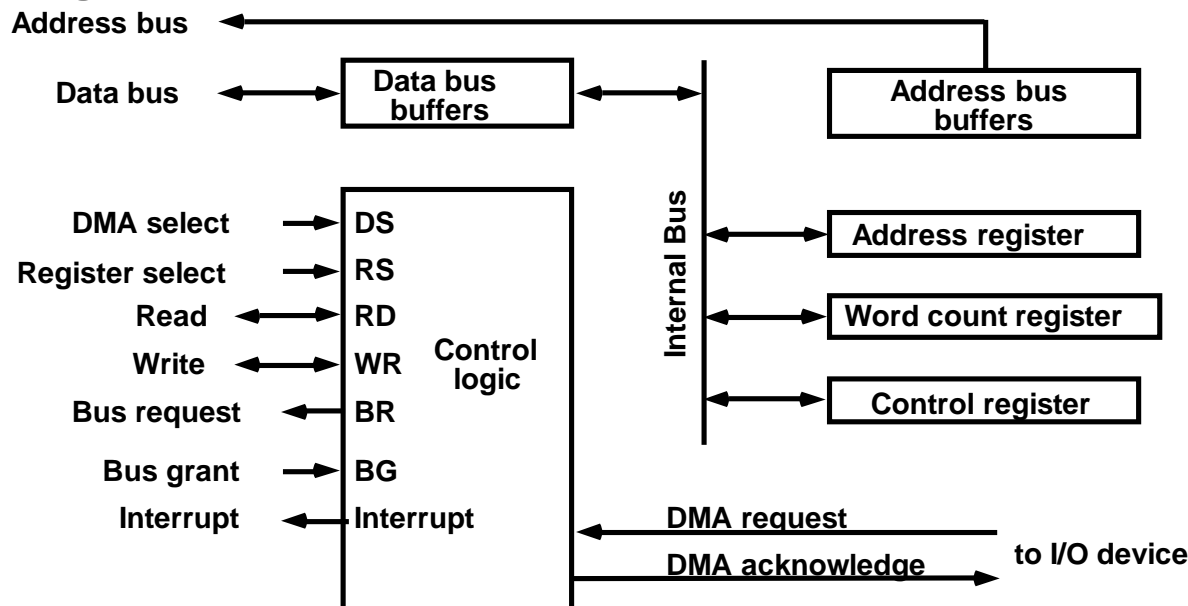
# DIRECT MEMORY ACCESS

- \* Block of data transfer from high speed devices, Drum, Disk, Tape
- \* DMA controller - Interface which allows I/O transfer directly between Memory and Device, freeing CPU for other tasks
- \* CPU initializes DMA Controller by sending memory address and the block size(number of words)

## CPU bus signals for DMA transfer



## Block diagram of DMA controller



## DMA I/O OPERATION

### Starting an I/O

- CPU executes instruction to
  - Load Memory Address Register
  - Load Word Counter
  - Load Function(Read or Write) to be performed
  - Issue a GO command

Upon receiving a GO Command DMA performs I/O operation as follows independently from CPU

### Input

- [1] Input Device  $\leftarrow$  R (Read control signal)
- [2] Buffer(DMA Controller)  $\leftarrow$  Input Byte; and  
assembles the byte into a word until word is full
- [4] M  $\leftarrow$  memory address, W(Write control signal)
- [5] Address Reg  $\leftarrow$  Address Reg + 1; WC(Word Counter)  $\leftarrow$  WC - 1
- [6] If WC = 0, then Interrupt to acknowledge done, else go to [1]

### Output

- [1] M  $\leftarrow$  M Address, R  
M Address R  $\leftarrow$  M Address R + 1, WC  $\leftarrow$  WC - 1
- [2] Disassemble the word
- [3] Buffer  $\leftarrow$  One byte; Output Device  $\leftarrow$  W, for all disassembled bytes
- [4] If WC = 0, then Interrupt to acknowledge done, else go to [1]

# CYCLE STEALING

**While DMA I/O takes place, CPU is also executing instructions**

**DMA Controller and CPU both access Memory -> Memory Access Conflict**

**Memory Bus Controller**

- Coordinating the activities of all devices requesting memory access
- Priority System

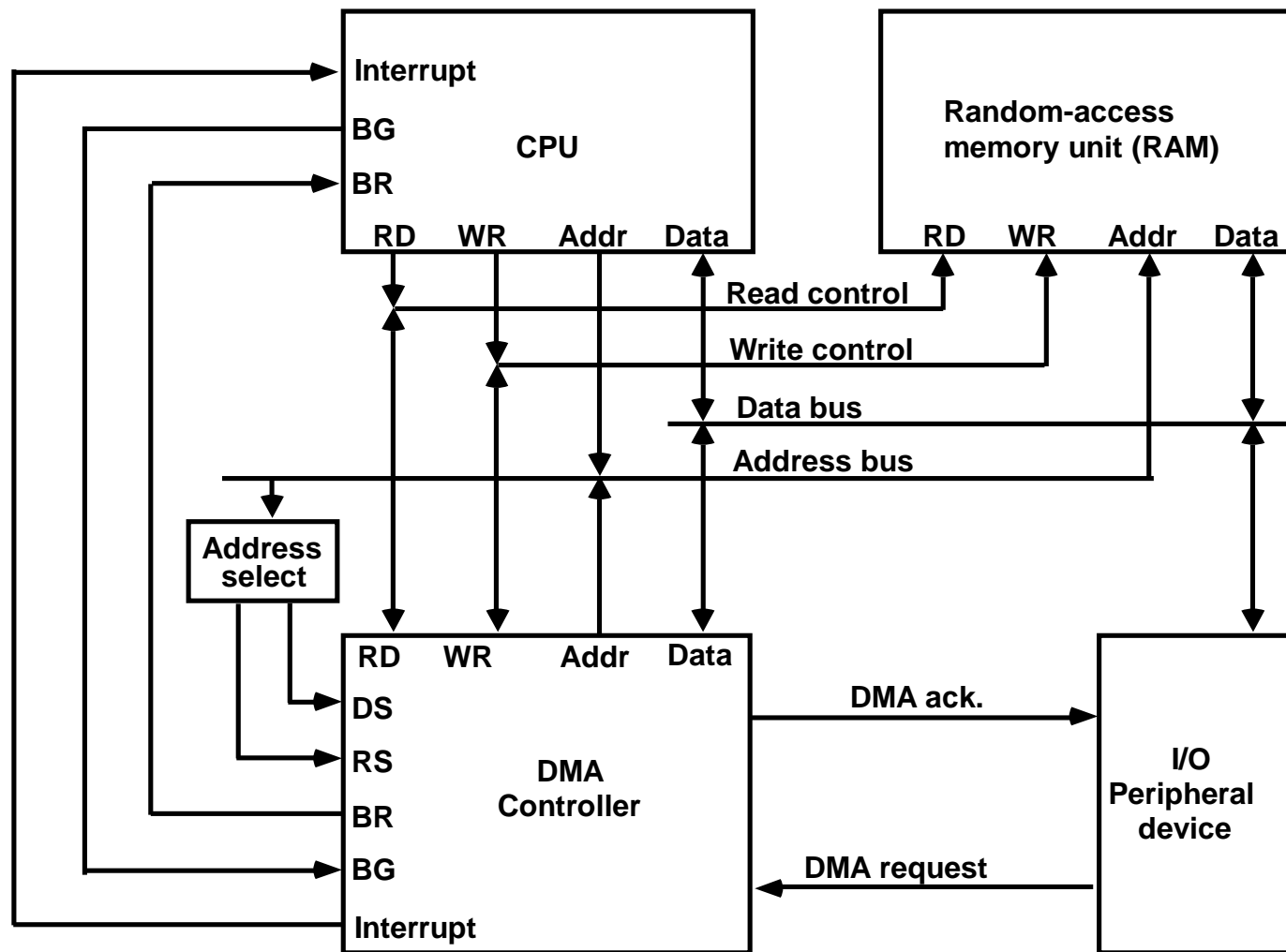
**Memory accesses by CPU and DMA Controller are interwoven,  
with the top priority given to DMA Controller**

**-> Cycle Stealing**

**Cycle Steal**

- CPU is usually much faster than I/O(DMA), thus  
CPU uses the most of the memory cycles
- DMA Controller steals the memory cycles from CPU
- For those stolen cycles, CPU remains idle
- For those slow CPU, DMA Controller may steal most of the memory  
cycles which may cause CPU remain idle long time

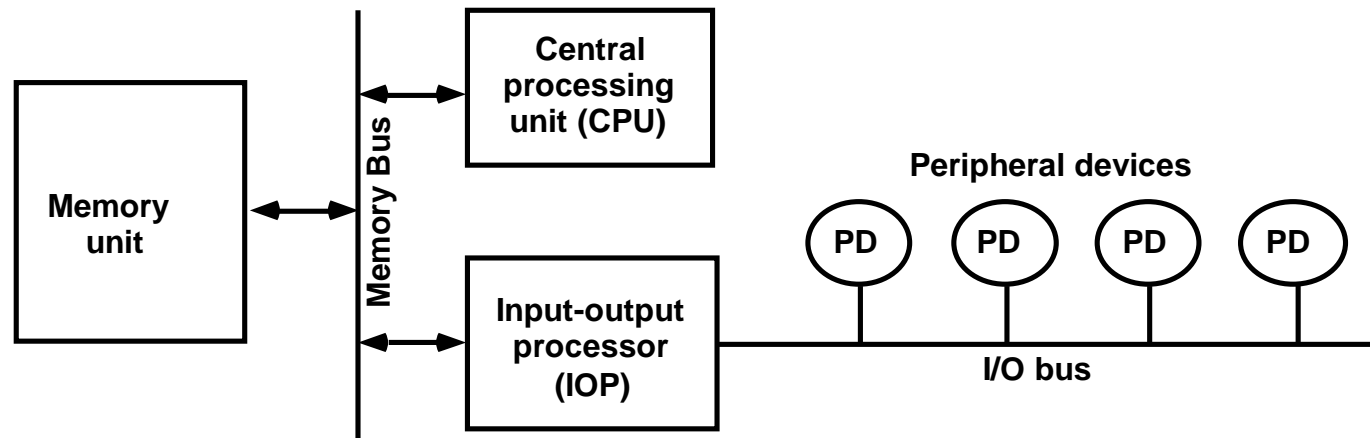
# DMA TRANSFER



# INPUT/OUTPUT PROCESSOR - CHANNEL -

## Channel

- Processor with direct memory access capability that communicates with I/O devices
- Channel accesses memory by cycle stealing
- Channel can execute a Channel Program
  - Stored in the main memory
  - Consists of Channel Command Word(CCW)
  - Each CCW specifies the parameters needed by the channel to control the I/O devices and perform data transfer operations
- CPU initiates the channel by executing an channel I/O class instruction and once initiated, channel operates independently of the CPU



# CHANNEL / CPU COMMUNICATION

