GLYCH

Team: The FreqZ

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**Application**

GLYCH is a four player third-person shooter game inside a maze. It is a game of elimination, meaning the last player remaining wins. The game begins by loading maze onto the screen and each of the four players being placed into one of the four corners of the screen. Each player will be a different color stick figure to allow the players to identify their character on the screen. When the game begins the players will navigate through the maze to eliminate other players by firing lasers. The rules of the game prohibit shooting through walls, and shooting in the north and south directions of the screen, allowing for only horizontal attacks. When two players are on the same level, and no wall separates them, they are poised for attack. When this occurs, if a player is hit by a laser, the player is eliminated and the character will no longer display on the screen. The game continues until only on player is left on the screen.

Audio effects will enhance the game by alerting a player when a laser had been fired, and termination effects being sounded when a player has been hit by a laser.

**Proposed Modifications to the ISA**

The main modification to be made to the provided ISA is to change the processor to a 32-bit processor. In this sense, we will ensure ample memory space with the possibility of accessing cellularRAM if necessary, and compress the amount of instructions required for our processor through the use of 32-bit registers.

**I/O**

The input and output required by this application will be:

1. VGA Display
2. 4 NES gaming controllers
3. Speakers

The VGA Display will be Glyph based to minimize memory consumption.

The NES gaming controllers will provide user the ability to interact with the application and will be used to play the game.

The sound will be provided through a music synthesizer written in Verilog, which can then be outputted to a speaker through a PMOD connector to the NEXYS board.

**Assembler Plan**

The assembler will be written in Python. The application will be written by using commas to separate both instructions, registers, immediate values, and comments, to allow for easy parsing.

**Team Responsibilities**

The project will be broken up into four parts with both lead roles and backup roles for each one as follows:

|  |  |  |
| --- | --- | --- |
| **Team Member** | **Lead Role** | **Backup Role** |
| Steven Brown | Application | Processor |
| Travis Gray | I/O | Assembler |
| Matthew Humphries | Processor | Application |
| Mark Stacey | Assembler | I/O |

**Assembler:**

The Assembler is a python script that reads in a coma separated value (CSV) configuration file and a CSV assembly code file. The configuration file contains information specific to the assembly of each instruction. Writing the assembler in this way makes it easy to parse. It also works across all platforms. The information from the configuration file is used by the assembler to assembly each line of assembly code into 32 bit binary instructions. Once the code has been assembled it is saved in a .dat file with the same name as the assembly code file. In order to run the assembler ensure that python is installed on your computer. Then assembler may be run from the command line by changing the directory to the directory containing the assembler, configuration file and the code file. Then type in the name of the assembler, “AssembleTitan.py”, into the command line and hit enter. It may also be run as an executable in windows by double clicking the file.

The assembler is set up to assemble three different types of instructions r-type, i-type, and j-type instructions. Each instruction is 32 bits long with a 4 bit operation (op) code. After the operation code the rest of the bits are decoded depending on the type of instruction that is specified in the op code.

R-type instructions include a 4 bit op code followed by three 5 bit register codes. The first register code is the destination register (Rd). The next two registers are source registers Rs and Rt. The last 4 bits specify a function code that determines the operation of the instruction in combination with the op code. In r-type instructions the ALU operations happen on Rs and Rt. Then the result of the ALU operation is stored into Rd

R-type Instruction [ Op][ Rd ][ Rs ][ Rt ][ 9’b0][ Func(4bit) ]

I -Type instructions include a 4 bit op code followed by two 5 bit register codes. The first register code is the destination register (Rd). The second is the source register Rs. The remaining 18 bits are used as an immediate value. In i-type instructions the ALU operation happens between Rs and the immediate value.

Then the result of the ALU operation is stored back into Rd.

I-type Instruction [ Op][ Rd ][ Rs ][ Immediate Value ]

J-Type instructions include only a 4bit op code and a 28 bit immediate value. The immediate value is the address of the next instruction that will be executed. The program counter will be set to the value of the immediate and then continue normally from that point.

j-type Instruction [ Op][ Jump Address Immediate Value ]

The Assembler is written in Python. Inside the assembler the data path to a configuration file and an assembly code file are specified. Both of these files are written in coma separated value (CSV) format to make parsing the files easier. Firs the assembler reads in the configuration file. The configuration file provides information about op codes and register encoding. The first value on each line designates the line as an op code or register encoding. Empty lines and comments beginning will // are ignored.

For op codes the remaining values specify in order the type, instruction name, op code, and for r-type instructions the function code.

op,rtype,add,0000,0101

op,itype,addi,1010

op,jtype,j,1101

Lines where the first value is reg specify register encoding. After the first value the register name is specified followed by its encoding.

reg,r1,00001

Each op code line is stored into an array then that array is stored into a large array called ‘op’ inside of the assembler. This array contains all of the information required for assembling each instruction except for the specific encoding for each register. The register information is stored into a python dictionary called ‘reg’. Each entry in reg is the register name with the definition equal to the register encoding. Once ‘reg’ and ‘op’ are populated the assembler is prepared to read in the code file and begin assembly.

When the code file is read into the assembler empty lined and comments are ignored just as in the configuration file. Then the code is assembled line by line. The first value in the line is checked to see if it is a label. If it is then the label is store in a dictionary labels where the definition is an 28 bit binary number represents the value of the program counter (PC) at that point. The value of the PC is stored in a second dictionary called addresses, where the definition for each label is the value of the PC as an integer value. These are used later on to finish the encoding for jumps and branches. If the line is and instruction and not a label then the assembler proceeds to assemble the instruction.

To assembly each institution the op code, type, and (if necessary) the function code are determined. Then the assembly for each instruction is determined by its type. Each instruction is assembled by concatenating the op code with the register encodings and the immediate value or the function code.

Then the assembled instruction is appended to an array that contains the assembled instructions in order. Finally the PC is incremented for the next instruction.

Once the Assembly is complete the assembler loops through the array of assembled instructions. Every time a label is encountered the label is replaced with the encoding from the ‘labels’ dictionary.

After the labels are inserted the assembly is complete. The code is written to a .dat file using a CSV writer. This file is ready for use by Xilinx ISE. This completes the assembly of the code into binary instructions.