This application note describes the theory and implementation of GSM channel equalization and channel decoding algorithms using the Freescale MSC8126 Viterbi coprocessor (VCOP). It also examines the theory behind the soft output Viterbi algorithm (SOVA) assisted by the VCOP. Code examples illustrate how the VCOP performs channel equalization and the SOVA algorithm. A set of suggested design practices for VCOP usage is followed by a discussion of the VCOP driver, which provides a simple, easy interface to the VCOP. Examples of driver usage cover GSM equalization, channel decoding, and SOVA. The source code and the header file for the VCOP driver are also presented.
1 Basics of Convolutional Encoding/Decoding

Convolutional coding is a method of transmitting code words consisting of 1/rate symbols affected by data bits instead of transmitting the data bits themselves. Since each data bit is used in more than one code word, the probability of correctly decoding each bit increases. All examples in this document are for an encoder in which rate = 1/2 (two symbols create a code word) and the constraint length is the length of the shift register, \( K = 3 \). Figure 1 shows a pictorial view of such an encoder.

![Convolutional Encoder Diagram](image)

The transmitted bits are mapped from \( \{0, 1\} \) to \( \{1, -1\} \), respectively. The channel adds noise to the transmitted signal, which is generally modeled using additive white gaussian noise (AWGN). This discussion references an example in which the data \( \{1, 0, 0, 1, 1, 0, 0, 0\} \) is transmitted and the last three bits are for flushing the transmitter. Table 1 lists the expected results.

### Table 1. Transitions of the Encoder

<table>
<thead>
<tr>
<th>State of the Encoder</th>
<th>Input Bit</th>
<th>New State of the Encoder</th>
<th>Transmitted Code Word (First, Second)</th>
</tr>
</thead>
<tbody>
<tr>
<td>000</td>
<td>1</td>
<td>100</td>
<td>11</td>
</tr>
<tr>
<td>100</td>
<td>0</td>
<td>010</td>
<td>10</td>
</tr>
<tr>
<td>010</td>
<td>0</td>
<td>001</td>
<td>11</td>
</tr>
<tr>
<td>001</td>
<td>1</td>
<td>100</td>
<td>11</td>
</tr>
<tr>
<td>100</td>
<td>1</td>
<td>110</td>
<td>01</td>
</tr>
<tr>
<td>110</td>
<td>0</td>
<td>011</td>
<td>01</td>
</tr>
<tr>
<td>011</td>
<td>0</td>
<td>001</td>
<td>11</td>
</tr>
<tr>
<td>001</td>
<td>0</td>
<td>000</td>
<td>00</td>
</tr>
</tbody>
</table>

Another view of an encoder is the view of a finite state machine (FSM). Figure 2 shows the state diagram view of the encoder.

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1. The initial state of the encoder is assumed to be all zeros. When all the data is encoded, the encoder is flushed by passing \( K - 1 \) zeros through it. The code words that result from these zeros are transmitted as well.
Table 2 shows the transitions of the states through transmission.

**Table 2. Transitions of the Encoder, State Diagram View**

<table>
<thead>
<tr>
<th>State of the Encoder</th>
<th>Input Bit</th>
<th>New State of the Encoder</th>
<th>Transmitted Code Word (First, Second)</th>
</tr>
</thead>
<tbody>
<tr>
<td>a</td>
<td>1</td>
<td>b</td>
<td>11</td>
</tr>
<tr>
<td>b</td>
<td>0</td>
<td>c</td>
<td>10</td>
</tr>
<tr>
<td>c</td>
<td>0</td>
<td>a</td>
<td>11</td>
</tr>
<tr>
<td>a</td>
<td>1</td>
<td>b</td>
<td>11</td>
</tr>
<tr>
<td>b</td>
<td>1</td>
<td>d</td>
<td>01</td>
</tr>
<tr>
<td>d</td>
<td>0</td>
<td>c</td>
<td>01</td>
</tr>
<tr>
<td>c</td>
<td>0</td>
<td>a</td>
<td>11</td>
</tr>
<tr>
<td>a</td>
<td>0</td>
<td>a</td>
<td>00</td>
</tr>
</tbody>
</table>

The rightmost column in Table 1 is equal to the rightmost column in Table 2. Although the state diagram provides all the information needed to follow the transitions of the convolutional encoder in time, this is not an easy task. To simplify tracking of the encoder transitions, we introduce the tree diagram in Figure 3. The bold line follows the transmitted bits (from the example) through the tree.
If we were to sum the states and code words around the bold line into a table, this table would be identical to Table 2. Tracing the transitions on the tree diagram is easy because the size of the block grows linearly while the size of the tree grows exponentially. Close inspection of the diagram reveals that the tree structure repeats itself at \( t_4 \), as the upper and lower half of the structure at \( t_4 \) are equal to the whole structure at \( t_3 \). These portions of the diagram are surrounded by a dotted line. Generally, any tree diagram starts repeating itself after \( K \) branches. It is this repetition that the trellis diagram (Figure 4) uses to provide all the information graphically and succinctly. Notice that the upper branch from each state represents a transmitted 0, while the lower branch represents a transmitted 1. As expected, the flow through the trellis diagram results in Table 2.
1.1 Viterbi Decoding

To decode the received data, we must maximize the likelihood function of the received sequence \(Z\) given all possible transmitted sequences \(U^{(m)}\). \(P(Z|U^{(m)}) = \max P(Z|U^{(m)})\) over all \(U^{(m)}\). The complexity of calculating the probability and therefore the computational load grows as the length of the received data grows, much as the complexity increases when we trace the received data using the tree diagram (Figure 3). To address this problem, Viterbi devised and proved an algorithm to detach the size of the received data from the complexity of calculation. The maximum likelihood function is calculated on each received code word rather than on the whole bulk of received data. The Viterbi algorithm calculates the similarity (distance) of the received symbol at time \(t_i\) and all branches entering all states at that time. This distance is the branch metric. Following are ways to calculate the branch metrics when the inputs are soft symbols.

- **Euclidean distance.** The Euclidean method involves straightforward distance calculations. The basis for calculating the distance is the 8-bit, twos complement representation of the maximum values. A received 0 is represented as 127 and a received 1 is represented as –127. Assuming that the received code words are \(\{x, y\}\) and we are calculating the distance from state \(b\) to state \(d\) \(\{0, 1\}\), the distance is calculated as shown in **Equation 1**:

  \[
  BM_{Euc} = \sqrt{(127-x)^2 - (127-y)^2}
  \]

  **Equation 1**

- **Manhattan distance.** The Manhattan metric calculates the multiplication of the expected data in the state and the received data. Assuming we are calculating the BM from state \(b\) to state \(c\) \(\{0, 1\}\) = \(\{1, -1\}\) and the received data is \(\{x, y\}\), as shown in **Equation 2**:

  \[
  BM_{Man} = (1 \cdot x) + ((-1) \cdot y)
  \]

  **Equation 2**

The Euclidean distance has proven to be mathematically optimal, but it is extremely difficult to implement in hardware. Although the Manhattan metric is not as mathematically powerful, it has proven to be effective and is easy to implement in hardware. Therefore, the VCOP uses the Manhattan metric, as do many other Viterbi coprocessors on the market.
If the inputs are hard symbols, the distance is calculated as the number of different bits between the expected input and the actual input. At time $t_i$ all states have a path metric (PM) of 0, the PM being the summation of all the branch metrics (BMs) on the surviving path up to that state. The BM from each two states in stage $t_{i-1}$ that enter the same state in stage $t_i$ are added to their respective PM from each state to create two possibilities for surviving paths. However, only the path with the best metric, the surviving path, is saved as the PM of the state in stage $t_i$.

Figure 5 shows an example of channel decoding that uses the Viterbi algorithm with hard inputs. The surviving path is the one with the lowest PM. The surviving path to each state is marked in a bold line. The PM numbers are shown in bold.

At $t_9$, the PM from both states in $t_5$ into states $a$ and $b$ add up to 3. The upper path was chosen as the surviving path because the example is consistent with the VCOP. However, both choices are equally right. After all decisions are made about the surviving paths of all states in all stages, we can trace back on the trellis diagram find the transmitted data. The decoded data is $\{1, 0, 0, 1, 1, 0, 0, 0\}$. That is, BER = $0/8 = 0$), even though two errors were received. At $t_9$, if there are two states with equal minimal PMs, we have two options:

- Choose either path (the VCOP chooses the upper state).
- Use the prior data at hand, that is, that the encoder was flushed. When this data is taken in to account, it is clear that the path to be chosen is the path ending in state $a$.

Figure 6 shows an example of decoding with soft inputs. The decoded data is $\{1, 0, 0, 1, 1, 0, 0, 0\}$. That is, BER = $0/8 = 0$), even though two errors were received. The BM are calculated in Equation 2 for the maximal PM. In Figure 5, we use minimum PM, and in Figure 6 we use maximum PM because of the different ways of calculating the BM. In the former, the BM measures the number of different bits in the expected and received, and we want a...
minimal difference. The latter multiplies the received soft value by the expected value using the maximum values \(\{127, -127\}\). If the sign of the expected value matches the sign of the received value, the multiplication results in a positive integer. We want the maximum product of these integer summations.
1.2 GSM Equalization, Channel Decoding and SOVA

The channel coding scheme, as specified by GSM, is depicted in Figure 7.

The blocks that use the Viterbi algorithm are Viterbi decoding and channel equalization (bold framed). The next paragraphs present the theory of channel equalization and a general implementation of VCOP in a GSM equalizer.

1.2.1 Channel Equalization Theory

The channels of time-division multiple access (TDMA) systems such as GSM introduce multi-path interference. The transmitted signal bounces between reflecting obstacles, such as buildings and hills, and reaches the receiver at various delays and attenuation values. In any given time slot, the received signal contains echoes from transmissions made at various times. These echoes are inter-symbol interference (ISI). The channel may therefore be modeled as an FIR filter with impulse response $h_c(t)$. The output of this FIR filter is a sum of its delayed and attenuated inputs, just as the received signal is a sum of delayed and attenuated paths.

In GSM, every transmitted slot includes the data bits and a training sequence, $s_{tr}(t)$, that is also known to the receiver. This training sequence enables the receiver to perform channel estimation and equalization. The received training sequence, $r_{tr}(t)$, is a convolution of the transmitted training sequence, $s_{tr}(t)$, and the channel’s impulse response, $h_c(t)$:

$ r_{tr}(t) = s_{tr}(t) \otimes h_c(t) \quad \text{Equation 3} $

The received training sequence in the digital domain, $r_{tr}[k]$, is fed into a digital matched filter with an impulse response, $h_{mf}[k]$, that is matched to $s_{tr}[k]$. The matched filter output, $h_c[k]$, can be written as shown in Equation 4.

$ h_c[k] = r_{tr}[k] \otimes h_{mf}[k] = s_{tr}[k] \otimes h_c[k] \otimes h_{mf}[k] = R_s[k] \otimes h_c[k] \quad \text{Equation 4} $ 

where $R_s[k]$ is the auto-correlation function of $S_{tr}[k]$. In GSM, the training sequences are engineered so that $R_s[k]$ is a highly peaked (impulse-like) real function. Therefore, $h_c[k]$ is a good estimation of the complex value $h_c[k]$.

Let $L$ denote the channel memory. That is, the channel has $L+1$ taps. $x[k]$ is the complex valued sample of the received signal at time $k$. The Viterbi equalizer finds the sequence $a[k] \in [-1,+1]$ that minimizes the Euclidian metric in Equation 5. Thus, $a[k]$ is the maximum likelihood sequence estimation (MLSE) that is the optimal estimation of the input symbols to the channel (for AWGN channels) [3].

![Figure 7. Block diagram of a typical GSM data communication system](image-url)
This Euclidian metric can be mathematically approximated to another metric called the matched filter metric, \( M[k] \). Due to a change in sign, we now maximize \( M[k] \) in Equation 6:

\[
M[k] = \sum_{l=0}^{k} a[l] \cdot \Re \left( y[l] - \sum_{i=1}^{L} S_i \cdot a[l-i] \right)
\]

where

\[
y[k] = \sum_{i=0}^{L} h_e^*[i] \cdot x[i+k]
\]

is the output of \( x[k] \) applied to a matched filter with an impulse response \( h_e[k] \) and

\[
S_k = \sum_{i=0}^{L} h_e^*(i) \cdot h_e(i+k)
\]

is the \( k \)-th tap of the autocorrelation of the channel impulse response estimation. The real part of the \( S_k \) series is called S-Parameters. Since \( a[k] \) can be only +1 or –1, and since the S-parameters are known, the expression in Equation 9:

\[
\Re \left( \sum_{i=1}^{L} S_i \cdot a[l-i] \right)
\]

can take only one \( 2^L \) value. These values are denoted as Viterbi parameters (VP). To maximize the matched filter metric \( M[k] \), we must try all the possible \( a[k] \) sequences. The Viterbi algorithm does exactly this very efficiently using \( 2^L \) states. In each stage all the possible VP values are calculated (one per state). Also, in each stage two branch metrics are calculated: the first is \(+ (y - VP)\) and the second is \(- (y - VP)\). Those path metrics are also called Ungerboeck metrics [2]. Each path in the trellis denotes the value of \( M[k] \) using different \( a[k] \). The MLSE path represents the \( a[k] \) that maximizes \( M[k] \).

### 1.2.2 GSM Channel Decoding

The Viterbi algorithm is also used in the GSM receiver for channel decoding. The theory behind convolutional encoding and channel decoding is explained in Section 1, Basics of Convolutional Encoding/Decoding, on page 2. The channel decoder performance significantly improves when soft input symbols are used instead of hard symbols. Therefore, the equalizer implements a soft output Viterbi algorithm (SOVA).
1.3 Soft Output Viterbi Algorithm (SOVA) Assist

We use SOVA for a GSM equalizer because a hard output Viterbi equalizer negates the capability of the outer Viterbi decoder to accept soft inputs for performing forward error correction (FEC). On the other hand, a SOVA-based inner Viterbi equalizer generates soft outputs, which in turn form the soft inputs for the outer Viterbi decoder performing FEC. The Viterbi algorithm is modified to deliver not only the most likely path sequence in a finite chain Markov sequence, but also an a posteriori probability or a reliability value for each bit. With this reliability indicator, the modified Viterbi algorithm produces soft decisions for use in the outer Viterbi decoder. Thus, the inner Viterbi algorithm accepts and returns soft sample values. The SOVA algorithm improves the signal to noise ratio (SNR) and is implemented with minimal changes to the original Viterbi algorithm.

Hagenauer and Hoeher [8] outline an algorithm that addresses this problem in two consecutive stages:

1. Channel equalization to minimize ISI.
2. Channel decoding, that is, Viterbi decoding.

According to [8], the VCOP must not only output the hard decision but also either an a posteriori probability for each bit or a reliability factor. The MSC8126 VCOP meets this requirement with the ability to provide:

- Hard decision bits.
- History buffer.
- Delta values for all states of all stages.
- Recursive traceback hard decisions.

The hard decision bits are the regular traceback hard decision that is later used as a reference for the SOVA assist algorithm.

The delta values are the difference between the PM + BM (branch metric) for each of the two states (stage n – 1) that are used to calculate the PM of a state in stage n. The delta values are PMxyz0_0–PMxyz0_1. In Figure 8, 0xyz and 1xyz are the states in the trellis diagram from which the butterfly originates; xyz can be any 3-bit binary value (xyz ∈ {000, . . . , 111}). They differ by the first bit, which is not relevant in the following stage. The trellis states xyz0 and xyz1 are the states at which the butterfly ends, and they have the same xyz value as the originating states. PMxyza_b is the PM from state xyz with the prefix b to state xyz with the suffix a. This PM is based on the PM from the previous stage (PM0xyz and PM1xyz).

![Figure 8. Delta Values](image-url)
To use the delta values, you can either perform software recursive traceback if VCOP resources are scarce or have the VCOP perform it. The recursive traceback is performed by running over the history buffer, which is why it can be dumped. For each state from N (block size) to 1, a traceback of M stages is performed. The VCOP supports $M \in \{16, 32\}$.

## 2 GSM Channel Equalization and Decoding on VCOP

The Viterbi algorithm uses the redundant information added to the information bits in the convolutional encoder to perform maximum likelihood decoding on the received data. The main calculation performed in the Viterbi algorithm and on the MSC8126 VCOP is add-compare-select (ACS), as shown in Figure 9. We add the BMs to the PMs from the previous stage and compare them to find the best metric, thereby creating the PMs for the current stage. The VCOP performs two butterflies in parallel (see Figure 10). The data widths are 16-bit PM, 11-bit BM, and 8-bit soft input symbols.

![Figure 9. Add Compare Select (ACS)](image1)

![Figure 10. Butterflies](image2)
GSM Channel Equalization and Decoding on VCOP

In Equalization mode, the branch metric for each transition within a Viterbi butterfly is a function of the matched filter output (MF) and the Viterbi parameters (VP). The VP values come from the channel autocorrelation. After the channel impulse response coefficients are extracted via a cross correlation process (also referred to as S-parameters estimated channel input response or channel coefficients), the VP value for a particular state, uvwxyz, is calculated as follows:

\[
VP(u, v, w, x, y, z) = (-1)^u S_6 + (-1)^v S_5 + (-1)^w S_4 + (-1)^x S_3 + (-1)^y S_2 + (-1)^z S_1
\]

Therefore, there can be \(2^{\text{Num. of S-Parameters}}\) different VP values for \(2^{\text{Num. of S-Parameters}}\) state trellis. This equation is calculated twice, in parallel, every clock to generate 2 VP values. The 2 VPs are used to calculate a butterfly once in every clock cycle. CNST is the constraint length, which defines the relation between the low and high states that compose the butterfly.

Figure 11 shows a typical GSM equalizer with partitioning between the VCOP and the SC140 core functions. The equalizer extracts the training sequence, \(r_{tr}[k]\), from the received signal and filters it using a matched filter with impulse response \(h_{mf}[k]\). The output of the matched filter, the channel estimation, \(h_{e}[k]\), is autocorrelated to obtain the S-parameters. The S-parameters are then correlated with all the possible \(2^L\) waveforms to generate the VP.

The data symbols of the received signal, \(x[k]\), are also filtered by a matched filter with impulse response \(h_{e}[k]\). The real part of the matched filter output, \(\Re(y[k])\), also denoted as \(MF\), is the input for the VCOP.

The branch metric calculator calculates the Ungerboeck metric, which the Viterbi Algorithm uses to find the MLSE. The equalized signal is the MLSE represented as hard decisions (±1).

![Figure 11. Viterbi Equalizer Application](image)

The Viterbi algorithm is used in the GSM receiver for channel decoding. The SOVA algorithm is composed of three tasks. The VCOP always performs the first task. Either the VCOP or the SC140 core can perform the second task, depending on how the user partitions the tasks. The SC140 core always performs the third task:

1. Delta values calculation. Calculate the difference (delta) between the path metrics that are in-bound to the same state. This task is performed for each state on each stage during the feed forward.
2. Recursive traceback. Generate a concurrent path starting from each state on the MLSE path (recursive traceback). See Figure 13.

3. Reliability values update, as follows:
   a. Set the reliability value of all the stages to infinity (or the highest possible positive value).
   b. Compare the hard decisions of each concurrent path to the MLSE path. If the hard decision obtained by the concurrent path on a certain stage differs from that of the MLSE path, set the reliability value of that stage to the lowest value between the current reliability value and the delta value of the starting stage of the concurrent path.
   c. Calculate the soft output symbols by multiplying each hard decision by its corresponding reliability value.

Table 3 lists the maximum number of stages that the VCOP supports for equalization.

<table>
<thead>
<tr>
<th>Number of S-Parameters</th>
<th>Number of Stages</th>
</tr>
</thead>
<tbody>
<tr>
<td>4</td>
<td>4090</td>
</tr>
<tr>
<td>5</td>
<td>4090</td>
</tr>
<tr>
<td>6</td>
<td>3072</td>
</tr>
</tbody>
</table>

There are four types of configuration registers for programming the VCOP:

- **Address registers.** Point to locations in the memory visible to the VCOP from where the input data is read, the output data is written, and the various algorithm assist dumps are performed.
  - VCOP Output Buffer Address Register (VOBAR)
  - VCOP Input Buffer Start Address Register (VIBSAR)
  - VCOP PM Fill Address Register (VPMFAR)
  - VCOP Algorithm Assist Data Dump Address Register (VAADAR)

- **Encoder profiling registers.** Give the VCOP all information necessary to decode the received data: length of the block, K, rate, polynomials, and so on. The reasoning and min/max values for each field are listed in the **MSC8126 Reference Manual.** See Table 4.
  - VCOP Configuration Register (VCONFR)
  - VCOP Polynomials Register (VPOLR)
  - VCOP Puncture Pattern Register (VPPR)
  - VCOP PM Init State Register (VPMISR)

- **Session profiling registers.** Give the VCOP the size of the input block and the type of traceback required. See Table 5.
  - VCOP Input Buffer Block Length Register (VIBBLR)
  - VCOP Trellis Count Register (VCNT)

- **Algorithm assist registers.** Can be programmed via the VCONFR[ISRNUM] bit to make the VCOP dump the PMs at various stages.
  - VCOP Interim Stage Register (and S-Parameters) A (VISRA). A dual-mode register. For feed-forward channel decoding mode, it holds the stages of PM memory content dumped out of the VCOP.
VCOP. For feed-forward channel equalization mode, it holds the channel autocorrelation parameters. This register can be read any time but is written only when the VCOP is in idle mode.

\{SPARAM\_i\_H,SPARAM\_i\_L\} — S Parameter i. Defines the i-th channel coefficient to be used in an equalization feed-forward session. The S-Parameter can be any 16-bit signed value \((2^{15} – 1 < S \text{ Parameter } i < –2^{15})\).

— VCOP Interim Stage Register (and S-Parameters) B (VISRB). A dual-mode register. For feed-forward channel decoding mode, it holds the stages of PM memory content dumped out of the VCOP. For feed-forward channel equalization mode, it holds the channel autocorrelation parameters. This register can be read any time but is written only when the VCOP is in idle mode.

\{SPARAM\_i\_H,SPARAM\_i\_L\} — S Parameter i. Defines the i-th channel coefficient to be used in an equalization feed-forward session. The S-Parameter can be any 16-bit signed value \((2^{15} – 1 < S \text{ Parameter } i < –2^{15})\).

— VCOP Interim Stage Register (and S-Parameters) C (VISRC). A dual mode register. For feed-forward channel decoding mode, it holds the stages of PM memory content dumped out of the VCOP. For feed-forward channel equalization mode, it holds the channel autocorrelation parameters. This register can be read at time but is written only when the VCOP is in idle mode.

\{SPARAM\_i\_H,SPARAM\_i\_L\} — S Parameter i. Defines the i-th channel coefficient to be used in equalization feed-forward session. The S-Parameter may be any 16-bit signed value \((2^{15} – 1 < S \text{ Parameter } i < –2^{15})\).

### Table 4. VCOP Encoder Profiling Registers

<table>
<thead>
<tr>
<th>Register</th>
<th>Field</th>
<th>Min Value</th>
<th>Max Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>VPOLR</td>
<td>G0[7–0]</td>
<td>N/A</td>
<td>N/A</td>
<td>Polynomial 0 for all values of VCONFR[RATE] and Polynomial 3, where VCONFR[RATE] = 0x3.</td>
</tr>
<tr>
<td></td>
<td>G1[7–0]</td>
<td>N/A</td>
<td>N/A</td>
<td>Polynomial 1 for all values of VCONFR[RATE] and Polynomial 4, where VCONFR[RATE] = 0x3.</td>
</tr>
<tr>
<td></td>
<td>G2[7–0]</td>
<td>N/A</td>
<td>N/A</td>
<td>Polynomial 2 where VCONFR[RATE] = {0x0–0x2}) and Polynomial 5, where VCONFR[RATE] = 0x3.</td>
</tr>
<tr>
<td></td>
<td>G3[7–0]</td>
<td>N/A</td>
<td>N/A</td>
<td>Polynomial 3, where VCONFR[RATE] = 0x2.</td>
</tr>
<tr>
<td>VPMISR</td>
<td>STATE_INDEX[7–0]</td>
<td>0x00</td>
<td>2(^{k–1})</td>
<td>After the PM memory is cleared, as it usually is, all states have an initial PM of 0. However, you may already know the state at which the convolutional encoder started coding (in 3G applications the encoder always starts at 0). To give the path starting from that state a better chance of being the surviving path with the best metric after the feed forward, you can program a value other than 0. For minimum PM calculations, program the favored state with a value lower than 0. For maximum PM calculations, program the favored state with a value higher than 0. VPMISR[PM_DATA] is a two's complement number.</td>
</tr>
<tr>
<td></td>
<td>PM_DATA[15–0]</td>
<td>0x3FFF</td>
<td>0xC000</td>
<td></td>
</tr>
<tr>
<td>VCONFR</td>
<td>CMD[5–0]</td>
<td>N/A</td>
<td>N/A</td>
<td>Specifies which sequence of operations to run</td>
</tr>
<tr>
<td></td>
<td>RATE[1–0]</td>
<td>0x0</td>
<td>0x3</td>
<td>Specifies the rate at which data is encoded.</td>
</tr>
<tr>
<td></td>
<td>FF_MIN/MAX</td>
<td>0x0</td>
<td>0x1</td>
<td>Specifies the best metric. The standards enable both minimum and maximum BMs to be considered as best.</td>
</tr>
<tr>
<td></td>
<td>CONST[2–0]</td>
<td>0x0</td>
<td>0x4</td>
<td>Defines K between 5 and 9 as specified in the various standards (K = VCONFR[CONST] – 5).</td>
</tr>
<tr>
<td></td>
<td>ISRNUM[3–0]</td>
<td>0x0</td>
<td>0xC</td>
<td>Specifies how many stages to dump for BTFD applications. The VISRx specifies which stages to dump.</td>
</tr>
</tbody>
</table>
After the VCOP is programmed, it starts processing the data with no intervention from the SC140 core. As it completes each stage in the process (not each stage in the trellis), the VCOP can interrupt the SC140 core. The overall stages of VCOP operation are summarized as follows:

1. Initialize PM memory using the PM FILL or PM CLEAR command and occasionally VPMISR.
2. Read the data required for each stage in the trellis diagram and process the data.
3. Dump the history memory in accordance with VCONFR[CMD].
4. Perform the traceback on the history memory in accordance with VCONFR[CMD].

### Table 5. VCOP Session Profiling Registers

<table>
<thead>
<tr>
<th>Register</th>
<th>Field</th>
<th>Min Value</th>
<th>Max Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>VCNT</td>
<td>TBNDX[11–0]</td>
<td>K+1</td>
<td>0xFFA1</td>
<td>For manually programming the starting stage of the traceback.</td>
</tr>
<tr>
<td></td>
<td>TBMOD[2–0]</td>
<td>0x0</td>
<td>0x31</td>
<td>Specifies whether to use VCNT[LEARN] and VCNT[PDTBS].</td>
</tr>
<tr>
<td></td>
<td>LEARN[5–0]</td>
<td>0x00</td>
<td>0x3F</td>
<td>Not applicable for GSM.</td>
</tr>
<tr>
<td></td>
<td>PDTBS</td>
<td>0x00</td>
<td>2k−1</td>
<td>Enables you not to use the absolute Min/Max (dependant on VCONFR[FF_MIN/MAX]) PM but rather to specify the starting state of the traceback. This is useful when you know the state of the encoder when it finished coding the data and therefore the location where the decoder should start decoding.</td>
</tr>
<tr>
<td>VIBBLR</td>
<td>VIBBL[13–0]</td>
<td>0x00011</td>
<td>0x1FF4</td>
<td>The maximum value is the multiplication of the maximum block size at Rate = 1/6 (2730) and 6.</td>
</tr>
</tbody>
</table>

NOTES: 1. The maximum value depends on VCONFR[RATE] and VCONFR[CONST] and can be found per each combination in the VCOP chapter of the MSC8126 Reference Manual. The value is the overall maximum value.

2. The values 0x4–0x7 are used in channel equalization.

3. Although 0x0001 is a legal value for VIBBLR[VIBBL], the minimum legal value is K + 1 to perform traceback sessions.

### 3 Recommended Design Practices

This section presents the VCOP features and recommends ways you can get the most benefit from these features.

#### 3.1 VCOP Features

- Fully programmable feed-forward channel decoding and traceback sessions.
- Channel decoding:
  - Constraint length between K = 5 and K = 9.
  - Puncture codes.
  - Rate of 1/2, 1/3, 1/4, and 1/6.
  - Four fully programmable polynomials (1/6 rate is implemented by three polynomials only).
- The input to equalization is 16-bit. The input symbols for decoding are 8-bit (256 levels) signed soft symbols.
- Output is hard decision (1-bit).
Recommended Design Practices

- Fully programmable block length for all sessions.
- Programmable traceback methods of maximum PM, minimum PM, or end state.
- Start of feed-forward according to a pre-saved PM memory content. However, the history buffer is not saved, so the traceback is according to the current block only.
- SC140 core programs the VCOP parameters while the VCOP is in idle mode and then the VCOP can run independently on the whole block of data.
- The number of users the VCOP supports is linear to frequency.
- Fully programmable feed forward channel equalization and traceback sessions.
- For GSM channel equalization:
  - Fully programmable 4 to 6 estimated channel autocorrelation coefficients (S-parameters).
  - History buffer with up to 4090 stages for GSM.
  - Matched filter input is 8 bits (256 levels).
  - SOVA assist algorithm.
  - Output 8-bit coded delta values for SOVA assist algorithm, 1-bit hard decision traceback, and history buffer or recursive traceback.
- Input symbols are 8-bit (256 levels) signed soft symbols.
- Output is hard decision (1-bit).
- Fully programmable block length for all sessions.
- Programmable traceback methods of Max path, Min path, or end state.
- Programmable learning period length for the traceback session.
- Start of feed forward according to a pre-saved PM memory content. However the history buffer is not saved. Therefore the traceback is according to the current block only.
- SC140 core programs the VCOP parameters while the VCOP is idle and then the VCOP independently processes the block of data.
- Interrupt lines and status bits notify the SC140 core when a session completes.
- Memory accesses are multiples of 8 bytes, even if meaningful data holds a fraction of 8 bytes, with a value of 0 in the filler bits.
- Performance monitoring unit with six monitored behaviors.

3.2 Interrupts Versus Polling

Although the VCOP allows polling, it is optimized for an interrupt-driven system. If the SC140 core is busy polling, it either constantly polls the VSTR, thus loading the bus and rendering at least one AGU and one DALU useless to the other processes, or it polls the VSTR occasionally, thus not catching the exact moment at which the VCOP is free for a new configuration. Either of these polling activities degrades performance. Moreover, during BTFD, it is not enough to poll the VSTR. The VSTR[PM_DONE] bit must be cleared after each PM dump to ensure that the next PM dump is performed. Constantly clearing this bit calls for constant polling.

The disadvantage of an interrupt-driven approach is that each interrupt costs approximately 100 core clock cycles. However, the reasons against polling outweigh the one for polling, so we recommend the use of interrupts. You can use a combination of interrupts and polling so that when the SC140 core initiates a VCOP session, it starts polling the VSTR when the session is supposed to finish. The expected finish time is known because the VCOP needs approximately 67 cycles per symbol, and the number of symbols is known. When the SC140 core detects that the

---

2. Based on the SmartDSP OS for StarCore-based architecture.
VCOP has finished the session, it starts a new session in a single-core operation or passes control of the VCOP to a different core in a multi-core operation.

### 3.3 Buffer Allocation

There is no time for you and/or the VCOP driver to allocate buffers in a real-time system, so you must allocate enough space for the four types of buffers the VCOP may use:

- Input buffer, to which the VIBSAR points
- Output buffer, to which the VOBAR points
- Algorithm assist buffer, to which the VAADAR points
- PM fill buffer, to which the VPMFAR points

When it is called, the VCOP driver provided as an example assumes that the code always points to the correct segment of each buffer.

### 3.4 Single-Core Operation

For single-core operation of the VCOP, you have all the information on a session and can simply program the VCOP by writing directly to the VCOP registers or by using the driver described in Section 4.

### 3.5 Multi-Core Operation

For multi-core operation of the VCOP, following are ways to share the common VCOP resource:

- *Use each SC140 core to perform part of the process* necessary for GSM channel equalization and decoding, with only one SC140 core actually using the VCOP. This is a type of single-core operation, so all information in Section 3.4 applies—with the difference that the SC140 core activating the VCOP is exempt from all decoding calculations before and after VCOP operation. The advantage of this approach is that only one of the four SC140 cores accesses the VCOP, thus rendering the whole resource management mechanism redundant. The disadvantage is that the load on the SC140 cores is probably not symmetrical because activating the VCOP is a relatively quick and easy task.

- *Use hardware semaphores.* The advantage of this approach is that it uses the hardware and requires minimal programming overhead. The disadvantage is that aborting the current VCOP operation is not straightforward because only the SC140 core that locked the semaphore can unlock it.

- *Create a software semaphore that instantiates a token ring,* or round-robin mechanism (see Figure 12) in which each SC140 core controls the VCOP an equal amount of time. The advantage of this approach is that it is easy to implement and requires little overhead. However, it is unlikely that all cores receive the same amount of data to process. If one SC140 core always receives smaller channels, it controls the VCOP a disproportionately small amount of time and may run out of data to process. The token ring/round robin mechanism puts a priority scheme in place. An SC140 core can raise its priority, thus increasing the probability of receiving control over the VCOP.

![Figure 12](image)

**Figure 12.** Token Ring for Multiple Cores

*GSM Channel Equalization, Decoding, and SOVA on the MSC8126 Viterbi Coprocessor (VCOP), Rev. 0*
Recommended Design Practices

- Create a software semaphore in which the next SC140 core to control the VCOP is the one that has processed the fewest incoming symbols. This approach ensures that each SC140 core controls the VCOP for the about same amount of time. The disadvantage is that the overhead of calculating the next SC140 core to control the VCOP consumes much more time than a simple token ring. The next SC140 core to control the VCOP is determined according to Equation 11, where $N$ is the number of cores on the DSP device. The token ring option should be implemented if the SC140 cores handle the same amount of data (on the average), making the more complicated method redundant.

$$\min \left( \frac{\sum_{n=0}^{N-1} \text{Processed Bits}_n}{\text{Processed Bits}_i} \right)$$

**3.5.1 Requesting and Releasing VCOP Services**

An SC140 core requests VCOP services as follows:

1. Use a read-modify-write on the address where the queue is managed to find whether the VCOP is in use. Then set the bit that signals to the other SC140 cores that the VCOP is in use.

   If no other SC140 core is using the VCOP, the requesting core can use it. If the VCOP is in use, the requesting SC140 core waits until the VCOP is free.

2. When an SC140 core finishes using the VCOP, it issues a read-modify-write on the address where the queue is managed. The read establishes which SC140 core is next in line to use the VCOP (generally the SC140 core to the right of the one freeing the resource). The write clears the SC140 core bit in the queue. Then it initiates a virtual interrupt (via the GIC) to the SC140 core next in line to use the VCOP.

   If the SC140 core needs further VCOP services, it can perform a simple read since clearing the bit is not necessary.

**3.5.2 Aborting VCOP Sessions**

To abort a VCOP session, the SC140 core currently using the VCOP must enable the VCOP abort interrupt in the LIC and PIC. An SC140 core aborts the current VCOP session (due to a high priority channel), as follows:

1. Enable the LIC and PIC to have the VCOP interrupt.
2. Write a value of 1 to VCONFR[ABORT] and wait for the resulting interrupt.
3. Initiate a VCOP session. When the session terminates, the token ring continues from the interrupting SC140 core.
4. Ignore any data that may have already come from the current session.
5. Disable VCOP interrupts via the LIC and PIC.
3.6 GSM Channel Equalization

The steps in GSM channel equalization are as follows:

1. Clear PM memory or load the initial state from external memory using the PM FILL command.
2. In the VPMISR, initiate any number of states to a desired starting value. Alternatively, configure VPMISR to initiate a single state after an automatic feed forward session, which clears the PM memory and initiates it according to the configuration of VPMISR. In the automatic approach, only a single state can be initialized and only the higher or lower part of it (not both).
3. Update the VIBSAR with the starting address of the raw data to be equalized, and in the VIBBAR, specify the amount of data.
4. Program the channel autocorrelation parameters (S-parameters) into the VISRA, VISRB, and VISRC.
5. Store the output address for the delta values of the SOVA assist, in VAADAR.
6. If automatic traceback is to be used, update the address for storing the output of the traceback session in VOBAR.
7. Start the session using one of these methods:
   — Start feed-forward channel equalization session command.
   — Start feed-forward channel equalization session and start HD traceback session automatically.
   — PM CLEAR and automatically start a feed-forward channel equalization session, followed by an HD traceback session in the VCONFR, together with the necessary parameters (such as rate, puncture code, constraint length, and interrupts to the SC140 core).

3.6.1 Recursive Traceback for SOVA Assist

In equalization mode, the SOVA requires special tracing back from each point on the regular traceback result. Each point is a root for traceback, but the first step is opposite to the one in the original traceback. It is not necessary to trace back all the way, since the branch normally combines with the original traceback after a few stages. The VCOP handles 16-stage or 32-stage recursive traceback. These data sizes are convenient because of the bus width, and they hold sufficient information. Figure 13 shows an example of recursive traceback. The traceback starting-point is specified by the VCONFR[MN, MAX] bits or the PDTBS field. The traceback uses the learning period.

Figure 13. Recursive Traceback
### 3.7 GSM Channel Decoding

The steps in GSM channel decoding proceed as follows:

1. Clear PM memory or use the PM FILL command to load the initial state from external memory.
2. In the VPMISR, initiate any number of states to a desired starting value.
   Alternatively, configure the VPMISR to initiate a single state after an automatic feed-forward session, which clears the PM memory and initiates it according to the configuration of VPMISR. In the automatic method, only a single state can be initialized.
3. Update the VIBSAR with the starting address of the equalized data to be decoded and the VIBBAR with the amount of data.
4. Program the polynomials into VPOLR.
5. If automatic traceback is to be used, update the address for storing the output of the traceback session in VOBAR.
6. Start the session by specifying the session type in the VCONFR (see Table 6), together with the necessary parameters, such as rate, puncture code, and constraint length. Enable the necessary interrupts to the SC140 core.

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Equalization feed-forward</td>
<td>The VCOP enters this mode when the “equalization feed-forward” command is written in Idle mode. The SC140 core configures the parameters for this operation, such as rate, S-Parameters, block length, and so on, before it issues this command. The VCOP can return to Idle mode if the ABORT command is issued. When the session terminates as specified in the VCNT register, the mode can change to Traceback if automatic traceback is enabled or return to Idle mode.</td>
</tr>
<tr>
<td>History buffer dump</td>
<td>The contents of the history buffer are part of the data required by the DSP code to perform the equalization. Therefore, a history buffer dump occurs automatically unless a recursive traceback is performed. A command to the VCOP can also cause a buffer dump when the decoding process is debugged. For an explicit command to the VCOP, the block size and the constraint length must be programmed correctly.</td>
</tr>
<tr>
<td>Hard decision traceback</td>
<td>The VCOP uses the traceback engine and the history buffer memory for a traceback after feed-forward decoding or feed-forward equalization. The bits are packed to 64-bit words. The SC140 core should program the parameters of the traceback operation in advance in Idle mode.</td>
</tr>
<tr>
<td>Equalization feed-forward with automatic traceback</td>
<td>A combination of the regular equalization feed-forward session and the traceback session. The main feature is the automatic change of session from feed-forward to traceback.</td>
</tr>
<tr>
<td>PM memory clear with automatic equalization feed-forward</td>
<td>A combination of the PM memory clear and regular equalization feed-forward session. The main feature is the automatic change of session from the PM memory clear to feed-forward.</td>
</tr>
<tr>
<td>PM memory clear with automatic equalization feed-forward and traceback</td>
<td>A combination of the PM memory clear, equalization feed-forward session and the hard decision traceback session.</td>
</tr>
</tbody>
</table>
4 VCOP Driver

The VCOP driver is a simple, easy interface to the VCOP. This section covers both the driver structs and driver functions. It also provides the driver header file and source code.

4.1 Driver Structs

The VCOP driver structs are listed as follows:

- **vcopStruct**. The driver view of the VCOP and the session, which includes the references in Table 7.

  Table 7. vcopStruct Internal References

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>VCOP</td>
<td>vcop_regs</td>
<td>A pointer to the VCOP base address.</td>
</tr>
<tr>
<td>vcopSessionStruct</td>
<td>session</td>
<td>A pointer to the current session.</td>
</tr>
<tr>
<td>vcopBTFDManagement</td>
<td>btfd_management</td>
<td>A data structure for BTFD</td>
</tr>
</tbody>
</table>

- **vcopSessionStruct**. Points to all the data to run the current session, including the interim dump points for calculating $S(n_{end})$ and the CRC used during encoding (see Table 8).

  Table 8. vcopSessionStruct Internal References

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>vcopAddressPointers</td>
<td>pointers</td>
<td>A pointer to a struct of addresses.</td>
</tr>
<tr>
<td>vcopFFStruct</td>
<td>ffData</td>
<td>A pointer to the relevant vcopFFStruct that contains data on the constraint length, polynomials, number of interim dumps (all relevant for programming VCONFR), and the CRC.</td>
</tr>
<tr>
<td>vcopTBStruct</td>
<td>tbData</td>
<td>A pointer to the relevant vcopTBStruct that contains data on the size of the input block and the type of traceback.</td>
</tr>
<tr>
<td>vcopInterimStruct</td>
<td>visrxData</td>
<td>An array defining the stages in the decoding where an interim dump is performed</td>
</tr>
</tbody>
</table>

- **vcopBTFDManagement**. Holds all information required for running BTFD. The most relevant part of this struct is the array stage_data, which contains a 12-element array of the vcopInterimStage struct. See Table 9.

  Table 9. vcopInterimStage internal references

<table>
<thead>
<tr>
<th>Type</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>bool</td>
<td>performed_traceback</td>
<td>Notifies the driver of whether a traceback has been performed at this stage.</td>
</tr>
<tr>
<td>bool</td>
<td>passed_CRC</td>
<td>Notifies the driver of whether the traceback result passed CRC.</td>
</tr>
<tr>
<td>fp32</td>
<td>Sn</td>
<td>The value of Sn (see Equation. 1 in Section A.1.2 of 3GPP TS 25.212).</td>
</tr>
<tr>
<td>uint32</td>
<td>vobar</td>
<td>A pointer to the traceback resulting from this interim dump.</td>
</tr>
</tbody>
</table>

For all other structs, refer to the VCOP driver header file in Section 4.3, Driver Header File, on page 29.
4.2 Driver Functions

This section presents the following driver functions:

- **Activate the VCOP**, `vcop_ioctl`, Section 4.2.1, *Activate the VCOP, vcop_ioctl*, on page 22.
- **Write the session configuration to the VCOP**, Section 4.2.2, *Write Session Configuration to VCOP, vcop_CreateConfig*, on page 26.
- **Initialize the VCOP driver**, Section 4.2.3, *Initialize the Driver, vcop_InitializeDriver*, on page 28.

4.2.1 Activate the VCOP, vcop_ioctl

```c
#include "vcopDriver.h"
extern volatile vcopStruct *global_dev_ch;
vcoopStatus vcop_ioctl(void *dev_ch, uint8 ioctl, void *param)
{
    volatile vcopStruct          *vcop            = (vcopStruct*)dev_ch;
    volatile vcopSessionStruct   *session_params  = (vcopSessionStruct*)param;
    volatile vcopBTFDManagement  *btfd_management = &vcop->btfd_management;
    volatile vcopAddressPointers *pointers        = session_params->pointers;
    volatile VCOP                *vcop_regs       = vcop->vcop_regs;
    // VCONFR[9:2]
    uint8 interrupt_mask = 0x00;
    // flag indicating if history dump is performed
    bool history_dump = FALSE;
    // flag indicating if traceback is performed
    bool traceback = FALSE;
    // flag indicating if interim stages are dumped - for BTFD
    bool interim_stages = FALSE;
    uint8 i;
    global_dev_ch = vcop;
    vcop->session = session_params;

    /***************************************************************************/
    /*                               Abort                                             */
    /***************************************************************************/
    if (ioctl == 0x00)
    {
        ENABLE_VCOP_INTERRUPTS_LIC();
        WRITE_UINT32(vcop_regs->VCONFR, 0x00000005);
        return VCOP_SUCCESS;
    } // if (ioctl == 0x00)

    /***************************************************************************/
    /*                            LPU                                                 */
    /***************************************************************************/
    if (session_params->updateLpu)
    {
        if(session_params->lpuData->reset)
            WRITE_UINT32(vcop_regs->VPCR, 0x00000000);
        vcop_createConfig(configLPU, dev_ch);
    } // if (session_params->updateLpu)

    /***************************************************************************/
    /*                            Illegal Configurations                               */
    /***************************************************************************/
    if (ioctl)
    {
        Illegal Configurations
    }
```

GSM Channel Equalization, Decoding, and SOVA on the MSC8126 Viterbi Coprocessor (VCOP), Rev. 0
case 0x11:
case 0x12:
case 0x13:
case 0x21:
case 0x22:
case 0x23:
case 0x31:
case 0x32:
case 0x33:
    return ILLEGAL_CONFIG;
}[/* 
    "Real" sessions */
]/*
 *---------------------------------------------
 *                            Decoding
 *---------------------------------------------
 */
if ((ioctl & 0x0C) == 0x04)
{
    if (session_params->updateVisrx)
        vcop_createConfig(configBTFD, (vcopStruct*)vcop);
/**************************************************************/
/* Analyze ioctl and decide whether there are interim dumps,  */
/* history dumps, and/or traceback                          */
/**************************************************************/
if (session_params->ffData->interimDumps)
{
    interim_stages = TRUE;
    ioctl = ioctl & 0x0C;
}
else
{
    if (ioctl & 0x01)
        traceback = TRUE;
    if (ioctl & 0x02)
        history_dump = TRUE;
}
/**************************************************************/
/* Update the BTFD management struct in dev_ch with the      */
/* relevant data to this session                            */
/**************************************************************/
if (interim_stages)
{
    // See Section 4.3, Driver Header File, on page 29
#ifdef VCOP_BTFD_PRE_KNOWLEDGE
    btfd_management->PM_dump_size = (uint16)VCOP_BTFD_PRE_KNOWLEDGE;
#else
    btfd_management->PM_dump_size = 
        (uint16)(1 << session_params->ffData->constraintLength);
#endif
}
```c
#endif
btfd_management->num_of_remaining_BTFD_tracebacks =
session_params->ffData->interimDumps;
WRITE_UINT32(vcop_regs->VAADAR, (uint32)pointers->vaadar);
for (i=0 ; i< session_params->ffData->interimDumps; i++)
{
    btfd_management->stage_data[i].performed_traceback = FALSE;
    btfd_management->stage_data[i].passed_CRC = FALSE;
    btfd_management->stage_data[i].Sn = (fp32)-1;
}
btfd_management->vobar = (uint32)pointers->vobar;
} // if (interim_stages)

/**************************************************************/
/* Calculate the next interrupt and enable it                  
/* Only one interrupt is enabled according to this priority:  */
/* ipi_int_tb, ipi_int_hd, ipi_int_ff                         */
/**************************************************************/
if (traceback)
    interrupt_mask = 0x04;  // assert VCONFP:TB_INTEN
else if (history_dump)
    interrupt_mask = 0x40;  // assert VCONFP:HD_INTEN
else
    interrupt_mask = 0x08;  // assert VCONFP:FF_INTEN
/**************************************************************/
/* Update address registers                                   */
/**************************************************************/
WRITE_UINT32(vcop_regs->VIBSAR, (uint32)pointers->vibsar);
if ((ioctl & 0x30) == 0x10)
    WRITE_UINT32(vcop_regs->VPMFAR, (uint32)pointers->vpmfar);
if (traceback || history_dump)
    WRITE_UINT32(vcop_regs->VOBAR, (uint32)pointers->vobar);
if (session_params->ffData->initValue != 0x0000)
    WRITE_UINT32(vcop_regs->VPMISR, (uint32)session_params->ffData->vpmisr);
break;
} // if ((ioctl & 0x0C) == (0x04))

/**************************************************************/
/* Equalization                                              */
/**************************************************************/
else if (ioctl & 0x0C)
{
    if (! session_params->updateVisrx)
        generate_s_params_and_mf ((vcopStruct*)vcop);
    vcop_createConfig(configBTFD, (vcopStruct*)vcop);
    if ((ioctl & 0x0C) == 0x08)
        WRITE_UINT32(vcop_regs->VAADAR, (uint32)pointers->vaadar);
    if (ioctl & 0x01)
        traceback = TRUE;
    if (ioctl & 0x02)
        history_dump = TRUE;
    /* Calculate the next interrupt and enable it               */
    /* Only one interrupt is enabled according to this priority: */
    /* ipi_int_tb, ipi_int_hd, ipi_int_ff                        */
    /* */
    /* */
    /* */
    /* */
    /* */
};```
if (traceback)
  interrupt_mask = 0x04; // assert VCONFT:TB_INTEN
else if (history_dump)
  interrupt_mask = 0x40; // assert VCONFT:HD_INTEN
else
  interrupt_mask = 0x08; // assert VCONFT:FF_INTEN

/**************************************************************/
/* Update address registers                                   */
/**************************************************************/
WRITE_UINT32(vcop_regs->VIBSAR, (uint32)pointers->vibsar);
if ((ioctl & 0x30) == 0x10)
  WRITE_UINT32(vcop_regs->VPMFAR, (uint32)pointers->vpmfar);
if (traceback || history_dump)
  WRITE_UINT32(vcop_regs->VOBAR, (uint32)pointers->vobar);
if (session_params->ffData->initValue != 0x0000)
  WRITE_UINT32(vcop_regs->VPMISR, (uint32)session_params->ffData->vpmisr);
bbreak;
} // if (ioctl & 0x0C)
/*                            Traceback (+ History Dump)                           */
/**************************************************************/
else if (ioctl & 0x01)
{
  interrupt_mask = 0x04; // assert VCONFT:TB_INTEN
  // Update VOBAR only if regular Traceback/History Dump
  if (session_params->ffData->interimDumps == 0)
    WRITE_UINT32(vcop_regs->VOBAR, (uint32)pointers->vobar);
bbreak;
}
/*                            History Dump                                         */
/**************************************************************/
else if (ioctl & 0x02)
{
  interrupt_mask = 0x40; // assert VCONFT:HD_INTEN
  WRITE_UINT32(vcop_regs->VOBAR, (uint32)pointers->vobar);
bbreak;
}
/*                            PM Fill                                              */
/**************************************************************/
else if (ioctl & 0x10)
{
  interrupt_mask = 0x10;
  WRITE_UINT32(vcop_regs->VPMFAR, (uint32)pointers->vpmfar);
bbreak;
}
/*                            PM Clear                                             */
/**************************************************************/
else if (ioctl & 0x20)
{
  interrupt_mask = 0x20;
bbreak;
}
/*                            PM Dump                                              */
/**************************************************************/
VCOP Driver

4.2.2 Write Session Configuration to VCOP, vcop_CreateConfig

```c
#include "vcopDriver.h"
void vcop_createConfig(configType type, vcopStruct* dev_ch) {
    volatile VCOP *vcop_regs = (VCOP*)dev_ch->vcop_regs;
    volatile vcopFFStruct *ffData;
    volatile vcopTBStruct *tbData;
    volatile vcopInterimStruct *decodingVisrxData;
    volatile vcopSParamStruct *equalizationVisrxData;
    volatile vcopLpuStruct *lpuData;
    switch (type) {
        // inConfig is ffData;
        case configFF:
            ffData = dev_ch->session->ffData;
            WRITE_UINT32(vcop_regs->VPOLR,
                         (ffData->polynomial3)      |
                         (ffData->polynomial2 << 8)  |
                         (ffData->polynomial1 << 16) |
                         (ffData->polynomial0 << 24));
            if (ffData->puncturePeriod)
                WRITE_UINT32(vcop_regs->VPPR,
                             (ffData->puncturePeriod - 1) |
                             (ffData->puncturePattern << (32 - ffData->puncturePeriod)));
            else
                WRITE_UINT32(vcop_regs->VPPR, 0x00000000);
            ffData->vpmisr =
                (((ffData->initState << 24) | 0xffff ) &
                 (ffData->initValue));
            ffData->vconfr =
                (((ffData->interimDumps << 11) |
                  (ffData->constraintLength - 5) << 16) |
                 (ffData->min_max << 19) |
                 (((ffData->rate == 3) ? 1 :
                   (ffData->rate == 4) ? 2 :
                   (ffData->rate == 6) ? 3 : 0) << 22));
            break;
        // inConfig is tbStruct;
        case configTB:
            tbData = dev_ch->session->tbData;
```
WRITE_UINT32(vcop_regs->VIBBLR, (tbData->inputSize));
break;

// inConfig is interimStruct;
case configBTFD:
    decodingVisrxData = (vcopInterimStruct*)dev_ch->session->visrxData;
break;

// inConfig is interimStruct;
case configSParam:
    equalizationVisrxData = (vcopSParamStruct*)dev_ch->session->visrxData;
    WRITE_UINT32(vcop_regs->VISRA, ((equalizationVisrxData->sParams[1] & 0x0000ffff) | (equalizationVisrxData->sParams[0] << 16)));
break;

// inConfig is lpuStruct;
case configLPU:
    lpuData = dev_ch->session->lpuData;
    WRITE_UINT32(vcop_regs->VPCR, (lpuData->event << 16) | (lpuData->genInt << 24) | (lpuData->stopCond << 25) | (lpuData->startCond << 30));
break;
 }
return;

#include "vcopDriver.h"
// Function in Assembly from vcopDriverAsm.asm
extern void initialize_driver();
// Variables from vcopDriver.c
extern VCOP *vcop_place_holder;
4.2.3 Initialize the Driver, vcop_InitializeDriver

vcop_InitializeDriver configures the LIC and the PIC and also the driver view of the VCOP.

```c
vcopStatus vcop_initializeDriver(vcopStruct* dev_ch)
{
    initialize_driver();
    dev_ch->vcop_regs = vcop_place_holder;
    #ifdef DECODING_BTFD
    dev_ch->btfd_management.num_of_remaining_BTFD_tracebacks = 0;
    dev_ch->btfd_management.num_of_BTFD_TB_handled           = 0;
    #endif
    DISABLE_VCOP_INTERRUPTS_LIC();
    return VCOP_SUCCESS;
}
```

The Assembly code for programming the LIC and PIC follows.

```assembly
section .oskernel_text_run_time_critical
include "common_macros.asm"
BASE_EXEPTION_TABLE equ $00001000 ; Defined in this file
GLOBAL     _initialize_driver
_initialize_driver:
    move.l #BASE_EXEPTION_TABLE,vba ; set VBA to some value
    bmclr #$00e0,sr.h
    nop
    nop
    ; un-mask all interrupts
    ; Clear all pending interrupts
    write_w#$ffff,IPRA
    write_w#$ffff,IPRB
    write_l#$ffffffff,LICAISR
    write_l#$ffffffff,LICBISR
    ; VCOPSD is No. 28 in LIC interrupt group A table (ipi_int_protocol)
    ; VCOPGI is No. 27 in LIC interrupt group A table (ipi_int_abort)
    ; programing the LIC to work in edge mode, and choose the IRQOUTA[0-3] to PIC
    ; EM28   = 01 edge,second edge
    ; IMAP28 = 00 route 28 through IRQOUTA[1]
    ; EM27   = 01 edge,ignore second edge
    ; IMAP27 = 00 route 27 through IRQOUTA[0]
    write_l #$00094000,LICAICR0
    ; Enable interrupts 28 and 27 (group A)
    write_l #$18000000,LICAIER; enable irq 28 and 27 - VCOPSD, VCOPGI
    ; LIC IRQOUTA[1] is goes to IRQ7 in PIC interrupt routine table
    ; LIC IRQOUTA[0] is goes to IRQ6 in PIC interrupt routine table
    ; The service routing address (offset from VBA) is #$980
    ; Program the PIC
    write_w #$6700,ELIRB ; LIC IRQOUTA0/IRQOUTA1: edge triggered, highest priority
    ; PED7 = 0 level
    ; {PIL70,PIL71,PIL72} = 110
    ; PED6 = 0 level
    ; {PIL60,PIL61,PIL62} = 111 = highest priority
    write_w #$7000,ELIRF ; Enable LICSEIRQ - LIC Second Edge IRQ (Groups A and B)
    ; PED23 = 0 level
    ; {PIL230,PIL231,PIL232} = 111 = highest priority

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4.3 Driver Header File

/********************************************************************************
@Cautions - Keep in mind that stage 0 is the first stage when a stage is called
for.
- The driver assumes that the user will perform an interim dump at the last stage of a decoding session that requires such dumps. Furthermore, the driver overrides automatic traceback that follow a decoding session with interim dumps.
- The driver assumes that if VCONF[R:ISRNUM] is different than 0, the interrupt handlers should treat the interrupt as part of a BTFD session. This is correct for traceback sessions as well.
- Illegal configurations may result in a system halt.
- When an interrupt is triggered, the user’s function is called. While this function is active, other hardware interrupts are masked. Therefore the user’s callback function should be as short as possible.
**********************************************************************************/
#ifndef VCOPDRIVER_H
#define VCOPDRIVER_H
/**********************************************************************************
@Description Various user definitions for the configuration of the driver
**********************************************************************************/
#define VCOP_BASE_ADDRESS        0x01FEF000
#define QBUS_BASE_ADDRESS        0x00F09C00
#define USE_DSP_COMPLEMETARY_TASKS
#ifdef USE_DSP_COMPLEMETARY_TASKS
#define VCOP_BTFD_PRE_KNOWLEDGE 512
#define BTFD_THRESHOLD           -0.5
#endif // USE_DSP_COMPLEMETARY_TASKS
#include "vcop_datatypes.h"
/**********************************************************************************
@Description vcopStatus enumerates the statuses the driver may return to the user
**********************************************************************************/
typedef void* USER_FUNCTION_RETURN_TYPE;
typedef void* USER_FUNCTION_VARS_TYPE;
// All user callback functions are assumed to return with the type of
// USER_FUNCTION_RETURN_TYPE
typedef void* USER_FUNCTION_RETURN_TYPE;
// All user callback functions are assumed to receive arguments the type of
// USER_FUNCTION_VARS_TYPE
typedef void* USER_FUNCTION_VARS_TYPE;
#include "vcop_datatypes.h"
/**********************************************************************************
@Description vcopStatus enumerates the statuses the driver may return to the user
**********************************************************************************/
typedef enum vcopStatus {
    // Notifies the user of a successful ending of a session
    VCOP_SUCCESS,
    // Notifies the user that the requested configuration failed
    ILLEGAL_CONFIG,
    // Notifies the user that the current session has been aborted
    SESSION_ABORTED,
    // Notifies the user that none of the Interim Dump/Traceback pairs are
    // candidates for a valid data
    BTFD_FAILURE,
    // Notifies the user that one of the Interim Dump/Traceback pairs contains valid data
    BTFD_SUCCESS,
    // Notifies the user that the driver could not be initialized
    INITIALIZATION_FAILURE,
} vcopStatus;

/**************************************************************************
@Description   minMax enumerates Min/Max PM calculations
This is used to set the ffStruct.min_max field to the desired
 type of PM calculation
****************************************************************************/
typedef enum minMax {
    // Minimum PM calculations
    MIN = 1,
    // Maximum PM calculations
    MAX = 0
} minMax;

/**************************************************************************
@Description   vcopCRCType enumerates the various numbers of CRC bits
 appended to the data. Default is CRC0
- gCRC24(D) = D24 + D23 + D6 + D5 + D + 1
- gCRC16(D) = D16 + D12 + D5 + 1
- gCRC12(D) = D12 + D11 + D3 + D2 + D + 1
- gCRC8(D) = D8 + D7 + D4 + D3 + D + 1
****************************************************************************/
typedef enum vcopCRCType {
    // No CRC
    CRC0 = 0,
    // 8 bit CRC. Polynomial is: D8 + D7 + D4 + D3 + D + 1
    CRC8 = 8,
    // 12 bit CRC. Polynomial is: D12 + D11 + D3 + D2 + D + 1
    CRC12 = 12,
    // 16 bit CRC. Polynomial is: D16 + D12 + D5 + 1
    CRC16 = 16,
    // 24 bit CRC. Polynomial is: D24 + D23 + D6 + D5 + D + 1
    CRC24 = 24
} vcopCRCType;

/**************************************************************************
@Description   vcopFFStruct is the user’s view of the what the encoder
 did before transmitting the data
****************************************************************************/
typedef struct {
    // Polynomial 0 as well as polynomial 3 (if vcopFFStruct.rate equals 6)
    uint8 polynomial0;
    // Polynomial 1 as well as polynomial 4 (if vcopFFStruct.rate equals 6)
    uint8 polynomial1;
    // Polynomial 2 (if vcopFFStruct.rate is larger than 2),
}
as well polynomial 5 (if vcopFFStruct.rate equals 6)
uint8 polynomial2;
// Polynomial 3 (if vcopFFStruct.rate equals 4)
uint8 polynomial3;
// The puncture pattern used when transmitting the encoded data. A '1' specifies an
// unpunctured bit.
uint32 puncturePattern;
// The repetition factor of the puncture pattern. If there is no puncturing set to 0
uint8 puncturePeriod;
// The rate at which the transmitted bits were encoded. The legal values are {2, 3, 4, 6}
uint8 rate;
// The constraint length used when encoding the bits. The legal values are {5, 6, 7, 8, 9}
uint8 constraintLength;
// Defines whether the VCOP should look for the minimum or maximum Path Metrics
minMax min_max;
// The number of interim dumps to be dumped during the Feed Forward session.
// The legal values are 0-12. SEE GENERAL CAUTIONS OF vcopDriver.h!!!
uint8 interimDumps;
// The state to be initialized to the value of vcopFFStruct.initState. This is used to help
// the VCOP reach the correct decision based on previous knowledge the user may have
uint8 initState;
// The value to which vcopFFStruct.initState should be initialized. If no initialization
// is required, set vcopFFStruct.initState to 0x0000
int16 initValue;
// The CRC type used
vcopCRCType crc_type;
uint32 vpmisr;
uint32 vconfr;
}

typedef struct
{
    // The size of the input buffer (in bytes)
    uint16 inputSize;
    // The stage from which to perform the traceback. If automatic traceback is used, this
    // should reflect the last stage in the session
    uint16 tbStage;
    // The mode to use for the traceback. The legal values are 0-7. For details, see the VCOP
    uint8 tbMode;
    // The period to be used for learning. This is used when "stitching" two blocks
    // together.
    // See the VCOP Spec for more information
    uint8 learnPeriod;
    // The state from which to start the Traceback (valid only for odd values of
    // vcopTBStruct.tbMode
    uint8 tbState;
}
vycopTBStruct;
**VCOP Driver**

```c
typedef struct {
    // Each element of the array describes the stage at which an Interim Dump is required
    // that vcopFFStruct.interimDumps enables it. The legal values are 0-255
    uint8 stage[12];
} vcopInterimStruct;

typedef struct {
    // Notifies the driver whether a traceback has been performed from this stage
    bool performed_traceback;
    // Notifies the driver whether the traceback result passed CRC
    bool passed_CRC;
    // The value of Sn (see Eq. 1 in Section A.1.2 of 3GPP TS 25.212)
    fp32 Sn;
    // A pointer to the traceback resulting from this interim dump
    uint32 vobar;
} vcopInterimStage;

typedef struct {
    vcopInterimStage stage_data[12];
    int8 num_of_remaining_BTFD_tracebacks;
    uint8 num_of_BTFD_TB_handled;
    uint16 PM_dump_size;
    uint32 vobar;
} vcopBTFDManagement;

typedef struct {
    // When true, the LPU is reset before the new configuration is programmed
    bool reset;
    // The starting trigger for the LPU counters (see VCOP Spec for more details)
    uint8 startCond;
    // The condition that stops the LPU counters (see VCOP Spec for more details)
    uint8 stopCond;
    // Useless in the MSC8126. Defines whether ipi_int_pmi should assert when the LPU stops
    // counting
    bool genInt;
    // The event during which the LPU counters count (see the MSC8126 Reference Manual for details)
    uint8 event;
} vcopLpuStruct;

typedef struct {
    // Each element of the array describes the stage at which an Interim Dump is required
    // that vcopFFStruct.interimDumps enables it. The legal values are 0-255
    uint8 stage[12];
} vcopInterimStruct;
```

---

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VCOP Driver

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typedef struct
{
    // VCOP Output Address Register (see VCOP Spec for more details)
    uint32 vobar;
    // VCOP Input Buffer Start Address Register (see VCOP Spec for more details)
    uint32 vibsar;
    // VCOP PM Fill Address Register (see VCOP Spec for more details)
    uint32 vpmfar;
    // VCOP Algorithm Assist Dump Address Register (see VCOP Spec for more details)
    uint32 vaadar;
    uint32 equalization_pre_vibsar;
} vcopAddressPointers;

typedef struct
{
    // A pointer to a struct of addresses
    volatile vcopAddressPointers *pointers;
    // Should be true if vcopSessionStruct.ffData has been updated since last session
    bool updateFF;
    // A pointer to the relevant vcopFFStruct
    volatile vcopFFStruct *ffData;
    // Should be true if vcopSessionStruct.tbData has been updated since last session
    bool updateTb;
    // A pointer to the relevant vcopTBStruct
    volatile vcopTBStruct *tbData;
    // Should be true if vcopSessionStruct.visrxData has been updated since last session. If
    // set to FALSE in Equalization sessions, the driver will calculate the S Parameters and
    // the
    // matched filter before activating the VCOP.
    bool updateVisrx;
    // A pointer to the relevant vcopInterimStruct
    volatile void *visrxData;
    // Should be true if LPU should be used this session
    bool updateLpu;
    // A pointer to the relevant vcopLpuStruct
    volatile vcopLpuStruct *lpuData;
} vcopSessionStruct;

typedef struct
{
    volatile uint32 VPOLR;
    volatile uint32 VPPR;
    volatile uint32 VCNT;
    volatile uint32 VOBAR;
    volatile uint32 VIBSAR;
    volatile uint32 VIBBLR;
    volatile uint32 VPMFAR;
    volatile uint32 VPMISR;
    volatile uint32 VISRA;
    volatile uint32 VISRB;
    volatile uint32 VISRC;
    volatile uint32 VAADAR;
    volatile uint32 reserved1[0x0004];
    volatile uint32 VCONF;
    volatile uint32 VSTR;
}
volatile uint8 reserved2[0x03AE];
volatile uint32 VPCR;
volatile uint32 VPCA;
volatile uint32 VPCB;
volatile uint8 reserved3[0x003D];
}

VCOP;

/**************************************************************************/
/*Description PIC and LIC as seen by the core’s QBUS memory map
.reloadData();
/**************************************************************************/
typedef struct
{
  // PIC
  volatile uint16 ELIRA;  /* Edge/Level-Triggered Interrupt Register A */
  volatile uint8 reserved20[6];
  volatile uint16 ELIRB;  /* Edge/Level-Triggered Interrupt Register B */
  volatile uint8 reserved21[6];
  volatile uint16 ELIRC;  /* Edge/Level-Triggered Interrupt Register C */
  volatile uint8 reserved22[6];
  volatile uint16 ELIRD;  /* Edge/Level-Triggered Interrupt Register D */
  volatile uint8 reserved23[6];
  volatile uint16 ELIRE;  /* Edge/Level-Triggered Interrupt Register E */
  volatile uint8 reserved24[6];
  volatile uint16 ELIRF;  /* Edge/Level-Triggered Interrupt Register F */
  volatile uint8 reserved25[6];
  volatile uint16 IPRA;   /* Interrupt Pending Register A */
  volatile uint8 reserved26[6];
  volatile uint16 IPRB;   /* Interrupt Pending Register B */
  volatile uint8 reserved27[14];
  volatile uint8 reserved28[4024];

  // LIC
  volatile uint32 LICAICR0;  /* LIC Group A Interrupt Configuration Register 0 */
  volatile uint8 reserved29[4];
  volatile uint32 LICAICR1;  /* LIC Group A Interrupt Configuration Register 1 */
  volatile uint8 reserved30[4];
  volatile uint32 LICAICR2;  /* LIC Group A Interrupt Configuration Register 2 */
  volatile uint8 reserved31[4];
  volatile uint32 LICAICR3;  /* LIC Group A Interrupt Configuration Register 3 */
  volatile uint8 reserved32[4];
  volatile uint32 LICAIER;   /* LIC Group A Interrupt Enable Register */
  volatile uint8 reserved33[4];
  volatile uint32 LICAISR;   /* LIC Group A Interrupt Status Register */
  volatile uint8 reserved34[4];
  volatile uint32 LICAISER;  /* LIC Group A Interrupt Error Status Register */
  volatile uint8 reserved35[12];
  volatile uint32 LICBICR0;  /* LIC Group B Interrupt Configuration Register 0 */
  volatile uint8 reserved36[4];
  volatile uint32 LICBICR1;  /* LIC Group B Interrupt Configuration Register 1 */
  volatile uint8 reserved37[4];
  volatile uint32 LICBICR2;  /* LIC Group B Interrupt Configuration Register 2 */
  volatile uint8 reserved38[4];
  volatile uint32 LICBICR3;  /* LIC Group B Interrupt Configuration Register 3 */
  volatile uint8 reserved39[4];
  volatile uint32 LICBIER;   /* LIC Group B Interrupt Enable Register */
  volatile uint8 reserved40[4];
  volatile uint32 LICBISR;   /* LIC Group B Interrupt Status Register */
  volatile uint8 reserved41[4];
  volatile uint32 LICBIESR;  /* LIC Group B Interrupt Error Status Register */
  volatile uint8 reserved42[0x4f8C];
}

msc8126_qbus_t;
typedef struct
{
    // A pointer to the VCOP's base address. Set to VCOP_BASE_ADDRESS in
    // vcop_initializeDriver(vcopStruct*)
    volatile VCOP                *vcop_regs;
    // A pointer to the current session. This pointer is updated whenever
    // vcop_Ioctl(void*, uint8, void*) is called
    volatile vcopSessionStruct   *session;
    // A pointer to the function the user wants the driver to call when sessions end
    USER_FUNCTION_VARS_TYPE      (*user_end_of_session)(USER_FUNCTION_VARS_TYPE,
                                              USER_FUNCTION_VARS_TYPE);
    vcopBTFDManagement            btfd_management;
} vcopStruct;

typedef struct
{
    vcopStruct        *dev_ch;
    vcopStatus         status;
} vcopSessionStatus;

typedef enum configType
{
    // Analyze a vcopFFStruct structure
    configFF,
    // Analyze a vcopTBStruct structure
    configTB,
    // Analyze a vcopInterimStruct structure
    configBTFD,
    // Analyze a vcopSParamSrtuct structure
    configSParam,
    // Analyze a vcopLPUStruct structure
    configLPU
} configType;
VCOP Driver

(vc)op initializes Driver

@Function vcop_initialDriver
@Description Initializes the Driver.
@Param dev_ch - A pointer to the driver’s view of the VCOP and the session
@Return The status of the initialization.

vcopStatus vcop_initializeDriver(vcopStruct* dev_ch);

(vc)op createConfig

@Function vcop_createConfig
@Description Translates the user’s view of the session to the VCOP’s view.
@Param type - The type of translation requested (use a value from the configType enumeration)
@Param dev_ch - A pointer to the driver view of the VCOP and the session
@Cautions Each call programs one or more registers in the VCOP, so unnecessary calls should be avoided because of timing.

void vcop_createConfig(configType type, vCopStruct *dev_ch);

(vc)op I/Octl

@Function vcop_Ioctl
@Description Programs the VCOP to perform a session.
@Param dev_ch - A pointer to the driver view of the VCOP and the session
@Param ioctl - The session to be run. The value of ioctl is equivalent to the value of VCONFR:CMD. A list of values and their meaning can be found in the VCOP chapter of the MSC1826 Reference Manual.
@Param param - A pointer to the current session to be run. This pointer is copied to dev_ch->session.
@Return The status of the configuration.
@Cautions If the function does not return VCOP_SUCCESS, the user callback function is not called for this session.

vcopStatus vcop_Ioctl(void *dev_ch, uint8 ioctl, void *param);

(vc)op _params and _filter

@Function generate_s_params_and_mf
@Description Calculates the S Parameters for equalization and performs the matched filter on the incoming data.
@Param dev_ch - A pointer to the driver view of the VCOP and the session.

void generate_s_params_and_mf (vcopStruct* dev_ch);

(vc)op IPI_INT_ABORT

@Function ACK_IPI_INT_ABORT
@Description Acknowledges an Abort interrupt.

void ACK_IPI_INT_ABORT();

(vc)op IPI_INT_PROTOCOL

@Function ACK_IPI_INT_PROTOCOL
@Description Acknowledges a Protocol interrupt.

void ACK_IPI_INT_PROTOCOL();

(vc)op DOUBLE_EDGE_PROTOCOL

@Function ACK_DOUBLE_EDGE_PROTOCOL
@Description Acknowledges a second edge Protocol interrupt.

void ACK_DOUBLE_EDGE_PROTOCOL();

(vc)op INTERRUPTS LIC

@Function ENABLE_VCOP_INTERRUPTS_LIC
@Description Enables VCOP interrupts via the LIC.

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4.4 Driver Source Code

#include "vcopDriver.h"
volatile vcopStruct *global_dev_ch;
#define VCOP_PLACE_IN_MEM (void*)VCOP_BASE_ADDRESS
VCOP *vcop_place_holder = (VCOP*)VCOP_PLACE_IN_MEM;
#define QBUS_PLACE_IN_MEM (void*)QBUS_BASE_ADDRESS
msc8126_qbus_t *qbus_place_holder = (msc8126_qbus_t*)QBUS_PLACE_IN_MEM;

void ACK_IPI_INT_ABORT()
{
    WRITE_UINT32(qbus_place_holder->LICAISR, 0x08000000);
    WRITE_UINT16(qbus_place_holder->IPRA, 0x0040);
    return;
}
5 VCOP Code Examples

Examples in this section demonstrate how to set up a 3GPP and CDMA2000 session using the VCOP driver. All the functions called from within the code can be found in Section 4.2, Driver Functions, on page 22. Section 5.4 shows a short interrupt handling session that also calls on functions described in Section 4.2.

5.1 VCOP Driver in GSM Equalization and GSM Decoding Session

```c
#include "vcopDriver.h"
#include "vcopCallBackFunctions.h"
#include <stdio.h>
#include "sova_test0_data.h"
#include "gsm_test0_data.h"
volatile bool send_next_session;

int main ()
{
    vcopStruct        dev_ch;
    vcopStatus          vcop_status;
    vcopFFStruct        decoding0_ff,       decoding1_ff;
    // Description An example of a user's application.
    // - First session - plain SOVA (16 stage recursive)
    // - Next session - GSM. 32 recursive SOVA leading to plain decoding
```
vcopTBStruct decoding0_tb, decoding1_tb;
// vcopInterimStruct decoding0_btf, decoding1_btf;
vcopAddressPointers decoding0_pointers, decoding1_pointers;
vcopSessionStruct decoding0, decoding1;
vycopFFStruct equalization0_ff, equalization1_ff;
vycopTBStruct equalization0_tb, equalization1_tb;
vycopSParamStruct equalization0_sparam, equalization1_sparam;
vycopAddressPointers equalization0_pointers, equalization1_pointers;
vycopSessionStruct equalization0, equalization1;
send_next_session = FALSE;
*************************************************************************/
/*  VCOP Channel (dev_ch) Setup                           */
*************************************************************************/
vycop_status = vcop_initializeDriver(&dev_ch);
if (vcop_status != VCOP_SUCCESS)
{
    printf("Couldn't initialize VCOP driver!!!\n");
    return 0;
}
dev_ch.user_end_of_session = cbSessionDone;
*************************************************************************/
/*  Session Setup (GSM - SOVA part)                           */
*************************************************************************/
equalization1_ff.polynomial0 = 0;
equalization1_ff.polynomial1 = 0;
equalization1_ff.polynomial2 = 0;
equalization1_ff.polynomial3 = 0;
equalization1_ff.puncturePattern = 0x00000000;
equalization1_ff.puncturePeriod = 0;
equalization1_ff.initState = 0;
equalization1_ff.initValue = 0;
equalization1_ff.rate = 2;
equalization1_ff.min_max = MAX;
equalization1_ff.constraintLength = 6;
equalization1_ff.interimDumps = 0;
equalization1_tb.inputSize = 228;
equalization1_tb.tbStage = 113;
equalization1_tb.tbMode = 6;
equalization1_tb.learnPeriod = 0;
equalization1_tb.tbState = 0x00;
equalization1_sparam.slot = 1;
equalization1_pointers.equalization_pre_vibsar = (uint32)&gsm_pre_vibsar0[0];
equalization1_pointers.vibsar = (uint32)&gsm_vibsar0[0];
equalization1_pointers.vaadar = (uint32)&gsm_vaadar0[0];
equalization1_pointers.vobar = (uint32)&gsm_vobar0[0];
equalization1_pointers = &equalization1_pointers;
equalization1.updateFF = TRUE;
equalization1.ffData = &equalization1_ff;
equalization1.updateTb = TRUE;
equalization1.tbData = &equalization1_tb;
equalization1.updateVisrx = FALSE;
equalization1.visrxData = (void*)&equalization1_sparam;
equalization1.updateLpu = FALSE;
*************************************************************************/
/*  Run the first part (SOVA) of the fourth session (GSM) */
*************************************************************************/
vycop_status = vcop_Ioctl((void*)&dev_ch, 0x29, (void*)&equalization1);
if (vcop_status != VCOP_SUCCESS)
{
    printf("Couldn't run session SOVA part of session 4 (GSM)!!!\n");
send_next_session = TRUE;
}

/************************ Session Setup (GSM - Decoding part) ************************/
/*
  Session Setup (GSM - Decoding part)                       */
/*************************************************************************/

decoding0_ff.polynomial0      = 0x09;
decoding0_ff.polynomial1      = 0x0D;
decoding0_ff.polynomial2      = 0;
decoding0_ff.polynomial3      = 0;
decoding0_ff.puncturePattern  = 0x000000;
decoding0_ff.puncturePeriod   = 0;
decoding0_ff.initState        = 0;
decoding0_ff.initValue        = 0;
decoding0_ff.rate             = 2;
decoding0_ff.min_max          = MAX;
decoding0_ff.constraintLength = 5;
decoding0_ff.interimDumps     = 0;
decoding0_ff.crc_type         = CRC0;
decoding0_tb.inputSize   = 114;
decoding0_tb.tbStage     = 113;
decoding0_tb.tbMode      = 0;
decoding0_tb.learnPeriod = 0;
decoding0_pointers.vibsar   = (uint32)&gsm_vibsar0[0];
decoding0_pointers.vobar    = (uint32)&gsm_vobar0[0];
decoding0_pointers          = &decoding0_pointers;
decoding0.updateFF           = TRUE;
decoding0.ffData             = &decoding0_ff;
decoding0.updateTb           = TRUE;
decoding0.tbData             = &decoding0_tb;
decoding0.updateVisrx        = FALSE;
decoding0.updatelpu          = FALSE;

/**************************** Wait for Session (GSM - SOVA) to End ****************************/
/*
  Wait for Session (GSM - SOVA) to End                       */
/*************************************************************************/

while(send_next_session == FALSE);
send_next_session = FALSE;

/**************************** Run the second part (Decoding) of the fourth session (GSM) ****************************/
/*
  Run the second part (Decoding) of the fourth session (GSM)                      */
/*************************************************************************/

vcop_status = vcop_Ioctl((void*)&dev_ch, 0x25, (void*)&decoding0);
if (vcop_status != VCOP_SUCCESS)
{
    printf("Couldn't run session Decoding part of session 4 (GSM)!!!\n");
    send_next_session = TRUE;
}

/**************************** Wait for Fourth Session (GSM - Decoding) to End ****************************/
/*
  Wait for Fourth Session (GSM - Decoding) to End                       */
/*************************************************************************/

while(send_next_session == FALSE);
send_next_session = FALSE;

/**************************** End of program *****************************/
/*************************************************************************/

return 0;
5.2 Pre-Equalization Tasks

// @Description Equalization preliminary activities.
KERNEL
#include "vcopDriver.h"
// Array of Training Sequences, one per slot
volatile const uint8 tsc[] = {
    0,0,1,0,1,0,1,1,0,0,0,1,0,0,1,0,1,0,1,1,1,
    0,0,1,0,1,1,0,1,1,1,0,1,0,1,1,0,0,0,1,0,1,1,1,
    0,1,0,0,0,0,1,1,1,0,1,1,0,1,0,1,0,0,0,0,1,1,1,0,
    0,1,0,0,0,1,1,1,0,1,1,0,1,0,0,0,1,0,0,0,1,1,1,1,0,
    0,0,0,1,1,0,1,1,0,1,0,0,0,0,0,1,1,1,1,0,1,0,0,1,1,1,0,
    1,0,1,0,0,1,1,1,0,1,1,0,0,0,0,1,0,0,1,1,0,1,1,1,1,0,
    1,1,1,0,1,1,1,0,0,0,1,0,1,1,1,1,0,1,1,1,1,0,1,1,1,0,1,
    1,1,1,0,1,1,1,0,0,1,0,0,1,0,1,1,1,1,0,1,1,1,1,1,0,0
};
volatile int8 vect[] = {
    0,0,0,0,0,0,0,0,
    0,0,0,0,0,0,0,0,
    0,0,0,0,0,0,0,0,
    0,0,0,0,0,0,0,0,
    0,0,0,0,0,0,0,0,
    0,0,0,0,0,0,0,0,
    0,0,0,0,0,0,0,0,
    0,0,0,0,0,0,0,0,
    0,0
};
void generate_s_params_and_mf (vcopStruct* dev_ch)
{
    volatile vcopSessionStruct *session = (vcopSessionStruct*)dev_ch->session;
    volatile vcopSParamStruct *sParamData = (vcopSParamStruct*)session->visrxData;
    int16 *sp = (int16*)sParamData->sParams;
    int16 *data_buf = (int16*)session->pointers->equalization_pre_vibsar;
    int16 *data_buf_mf = (int16*)session->pointers->vibsar;
    uint8 k = session->ffData->constraintLength;
    int8 i,j;
    int16 *tsrx; // Pointer to the TS in the data_buf
    int16 tsmf[26]; // TS after Matched Filter.
    int32 tsmf_tmp; // Has to use 32 bits for the calculation, before devision
    int16 cir_[7]; // Effective Coeficiantes
    int32 sp_tmp; // Has to use 32 bits for the calculation, before devision
    int16 tsrx_[121]; // This is the actual data, without the TS, with some padding
    int32 data_buf_mf_tmp;
    // Pointer to the Training Sequence in the recieved data.
    tsrx = data_buf + 57;
    // Useing only the middle 16 bits of the TS. Flip their order and padd with
    // zeros for convolution calculation.
    for (i=0; i<16; i++)
        vect[25+i] = 1 - 2 * (int8)tsc[(sParamData->slot * 26) + 20 - i];
    // Convolution
    for (i=0; i<26; i++)
    {
        tsmf_tmp = 0;
        for (j=0; j<26; j++)
            tsmf_tmp += tsrx[j] * vect[25 + i - j];
        tsmf[i] = tsmf_tmp / 16;
    }
// Prepare the vector of effective coefficients for the S calculation.
for (i=0; i<7; i++)
  if (i<k)
    cir[i] = tsmf[20+i];
  else
    cir[i] = 0;

// SP Calculation
for (i=0; i<6; i++)
{
  if (i >= k)
    sp[i] = 0;
  else
  {
    sp_tmp = 0;
    for (j=0; j<k-1-i; j++)
      sp_tmp = sp_tmp + cir[j]*cir[j+i+1];
    sp[i] = sp_tmp / 16384;
  }
}

// Create the actual data vector
// First remove the TS
for (i=0; i<57; i++)
{
  tsrx[i] = data_buf[i];
  tsrx[i+57] = data_buf[i+57+26];
}

// Then add padding for calculation purposes
for (i=0; i<7; i++)
  tsrx[i+114] = 0;

// Perform the Matched Filter
for (i=0; i<114; i++)
{
  data_buf_mf_tmp = 0;
  for (j=0; j<k; j++)
    data_buf_mf_tmp = data_buf_mf_tmp + cir[j]*tsrx[j+i];
  data_buf_mf[i] = data_buf_mf_tmp / 16384;
  data_buf_mf[i] = data_buf_mf[i] / 32768; // 2^15
  data_buf_mf[i] = ((data_buf_mf[i] & 0xFF00) >> 8) | ((data_buf_mf[i] & 0x00FF) << 8);
}
return;
}

5.3 Driver Functions for Handling SOVA
//@Description Implementation of VCOP Driver internal functions for SOVA handling
*/
#include "vcopDriver.h"
#ifdef USE_DSP_COMPLEMETARY_TASKS
#include "vcopDriverComplementaryTasks.h"

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// Soft Output Viterbi Algorithm

// ++++++++++++++++++++++++++++++++

// tb_head : Pointer to the buffer of regular traceback

// tb_rec  : Pointer to the buffer of recursive traceback.

// delta   : Pointer to the buffer of Delta values

// tbndx   : Total number of stages [0..Num of stages-1]

// k       : Number of taps in filter (5,6,7)

// state   : Index number of state to start from [0..2^(k-1)-1]

// soft_output : Pointer to allocated memory buffer for results of SOVE, soft

// output for the decoding stage, byte size signed values

void perform_SOVA_16 (vcopStruct* dev_ch)
{

#pragma opt_level = "O0"

volatile vcopSessionStruct *session = (vcopSessionStruct*)dev_ch->session;

uint8 *tb_head = (uint8*)session->pointers->vobar;
uint8 *delta = (uint8*)session->pointers->vaadar;
int8 *soft_output = (int8*)session->pointers->vibsar;
uint16 tbndx = session->tbData->tbStage;
uint8 k = session->ffData->constraintLength;

uint8* tb_rec;
uint8 k_array[] = {0, 0, 0, 0, 8, 16, 32, 64}; // Lookup table for num. of stages
uint8* tb_ptr = tb_head; // Pointer to the relevant word in the TB buffer
uint8 tb_word; // The effective TB word
uint8 tb_next_word; // The next (previous in order) TB word from the buffer
uint16 tb_internal_word; // TB word to be used within the recursion
uint16 tb_internal_next_word; //
uint16 rec_word; // The current Recursive word
int16 current_stage; //

static const int8 inf8 = 0x7f;

if (session->tbData->tbMode & 0x1)
    state = session->tbData->tbState;
else
{
    uint32 vstr_tmp;
READ_UINT32(vstr_tmp, dev_ch-&gt;vcop_regs-&gt;VSTR);

    state = (uint8)(vstr_tmp &gt;&gt; 24);
}

// Update the start of the traceback data according to size of dumped history buffer
if (session-&gt;ffData-&gt;vconfr &amp; 0x08000000)
{
    tb_head += (k_array[k] * (tbndx + 1)) &gt;&gt; 3;
    tb_head += ((k_array[k] * (tbndx + 1)) &amp; 0x003F) ? 1 : 0;
}

    tb_rec = tb_head + (((tbndx &gt;&gt; 6) + ((tbndx &amp; 0x003F) ? 1 : 0))) &lt;&lt; 3;

// Adjust according to bug of offset on recursive data start. Bug Id : MSIIs13510
    tb_rec += 2*((k-2*(k-6)+(tbndx+1)) &amp; 4);

// Point to the end of the buffer because TB is done backwards.
    delta += tbndx * k_array[k];

// Align the full TB to the starting point.
// Prepare initial TB word and shift the next to be usefull.
    tb_ptr += 8 - ((tbndx &amp; 0x003F) &gt;&gt; 3) - (tbndx &amp; 0x07);
    tb_word = *tb_ptr++;(8 - ((tbndx+1) &amp; 0x07));
    tb_next_word = *tb_ptr++;

    tb_word += tb_next_word<<<((tbndx+1) &amp; 0x07);
    tb_next_word &gt;&gt;= (8 - ((tbndx+1) &amp; 0x07));

// Initialize the vector to infinity.
for (current_stage=0; current_stage&lt;=tbndx; current_stage++)
    soft_output[current_stage] = inf8;

// This is the recursive loop
for (current_stage=tbndx-(k-1); current_stage&gt;0 ; current_stage--)
{
    uint16 rec_stages;
    uint16 internal_ptr;
    // Prepare the recursive TB word
    rec_word = *tb_rec++ &amp; 0x00FF;
    rec_word += ((*tb_rec++ &amp; 0x00FF) &lt;&lt; 8);

    // Prepare the current TB word
    tb_internal_word = *tb_ptr;
```c
    tb_internal_word <<= ((current_stage+k) & 0x07);
    tb_internal_word += tb_next_word;
    tb_internal_word <<= 8-(k-1);
    tb_internal_word += (tb_word >> (k-1));
    tb_internal_next_word = *(tb_ptr+1);
    tb_internal_next_word <<= (16 - (k-1) + ((current_stage+k) & 0x07));
    tb_internal_word += tb_internal_next_word;

    if (current_stage == 0)
        rec_stages = 1;
    else if (current_stage < 16)
        rec_stages = current_stage;
    else
        rec_stages = 16;
    for (internal_ptr=0; internal_ptr<rec_stages; internal_ptr++)
    {
        if (((tb_internal_word & 0x01) != (rec_word & 0x01)) &&
            (soft_output[current_stage-internal_ptr] > (int8)(delta[state] >> 1)))
            soft_output[current_stage-internal_ptr] = (int8)(delta[state] >> 1);
        tb_internal_word>>=1;
        rec_word>>=1;
    } // internal_ptr

delta -= k_array[k];
state = (state>>1) + (k_array[k-1])*((tb_word>>(k-1)) & 0x01);
if (!(((current_stage+k) & 0x07)) // Word is empty, get the next word from mem.
    tb_next_word = *tb_ptr++;
    tb_word >>= 1;
    tb_word += (tb_next_word & 0x01)<<7;
    tb_next_word >>= (8 - ((tbndx+1) & 0x07));
for (current_stage=tbndx+1; current_stage>0 ; current_stage--)
{
    if (tb_word & 0x01)
        soft_output[current_stage-1] = -soft_output[current_stage-1];
    if (!(((current_stage) & 0x07)) // Word is empty, get the next word from mem.
        tb_next_word = *tb_ptr++;
        tb_word >>= 1;
        tb_word += (tb_next_word & 0x01)<<7;
        tb_next_word>>=1;
} // Sign the vector
    return;
```
void perform_SOVA_32 (vcopStruct* dev_ch)
{
    #pragma opt_level = "O0"
    volatile vcopSessionStruct *session = (vcopSessionStruct*)dev_ch->session;
    uint8 *tb_head = (uint8*)session->pointers->vobar;
    uint8 *delta = (uint8*)session->pointers->vaadar;
    int8 *soft_output = (int8*)session->pointers->vibsar;
    uint16 tbndx = session->tbData->tbStage;
    uint8 k = session->ffData->constraintLength;
    uint8 state;

    uint8* tb_rec;
    uint8 k_array[] = {0, 0, 0, 0, 8, 16, 32, 64}; // Lookup table for num. of stages
    uint8* tb_ptr = tb_head; // Pointer to the relevant word in the TB buffer
    uint8 tb_word; // The effective TB word
    uint8 tb_next_word; // The next (previous in order) TB word from the buffer
    uint32 tb_internal_word; // TB word to be used within the recursion
    uint32 tb_internal_next_word;
    uint32 rec_word; // The current Recursive word
    int16 current_stage;
    static const int8 inf8 = 0x7f;

    if (session->tbData->tbMode & 0x1)
        state = session->tbData->tbState;
    else
    {
        uint32 vstr_tmp;
        READ_UINT32(vstr_tmp, dev_ch->vcop_regs->VSTR);
        state = (uint8)(vstr_tmp >> 24);
    }

    // Update the start of the traceback data according to size of dumped history buffer
    if (session->ffData->vconfr & 0x08000000)
    {
        tb_head += (k_array[k] * (tbndx + 1)) >> 3;
        tb_head += ((k_array[k] * (tbndx + 1)) & 0x003F) | 0;
    }
    tb_rec = tb_head + (((tbndx >> 6) + ((tbndx & 0x003F) ? 1 : 0)) << 3);

    // Adjust according to bug of offset on recursive data start. Bug Id : MSI1s13510
    tb_rec += 4*((k+tbndx) % 2);
    // Point to the end of the buffer because TB is done backwards.
    delta += tbndx * k_array[k];

    // Align the full TB to the starting point.
    // Prepare initial TB word and shift the next to be usefull.
    tb_ptr += 8 - ((tbndx & 0x003F) >> 3) - (tbndx & 0x07);
    tb_word = *tb_ptr++>>(8 - ((tbndx+1) & 0x07));
tb_next_word = *tb_ptr++;  
tb_word += tb_next_word<<((tbndx+1) & 0x07);  
tb_next_word >>= (8 - ((tbndx+1) & 0x07));

// Initialize the vector to infinity.  
for (current_stage=0; current_stage<=tbndx; current_stage++)  
    soft_output[current_stage] = inf8;  
// This is the recursive loop  
for (current_stage=tbndx-(k-1); current_stage>=0 ; current_stage--)  
{
    uint16 rec_stages;  
    uint16 internal_ptr;

    // Prepare the recursive TB word
    rec_word = *tb_rec++ & 0x00FF;
    rec_word += ((*tb_rec++ & 0x00FF) << 8);
    rec_word += ((*tb_rec++ & 0x00FF) << 16);
    rec_word += ((*tb_rec++ & 0x00FF) << 24);  

    // Prepare the current TB word
    tb_internal_word = *tb_ptr;  
    tb_internal_word += *(tb_ptr+1) << 8;  
    tb_internal_word += *(tb_ptr+2) << 16;  
    tb_internal_word <<= ((current_stage+k) & 0x07);  
    tb_internal_word += tb_next_word;  
    tb_internal_word <<= 8-(k-1);  
    tb_internal_word += (tb_word >> (k-1));  
    tb_internal_next_word = *(tb_ptr+3);  
    tb_internal_word += tb_internal_next_word & 0xff000000;

    if (current_stage == 0)
        rec_stages = 1;  
    else if (current_stage < 32)  
        rec_stages = current_stage;  
    else
        rec_stages = 32;  
    for (internal_ptr=0; internal_ptr<rec_stages; internal_ptr++)
    {
        if (((tb_internal_word & 0x01) != (rec_word & 0x01)) &&
            (soft_output[current_stage-internal_ptr] > (int8)(delta[state] >> 1)))
            soft_output[current_stage-internal_ptr] = (int8)(delta[state] >> 1);
        tb_internal_word>>=1;  
        rec_word>>=1;
    }  // internal_ptr

delta -= k_array[k];  
state = (state>>1) + (k_array[k-1])*((tb_word>>(k-1)) & 0x01);  
if (!(((current_stage+k) & 0x07))) // Word is empty, get the next word from mem.
    tb_next_word = *tb_ptr++;
    tb_word >>= 1;  
    tb_word += (tb_next_word & 0x01)<<7;  
    tb_next_word>>=1;
}  // The recursive loop

// Quantize the vector - devide by 2 and add sign  
//for (current_stage=0; current_stage<=tbndx; current_stage++)  
//    soft_output[current_stage] /= 2;

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// Sign the vector according to the TB bits.
tb_ptr = tb_head + 8 - ((tbndx & 0x003F) >> 3) - (tbndx & 0x07);
tb_word = *tb_ptr++>>(8 - ((tbndx+1) & 0x07));
tb_next_word = *tb_ptr++;
tb_word += tb_next_word<<((tbndx+1) & 0x07);
tb_next_word >>= (8 - ((tbndx+1) & 0x07));
for (current_stage=tbndx+1; current_stage>0 ; current_stage--)
{
    if ((tb_word & 0x01))
        soft_output[current_stage-1] = -soft_output[current_stage-1];
    if (((current_stage) & 0x07)) // Word is empty, get the next word from mem.
        tb_next_word = *tb_ptr++;
    tb_word >>= 1;
    tb_word += (tb_next_word & 0x01)<<7;
    tb_next_word >>=1;
} // Sign the vector
return;
} // perform_SOVA_32
#endif // USE_DSP_COMPLEMETARY_TASKS

5.4 Interrupt Handling

// VCOP driver include file
#include "vcopDriver.h"
/*
***********************************************************************/
/*ipi_int_abort Handler*/
void HWI_vcop_abort_handler (os_hwi_arg dev_ch)
{
    // Acknowledge the Interrupt
    ACK_IPI_INT_ABORT();
    // Call the VCOP drivers’ end of session function
    session_done(SESSION_ABORTED);
    return;
}
/*
***********************************************************************/
/*ipi_int_protocol Handler*/
void HWI_vcop_protocol_handler(os_hwi_arg dev_ch)
{
    // Acknowledge the Interrupt
    ACK_IPI_INT_PROTOCOL();
    // Call the VCOP drivers’ end of session function
    session_done(VCOP_SUCCESS);
    return;
}

5.5 VCOP Interrupt Handlers for Equalization

// @Description Handling of hardware interrupts
// The interrupt handlers call on functions to
// perform the actual handling.
#include "vcopDriver.h"
#ifdef USE_DSP_COMPLEMETARY_TASKS
    #include "vcopDriverComplementaryTasks.h"
#endif
extern volatile vcopStruct *global_dev_ch;
volatile bool continue_int_handling;
/*
***********************************************************************/
/*************************************************************************************/
void HWI_vcop_abort_handler (os_hwi_arg dev_ch) {
    ACK_IPI_INT_ABORT();
    session_done(SESSION_ABORTED);
    return;
}

/***********************************************************************************/
void HWI_vcop_protocol_handler(os_hwi_arg dev_ch) {
    #ifdef USE_DSP_COMPLEMETARY_TASKS
    /*******************************************************************************/
    /* Handle an interrupt with Interim Dumps specially */
    /*******************************************************************************/
    if (global_dev_ch->session->ffData->interimDumps)
    {
        // If ipi_int_ff, set the tracebacks in to motion
        continue_int_handling = FALSE;
        perform_BTFD_traceback(global_dev_ch, 0);
        while (global_dev_ch->btfd_management.num_of_remaining_BTFD_tracebacks > 0)
        {
            while (continue_int_handling == FALSE);
            continue_int_handling = FALSE;
            perform_CRC_on_stage(global_dev_ch);
        }
        // analyse the last stage
        perform_CRC_on_stage(global_dev_ch);
        analyze_all_BTFD_TB(global_dev_ch);
    }
    /*******************************************************************************/
    /* Handle an interrupt with SOVA specially */
    /*******************************************************************************/
    else if ((global_dev_ch->session->tbData->tbMode & 0x04) && (global_dev_ch->session->ffData->vconfr & 0x04000000))
    {
        if (global_dev_ch->session->tbData->tbMode & 0x02)
            perform_SOVA_32((vcopStruct*)global_dev_ch);
        else
            perform_SOVA_16((vcopStruct*)global_dev_ch);
        session_done(VCOP_SUCCESS);
    }
    /*******************************************************************************/
    /* Handle a regular interrupt */
    /*******************************************************************************/
    else
    #endif // USE_DSP_COMPLEMETARY_TASKS
    ACK_IPI_INT_PROTOCOL();
    session_done(VCOP_SUCCESS);
    return;
}

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/* ipi_int_protocol Second Edge Handler */
/* *********************************************/
void HWI_vcop_protocol_second_edge_handler(os_hwi_arg dev_ch)
{
    continue_int_handling = TRUE;
    ACK_DOUBLE_EDGE_PROTOCOL();
    return;
}

6 Local Profiling Unit (LPU)

The local profiling unit of the VCOP contains three registers, as follows:

- VPCR is the control register for the profiling monitor unit of the VCOP. The register should be programmed while the VCOP is in the IDLE mode, prior to issuing any command to the VCONFR.
- Viterbi Coprocessor Performance Monitor Counter A (VPCA). Counts the total number of cycles for this session of performance monitoring. This register can only be read when the performance monitoring session is complete. The value is read from inside the VCOP, so it is updated according to the internal clock. The data is stable and valid to be read only after the interrupt is issued.
- Viterbi Coprocessor Performance Monitor Counter B (VPCB). Counts the total number of cycles for the monitored event. For example, it counts the total number of cycles the VCOP spends waiting for ipm_req_ack. When the number of cycles of the monitored event is divided by the total number of cycles from the VPCA, the result is a percentage of time used for the monitored event. This register can be read only when the performance monitoring session completes. The value is read from inside the VCOP, so it is updated according to the internal clock. The data is stable and valid to be read only after the interrupt is issued.

7 References

[7] Initializing the MSC8101 Communications Processor Module and Using Pin_mux8101 (AN1854). This Freescale application note describes how to use Pin_mux8101 to initialize the MSC8101 CPM I/O. Both this application note and the software that accompanies it are available at the web site listed on the back cover of this application note.