



Politecnico di Torino

Electronic engineering

Master theses

CIC filter design with HLS

Master degree in Electronic Engineering

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Abstract

The thesis work is based on the use of the High-Level-Synthesis methodology and focuses on the use of an High-Level-Synthesis tool, Mentor Catapult, to apply the HLS design methodology to an industrial application. In collaboration with the company Silicon Mitus, a CIC filter is developed. The CIC filter is one of the upstream filters in an high-performance DAC for audio application, developed by Silicon Mitus. The thesis goal is to prove that an architecture designed with HLS design methodology, can achieve performance in terms of area, power consumption and timing, which are comparable with the one obtained by an architecture, designed with the classical RTL design flow. The thesis work starts with an introduction to HLS, explaining its concepts, the structures of HLS tools and its advantages over those of RTL design flow. An overview on the structures and the frequency behaviour of the CIC filters is reported, with different CIC filter state-of-the-art architectural solutions. Finally the description of the design flow is introduced and the final results are discussed.

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CHAPTER 1

High-Level-Synthesis and Mentor Catapult

1.1 High-Level-Synthesis

Digital electronic systems have grown their complexity and this trend will only increase in the next future. This aspect of the digital design with the increasing capability of silicon technology, leads to a high effort from hundreds of engineers and very expensive projects in terms of time and cost. The request of short time-to-market reduces a product development time and the productivity per engineer has to increase to allow the development and the optimization of products.

Designs developed with hardware description language will eventually become impractical because of the growing complexity of the systems. These reasons have forced design methodologies and tools to rise the abstraction description levels. In particular, designers would use High-Level-Language (HLL) to describe the algorithm, instead of using hand-written Verilog or VHDL code, describing a RTL architecture.

Typically, design projects start with some kind of specification. An executable code is created in HLL (typically MATLAB and C), providing *functional* specification. The first step of a design using traditional methodologies is to define an optimal architecture, and as a consequence to describe the architecture using hardware description language as Verilog or VHDL. This fully-manual approach hides very big problems: first, to find an optimal architecture is challenging, then manual interventions may cause errors, involving behavioural *bugs*.

High-Level-Synthesis is a design methodology that generates register-transfer level description from behavioural specification. More precisely, the HLS tool performs a translation of the high-level code into RTL-code starting from the description in an high-level programming language (C++, C, SystemC and others).

1.1.1 Advantage of High-Level-Synthesis

Reducing design and Verification effort

By working with HLS, designers need to worry only about the desired behaviour and not about implementation details, as clock, technology and so on. HLS tools allow to accelerate the design process and to reduce the verification effort. Verification can be done by writing few lines of code. Even if the HLS eliminates the manual intervention of the RTL code, it continues to guarantee some decisions that a designer could take, as the level of parallelism, the proper architecture (performing *pipelining*, *re-timing* for example) and so on.

With HLS, it is possible to obtain correct RTL code, in a small amount of time.

More effective reuse

Since clock, technology and micro-architecture are automatically added by the HLS tool, changes can be made and verified more easily, without time-consuming problems as re-writing the code, the state machine or breaking a pipeline.

Investing R&D resources

HLS leads an important advantage: the research and development resources can be spent to create new algorithm and optimization, instead of writing RTL code. Features superiority, performance and low cost can be easily achieved rising the abstraction level.

1.1.2 HLS flow description

In Figure 1.1 a typical High-Level-Synthesis flow is described. The flow depends on the tool but typically most of the tools use this approach for the synthesis.

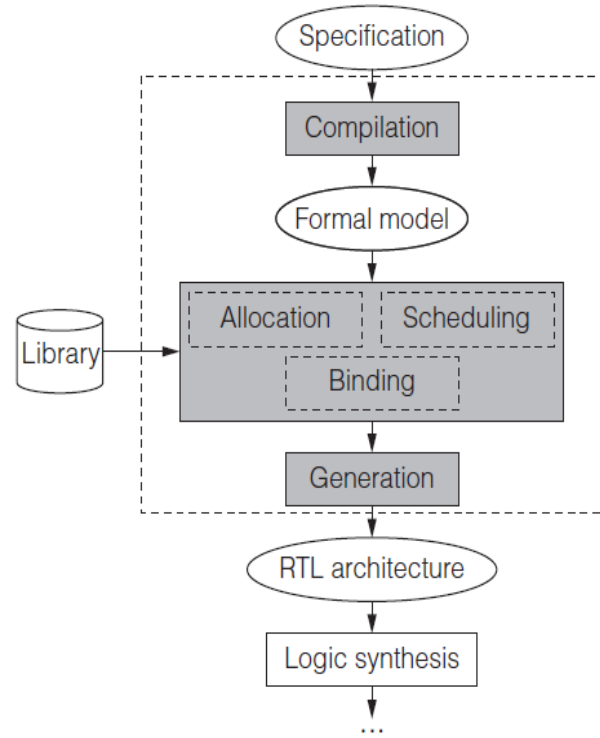


Figure 1.1: HLS flow [1]

Compilation

The first step is the code compilation. Compilation typically includes other optimization codes as dead-code elimination or false data dependency elimination. A formal model is created by compiling the code. It contains informations about loops iterations, data dependencies and parallel structure in the HLL code. The compilation step produces a data flow graph (DFG), explaining all the data dependencies and the operations. DFG representation is extended by using control DFGs (CDFG) used to represent the control flow between the basic blocks and the data dependencies inside them.

Allocation

The allocation step provides the number and the type of allocated resources. This is not the unique step for resources allocation. Some resources could be added during the scheduling and the binding step. The allocation is done using the components of a specified library, where also timing power and area properties of the components are

contained.

Scheduling

The functional operations are scheduled into cycles. These functional operations can be *chained*, so that their outputs feed other successive operations, or scheduled to be executed in parallel, when no data dependencies occur.

Binding

In the binding phase, the tool checks if the allocated resources and scheduling allows the resources sharing. As a result every functional operation, variable and connection is bound to a physical resource. Since area and delay are estimated as early as possible, the binding step can perform some kind of optimization of the architecture.

Generation

This step takes all the decisions taken in the allocation, scheduling and binding steps and it generates the final RTL architecture.

1.1.3 HLS State-Of-The-Art

It is possible to divide the story of the HLS in three generations. The first generation (1980s-early 1990s) failed [2] because of:

- input language (Silage);
- poor results quality, involving in too simple architecture, poor scheduling;
- domain specialization (HLS was DSP oriented, not appropriate for ASIC designs).

The second generation (mid-1990s-early 2000s) failed, too [2]. The main reasons are:

- attempting of substituting RTL synthesis with HLS;
- wrong input HLLs;
- variable and unpredictable results;
- hard validation process;

- poor attention on interfaces.

The current generation is the third (from early 2000s) [2]. In spite of the second and the first HLS generations, the third one is doing better for several reasons:

- Focus on domain of application: tools are used typically on domains where they have an higher probability of generating quality results (DSP application).
- the use of comfortable language to develop algorithms implies the success of the third generation;
- higher results quality;
- shifted design domains: the huge amount of signal and multimedia processing incorporated by many products, allows different kind of designs to take advantages from HLS;
- using HLS for FPGA means to quickly get an algorithm in hardware.

1.2 Catapult C

Catapult C is a product of Mentor Graphics used for HLS synthesis. Catapult accepts as inputs C/C++ and System C code producing register transfer level (RTL) code. The target platforms are FPGA and ASIC. It is also capable of verifying the correctness of the output of the synthesized architecture, directly comparing its output with the ones produced by the description algorithm. In Figure 1.2, the Catapult design flow is shown. Notice the presence of a section (Constraints) exploiting the concept of Folding/Unfolding, Re-timing/Pipelining and so on, to explore different architectural solutions.

The High-level-synthesis tool needs the top entity to be specified. In this way the top-module specifies port interface and definitions, bit widths and data types. Another characteristic is that Catapult produces registered output so that it is easier to interface modules one to each other.

Since the C++ description is time agnostic, clock, enable and reset signals are added by the synthesis tool.

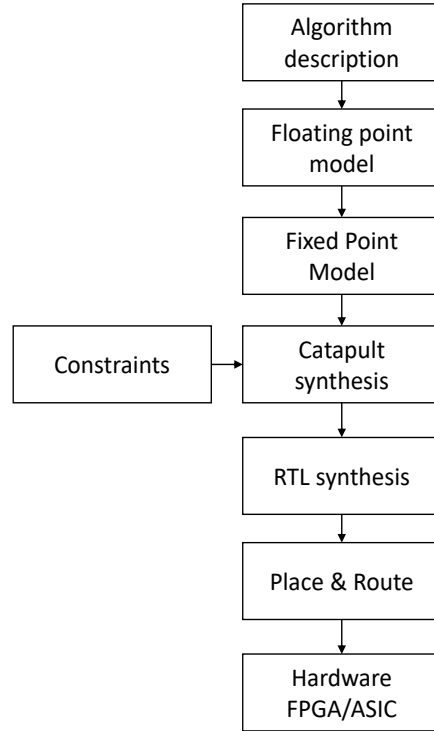


Figure 1.2: Catapult flow

1.2.1 Data types

Catapult allows the designer to use variables defined in a way suitable to be used in the synthesized architecture in order to optimize the hardware design. There are two possible data types that can be used: *ac_int* and *ac_fixed*. The Table 1.1 shows

Table 1.1: Numerical range of *ac_int* and *ac_fixed*

TYPE	DESCRIPTION	NUMERICAL RANGE
<code>ac_int<W, false></code>	unsigned integer	0 to 2^{W-1}
<code>ac_int<W, true></code>	signed integer	-2^{W-1} to $2^{W-1} - 1$
<code>ac_fixed<W, I, false></code>	unsigned fixed-point	0 to $(1 - 2^{-W})2^I$
<code>ac_fixed<W, I, true></code>	signed fixed-point	$(-0.5)2^I$ to $(0.5 - 2^{-W})2^I$

the possible basic declaration of variables using *ac_int* or *ac_fixed*. The template parameter '*W*' is a positive integer, so it defines the number of bits of the number. The second parameter '*I*' defines the position of the fixed point, so it identifies the

number of bits representing the integer part. The third parameter is a boolean value and can be set to "*false*" for unsigned numbers or "*true*" for signed. The fixed-point datatype *ac_fixed* has two additional template parameters. Its full template is:

$$ac_fixed < intW, intI, boolS, ac_q_modeQ, ac_o_modeO > \quad (1.1)$$

The parameter *ac_q_mode* imposes which kind of *Quantization method* must be used and the parameter *ac_o_mode* impose the *Overflow method*. In Tables 1.3 and 1.4 the possible *Quantization* and *Overflow* modes are shown. The last thing to remark

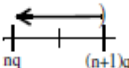
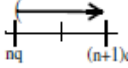
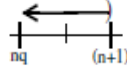
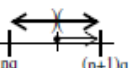
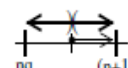
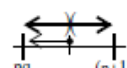
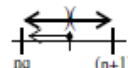

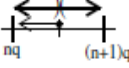
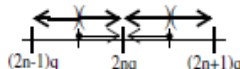
Modes	Behavior n is integer, q is 2^{I-W}	Simulation/Synthesis cost
AC_TRN (default) (trunc towards $-\infty$)		Delete bits, no cost except for /= (div assign) signed
AC_TRN_ZERO (trunc towards 0)	<div style="display: flex; justify-content: space-around;"> <div style="text-align: center;"> $n < 0$  </div> <div style="text-align: center;"> $n \geq 0$  </div> </div>	No cost for /=, or unsigned src For signed: incremter, OR for deleted bits, AND with sign bit
AC_RND (round towards $+\infty$)		Various forms differ only on the direction of the rounding for values that are exactly at half point. All require an incremter, some require to OR deleted bits, some only require to look at the MSB of the deleted bits.
AC_RND_ZERO (round towards 0)	<div style="display: flex; justify-content: space-around;"> <div style="text-align: center;"> $n < 0$  </div> <div style="text-align: center;"> $n \geq 0$  </div> </div>	
AC_RND_INF (rounds towards $\pm\infty$)	<div style="display: flex; justify-content: space-around;"> <div style="text-align: center;"> $n < 0$  </div> <div style="text-align: center;"> $n \geq 0$  </div> </div>	
AC_RND_MIN_INF (round towards $-\infty$)		
AC_RND_CONV (round towards even q multiples)		

Figure 1.3: Quantization modes

is that there a group of methods and operators that can be used using *ac_int* and *ac_fixed* data types. A complete overview on these methods and operators is shown in Figures 1.5 and 1.6.

Mode	Behavior all references are to <i>target</i> type MIN, MAX are limits	Simulation/Synthesis cost
AC_WRAP (default)	Drop bits to the left of MSB	No cost
AC_SAT	Saturate to closest of MIN or MAX	Overflow checking and Saturation logic
AC_SAT_ZERO	Set to 0 on overflow	Overflow checking and Saturation logic
AC_SAT_SYM	For unsigned: treat as AC_SAT, For signed: on overflow or number is MIN set to closest of $\pm MAX$.	Overflow checking and Saturation logic

Figure 1.4: Overflow modes

1.2.2 Synthesis tool steps

Catapult synthesis tool needs different steps to complete the extraction of the RTL code.

- **Hierarchy:** Catapult requires to identify the top entity, selecting TOP in the *Hierarchy setting* in the *Constraint editor*;
- **Libraries:** the technology is set.
- **Mapping:** allows to set the clock frequency and also other signals related to timing as resets (synchronous and asynchronous) and enable;
- **Architecture:** to apply loop Pipeline and loop Unfolding technique to the architecture;
- **Schedule:**
 1. Catapult adds time to the design in this phase;
 2. Scheduling task determines when a certain operation must be performed and can be modified due to registers insertion, according to the target clock the architecture ;
 3. Scheduling task corresponds to a *pipelining* operation, with the purpose of reducing the combinational delay;

Methods	ac_int<W,S>	ac_fixed<W,I,S,Q,O>
slc<W2>(int_type i)	Returns slice of width W2 starting at bit index i, in other words slice (W2-1+i downto i). Slice is returned as an ac_int<W2,S>. Parameter <i>i</i> needs to be non-negative and could of any of the following types: <i>ac_int</i> , <i>unsigned</i> , <i>int</i>	
set_slc(int_type i, ac_int<W2,S2> x)	Bits of x are copied at slice with LSB index <i>i</i> . That is, bits (W2-1+i downto i) are set with bits of x. Parameter <i>i</i> needs to be non-negative and could of any of the following types: <i>ac_int</i> , <i>unsigned</i> , <i>int</i>	
to_ac_int()	NOT DEFINED	return an ac_int<W _I ,S> where W _I is max(I, 1). Equiv to AC_TRN quantization. Return type guarantees no overflows.
to_int(), to_uint(), to_long(), to_ulong(), to_int64(), to_uint64()	Conversions to various C INTS	Conversions to various C INTS Equiv to to_ac_int() followed by conversion
to_double()	Conversion to double	Conversion to double
to_string(ac_base_mode base_rep, bool sign_mag = false)	convert to std::string depending on parameters <i>base_rep</i> {AC_HEX, AC_DEC, AC_OCT, AC_BIN} and <i>sign_mag</i>	
length()	Returns bitwidth (value of template parameter W)	
set_val<ac_special_val>()	Set to special value specified by template parameter AC_VAL_DC, AC_VAL_0, AC_VAL_MIN, AC_VAL_MAX, AC_VAL_QUANTUM.	

Figure 1.5: Methods for *ac_fixed*

- **RTL:** Catapult generates the RTL netlist.

An important consideration must be done for the *Architecture* section. In this section it is possible to "pipeline" the loops. To pipeline a loop means that a new iteration can start before the current one has completed. This operation has two important results: execution of the loop iterations are overlapped and clearly an increase of performance since the loops run in parallel. When a loop is pipelined, the *initiation interval (II)* is set, and the number of pipeline stages are specified. The *initiation interval (II)* is

Operators	<i>ac_int</i>	<i>ac_fixed</i>
Two operand +, -, *, /, %, , &, ^	Arithmetic result. First or second arg may be <i>C INT</i> or <i>ac_fixed</i> / truncates towards 0	Arithmetic result. First or second arg may be <i>ac_int</i> or <i>C INT</i> / truncates towards 0. % NOT DEFINED
>>, <<	bidirectional return type is type of first operand Second arg is <i>ac_int</i> or <i>C INT</i>	bidirectional return type is type of first operand Second arg is <i>ac_int</i> or <i>C INT</i>
=	assignment	quantization, then overflow handling specified by target
+=, -=, *=, /=, %=, =, &=, ^=, >>=, <<=	Equiv to op then assign. First arg is <i>ac_int</i>	Equiv to op then assign. First arg is <i>ac_fixed</i>
==, !=, >, <, >=, <=	First or second arg may be <i>C INT</i> or <i>ac_fixed</i>	First or second arg may be <i>ac_int</i> or <i>C INT</i> or <i>C double</i>
Unary +, -, ~	Arithmetic	Arithmetic
++x, x++, --x, x--	Pre/post incr/dec by 1	Pre/post incr/dec by 2^{I-W}
! x	Equiv to $x == 0$	Equiv to $x == 0$
(long long)	defined for <i>ac_int</i> <W,true>, $W \leq 64$	NOT DEFINED
(unsigned long long)	defined for <i>ac_int</i> <W,false>, $W \leq 64$	NOT DEFINED
x[i]	returns <i>ac_int::ac_bitref</i> index: <i>ac_int</i> , <i>unsigned</i> , <i>int</i> asserts for index out of bound	returns <i>ac_fixed::ac_bitref</i> index: <i>ac_int</i> , <i>unsigned</i> , <i>int</i> asserts for index out of bounds

Figure 1.6: Operators for *ac_fixed*

the number of clock cycles between the start of two consecutive loop iterations. As a direct consequence the loop pipelining leads to an increase of the allocated resources. As output Catapults provides:

- reports: RTL report and Cycle report;
- RTL description in VHDL and Verilog;
- Gantt chart: a timing chart;

- RTL schematic.

Finally, it is possible to proceed with the Verification step. The SCVerify infrastructure is shown in Figure 1.7.

SCVerify flow allows the validation of the RTL netlist using the testbench written in C/C++, comparing its output with a SCVerify-generated testbench. SCVerify places the RTL netlist in a SystemC wrapper and it encapsulates the C/C++ testbench with the C/C++ algorithm in the total infrastructure. The same input stimuli are passed to both the SystemC wrapper and the C/C++ testbench. Finally the output from both the modules are compared. SCVerify manages also timing signals:

- *generate_sync*: provides the synchronization events
 1. *ac_channel*: synchronization signals like handshake protocols signals (*ccs_in_valid*, *ccs_in_vld* or **_wait*);
 2. *Transaction Done Signal (triosy_lz)*: it is a signal which is added to the C++ variables. This signal is enabled for 1 clock cycle at the completion of each I/O transaction;
- *geratate_reset*: manages the assertion of the reset signal;
- *watch_comparators*: compares the output and reports the number of comparisons passed and the number of comparison failed.

SCVerify supports different simulation enviroments for verification as: Questasim and Modelsim, Synopsys VCS and Cadance IUS/NCSim.

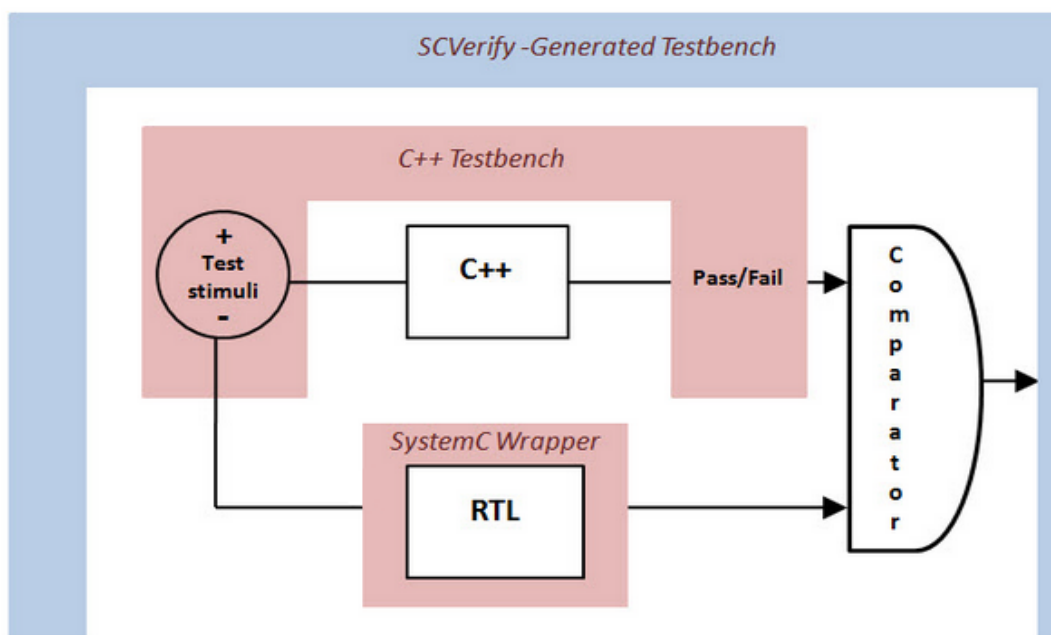


Figure 1.7: SCVerify infrastructure

CHAPTER 2

CIC filter and state of art

2.1 Cascaded Integrator and Comb (CIC) filter

In DSP systems, the applications for extraction narrow-band signals from wide-band source and narrow-band construction of wide-band signals are becoming more important. In audio applications different sample rates coexist and this means that it is necessary to change the rate of a system for lower or higher sampling rates. The change of the samples rates is performed exploiting two operations: interpolation, to increase the samples rates, and decimation, to decrease the samples rates.

In the following sections the decimation filtering is studied. The decimation operation can be performed using FIR-based filters. These class of filters have the great disadvantage of having a structure with multipliers. This means that the computational costs in terms of power consumption would increase dramatically, because it is necessary to perform a high number of multiplications per second. In [5] a way to perform interpolation and decimation is introduced. Hogenauer proposed the CIC filters, a class of digital linear phase finite impulse response (FIR) filters, for decimation and interpolation operations. The peculiar characteristic of the CIC filter is its multiplierless structure, implying a save of power consumption and area, because it is no more necessary the coefficients storage for multipliers. In the following sections the behaviour of a CIC decimation filter is studied.

A CIC decimation filter structure is shown in Figure 2.1.

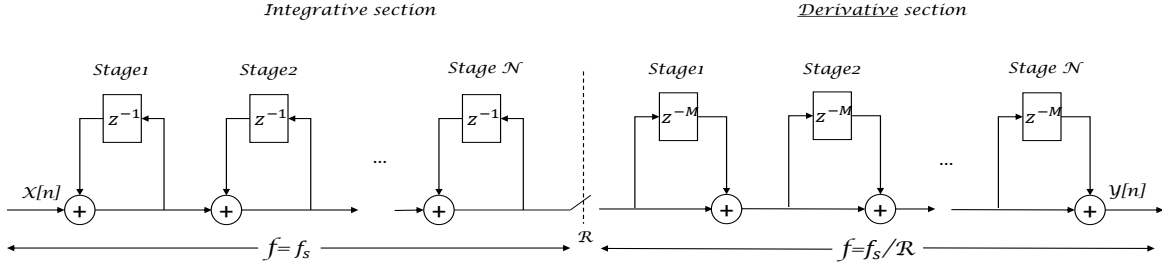


Figure 2.1: Decimation filter with CIC structure

The entire structure of a decimation filter consists of two sections: the integral section and derivative section, also called comb section, connected by a decimation step R .

The integrator section is composed by a number N of ideal integrator stages working at the high sampling rate f_s , where N is the order of the filter. Each integrator stage is implemented as single-pole filter with a unitary feedback coefficient. A single integrator stage is shown in Figure 2.2. The performed equation by this base integrator is:

$$y[n] = y[n - 1] + x[n] \quad (2.1)$$

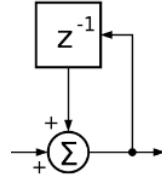


Figure 2.2: A single integrator stage

The transfer function of that stage is:

$$H_i(z) = \frac{1}{1 - z^{-1}} \quad (2.2)$$

Since N is the filter order, and so it contains the information about the number of stages per section, the transfer function of the total integrator section is the following:

$$H_I(z) = \left(\frac{1}{1 - z^{-1}} \right)^N \quad (2.3)$$

The combinational or derivative part works at lower frequency: f_s/R , where R is called *integer change rate factor*. This stage is composed by N comb stages and each one is a differential delay M, that in practice is 1 or 2. A combinational stage is the one shown in Figure 2.3, and the performed equation is:

$$y[n] = y[n-1] - x[n-RM] \quad (2.4)$$

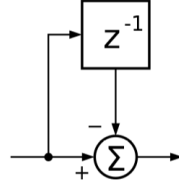


Figure 2.3: A single differential stage, with M=1

Its transfer function is:

$$H_d(z) = 1 - z^{-RM} \quad (2.5)$$

Even in this case the resulting transfer function of the whole differential section is:

$$H_D(z) = (1 - z^{-RM})^N \quad (2.6)$$

There is a switch between the two sections, that for decimation filters, reduces the number of samples coming from the integral section by factor R factor. The entire structure and transfer function of the CIC filter is:

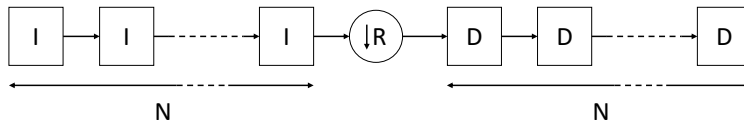


Figure 2.4: Scheme of the CIC decimation filter structure

$$H_D(z)H_I(z) = \frac{(1 - z^{-RM})^N}{(1 - z^{-1})^N} = \left[\sum_{k=0}^{RM-1} z^{-k} \right] \quad (2.7)$$

So from this result it is clear that a CIC filter is the equivalent of a cascade of N FIR filters like in Figure 2.5, but it is less expensive for the following reasons:

- no multipliers and no storage for coefficients are required (saving of area);

- intermediate storage is reduced (saving of area);
- the CIC filter structure is very regular since it consists 2 sections (integral and differential);
- there is no need of control units or complex timing;
- re-usability of the same filter with different input sample rate

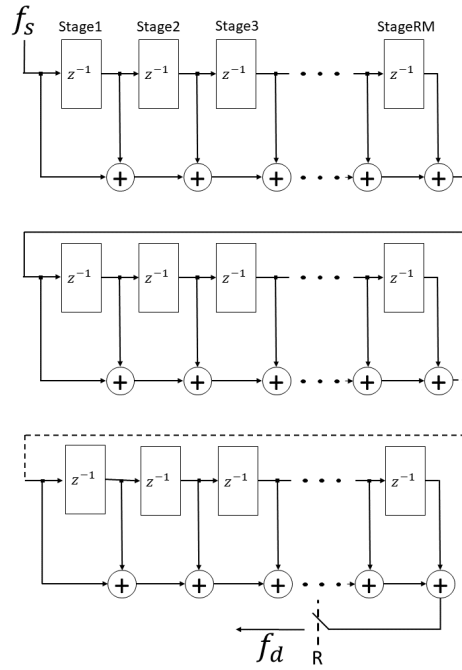


Figure 2.5: Decimation filter implemented as a cascade of FIR filters

2.2 CIC filter frequency response

A CIC filter behaves like a low-pass filter. Since the CIC filter is an LTI filter, in order to evaluate the frequency response, it is necessary to evaluate the spectrum of the output signal divided by the spectrum of the input signal.

$$Y(z) = H(z)X(z) \quad (2.8)$$

where $Y(z)$ is the z-transform of the output $y[n]$, while $X(z)$ is the z-transform of the input $x[n]$.

Thus the $H(z)$ has to be consider to evaluate the frequency response of a LTI filter like the CIC. In particular $H(z)$ has to be evaluated in the unit circle in the z-plane, where as definition, $z = e^{j(2\pi ft_s)}$. Notice that $f_s = 1/t_s$ is the input sample rate. From (2.7), the frequency response can be simply obtained:

$$H(f) = \left(\frac{1 - e^{-j2\pi RM ft_s}}{1 - e^{-j2\pi ft_s}} \right)^N = e^{-j\pi ft_s(RM-1)N} \left[\frac{\sin(\pi ft_s RM)}{\sin(\pi ft_s)} \right]^N \quad (2.9)$$

From (2.9), it is possible to notice that $H(0) = (RM)^N$. So the frequency response of the CIC filter can be obtained by considering:

$$\frac{H(f)}{H(0)} = e^{-j\pi ft_s(RM-1)N} \left[\frac{1}{RM} \frac{\sin(\pi ft_s RM)}{\sin(\pi ft_s)} \right]^N \quad (2.10)$$

It is possible to notice that the zeros of the frequency response occur every $1/RM$, so both the *differential delay* and the *integer change rate factor* are parameters that can be used to control the zeros placements. In Figure 2.6, the frequency response of a CIC decimation filter is shown using the MATLAB function for the CIC filters:

$$dsp.CICDecimator(R, M, N) \quad (2.11)$$

The simulation is done using the following parameters:

- R=8;
- N=6;
- M=1;
- $f_s=8\text{MHz}$

Notice that the zeros occur every $1/RM$ positions, which means that the zeros are placed every $8\text{MHz}/8*1$

Figure 2.7 displays the frequency response of the CIC decimation filter characterized by the same parameters (R=8 and N=6), but with M=2. In this case is it possible to appreciate that the zeros are placed every $1/RM$. This is important since for decimation filters implemented with CIC filter, the region around every $M - th$ zero, falls inside the passband, causing aliasing errors.

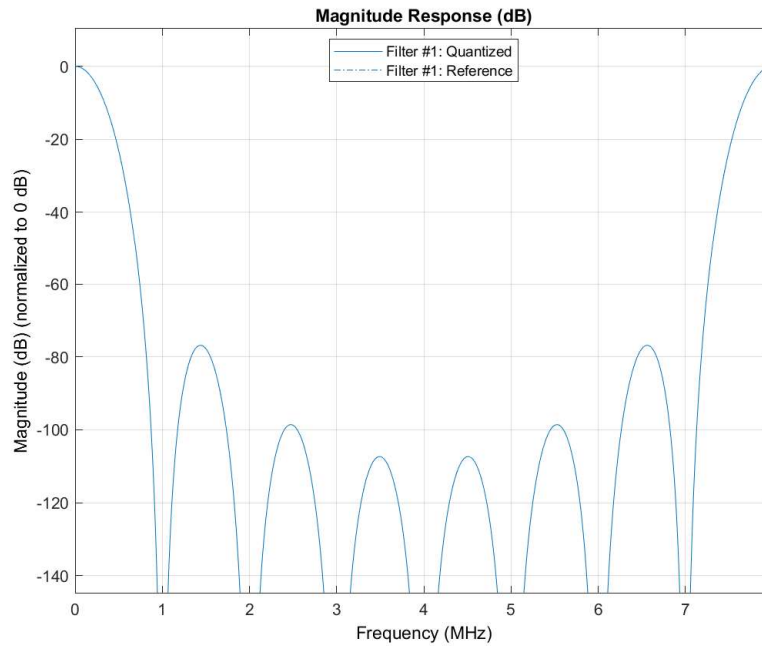


Figure 2.6: CIC filter frequency response, with $M=1$

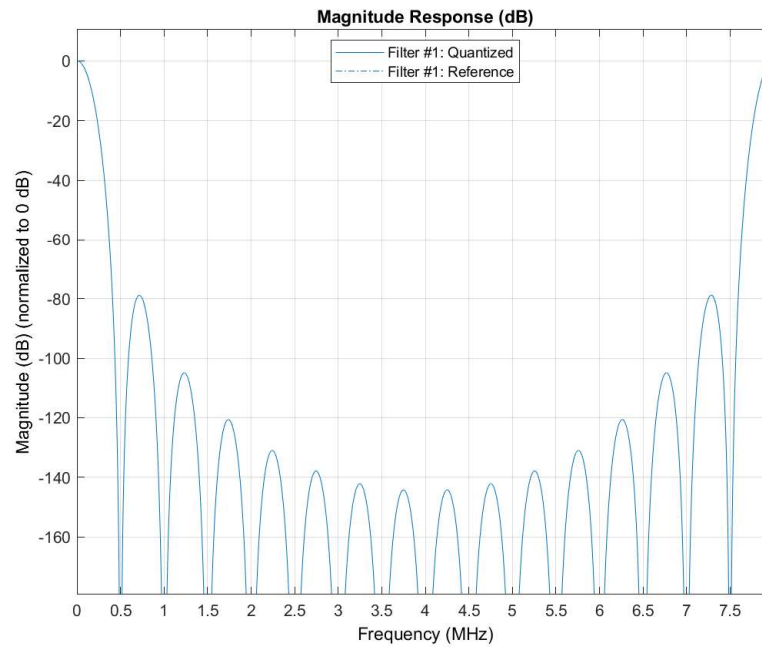


Figure 2.7: CIC filter frequency response with $M=2$

2.3 Two possible algorithms for a CIC filter implementation

There are two ways for the implementation of a CIC filter: *recursive* and *non-recursive* [8]. The implementation described above in Figure 2.1 is a *recursive* structure.

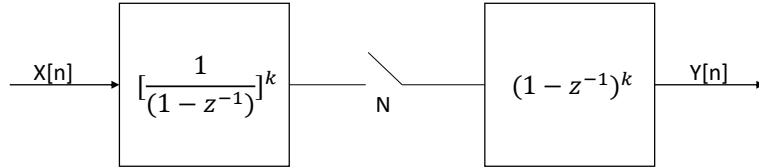


Figure 2.8: General structure of a recursive CIC filter 2.8

In Figure 2.8 a general structure of a CIC implemented using recursive algorithm is shown.

	Input	Output
Sampling rate	f_{os}	f_{os}/N
Word Length	m	$m + k * \log_2 N$

Table 2.1: Sampling rate and word length for recursive algorithm

The main problem of this structure is the high power consumption and the speed limitation. A/D sigma-delta converters have become very popular, because they avoid the problems of the classical A/D, thanks to the help of the large digital decimation filters. The A/D sigma-delta converters usually have an output characterized by a small parallelism (1 bit or 2 bits), and a very high output sample rate. Taking into account *recursive* structures of the decimation CIC filter, it is possible to notice that the integrative section takes as input the samples coming from a sigma-delta A/D converter output. To maintain accuracy, the internal parallelism is $m + k * \log_2 N$, where m is the input parallelism, k is the filter order, and N is the decimation factor. Thus the integral section of the filter is the dominant part in terms of power consumption, because the computation requires additions between high parallelism data, performed to a very high sampling rate.

The new non-recursive algorithm provides an architecture like the one shown in Figure 2.9. At every stage, the frequency is lowered by a factor of 2. From the Table 2.2 it is clear that when the frequency is high the word length is low, reducing the problem of power consumption. Another comparison can be done by estimating the

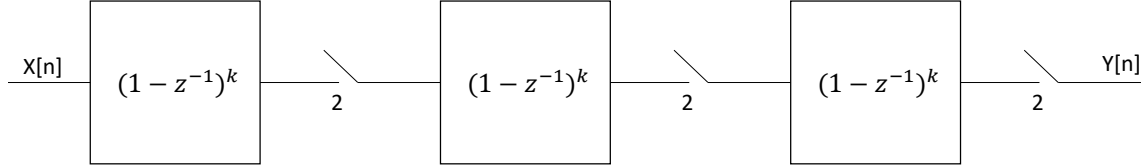


Figure 2.9: General structure of a non-recursive CIC filter 2.8

power consumption, the highest working frequency and the estimated area, against the decimation factor, as shown in Figure 2.10

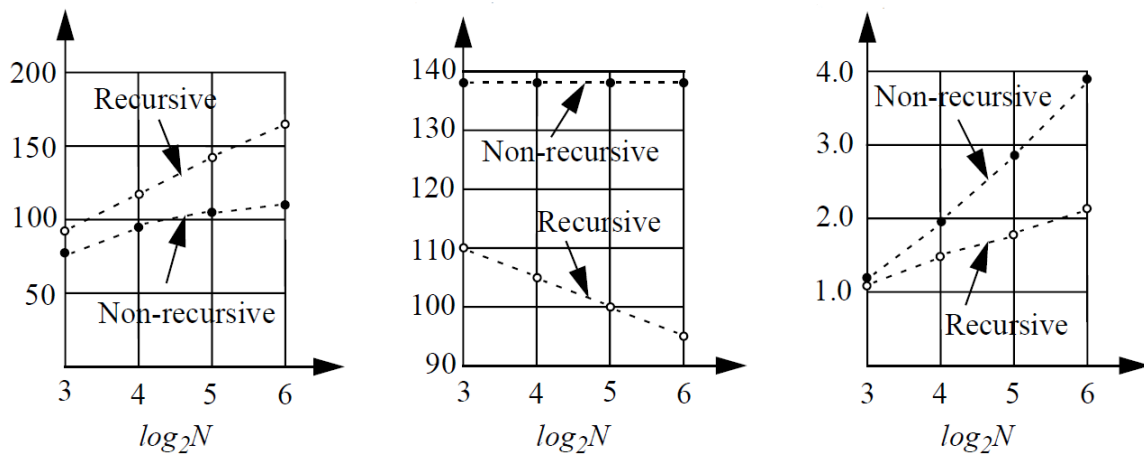


Figure 2.10: Comparison between non-recursive and recursive algorithm, in terms of area, power consumption and frequency [8]

	Input	Output
Sampling rate	$f_{os}/2^{i-1}$	$f_{os}/2^i$
Word Length	$m + k * (i - 1)$	$m + k * i$

Table 2.2: Sampling rate and word length for non-recursive algorithm

In conclusion, the architectures implemented using non-recursive algorithm can be used for low-power and high-speed applications, while the architecture implemented with recursive algorithm are suitable for applications requiring small area devices.

2.4 State-of-the-art CIC filter

2.4.1 Bit-serial implementation (Recursive structure)

The architecture described in 2.1 is the typical implementation proposed by Hogenauer and it is characterized by a recursive architecture. As shown in Figure 2.4, the recursive implementation of a CIC filter requires a certain number of integrator stages and derivative stages. For recursive filter, bit-serial implementation is proposed in [9]. Bit-serial implementation exploits 1-bit input per clock cycle processing, having as immediate result the reduction in the allocated hardware resources (few processing element and smaller buses) and so the chip area is significantly reduced compared with the one of the bit-parallel implementation. For this architecture the same working frequency rules for the integral and derivative section are kept. It means that the integrative section works at a frequency equal to the input sample rate, the derivative section works at a frequency equal to the input sample rate divided by the decimation factor (taking into account a CIC decimation filter). By using the bit-serial implementation, three possible architecture are developed:

- CBS: conventional bit serial;
- BSAD: bit-serial with address decoder;
- BSOP: bit-serial with one-hot pointer.

The CIC filter proposed is a fifth-order filter with a *integer change rate factor* equal to 16. The block diagrams of the integral and derivative stages are shown in Figure 2.11. These stages are cascaded with a number according to the filter order. Notice that the shift register is a 25-bit shift register. The reason is that to maintain accuracy the intermediate word length is bigger than the input one and it is chosen using the following relation:

$$m + K * \log_2(M) \quad (2.12)$$

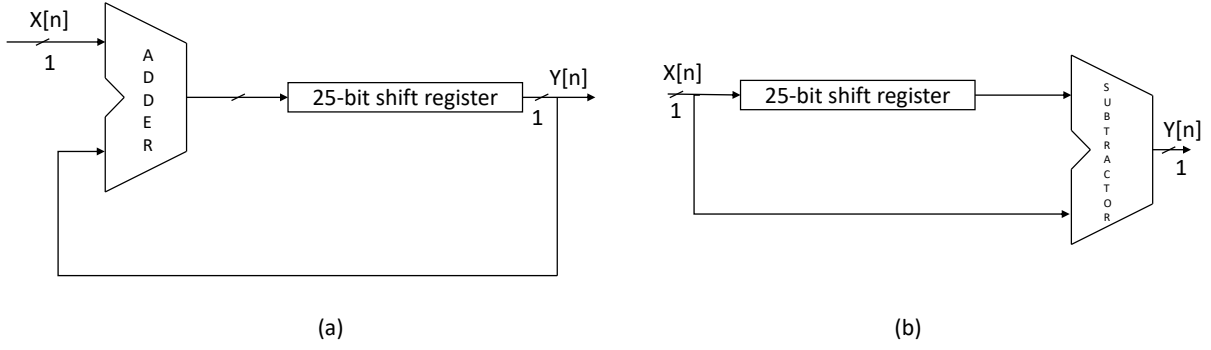


Figure 2.11: Structure of integrative stage (a) and derivative stage (b) [9]

where:

- m is the input word length, which is 5 in this case;
- K is the filter order, whose value is 5;
- M is the *integer change rate factor* equal to 16.

This architecture is the CBS one. The other optimized implementations are derived from this one and they are the BSAD and BSOP architectures. The first one is proposed to avoid the problem of the large shift register, by substituting it with registers addressed with a 5-bit decoder. The structure of the array registers and the address decoder is shown in Figure 2.12

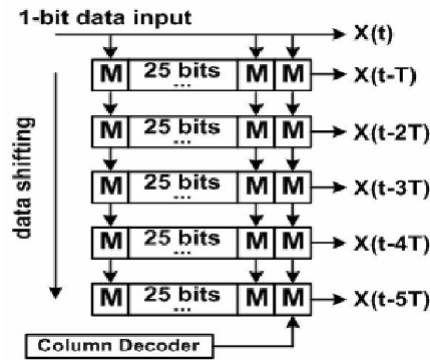


Figure 2.12: Array registers and adder decoder [9]

The BSOP architecture avoids the decoder and inserts a one-hot pointer.

2.4.2 Implementation of a sharpened CIC filter

One disadvantage of the CIC filters frequency response is the lack of a flat pass-band. The typical implementations of the CIC filter structure proposed in [5] exhibit good stop-band attenuation, but also pass-band droop. By increasing the filter order the stop-band attenuation increases as reported in Figure 2.13, 2.14 and 2.18, but the pass-band droop increases, too. This behavior is shown in figures 2.16, 2.17 and 2.18.

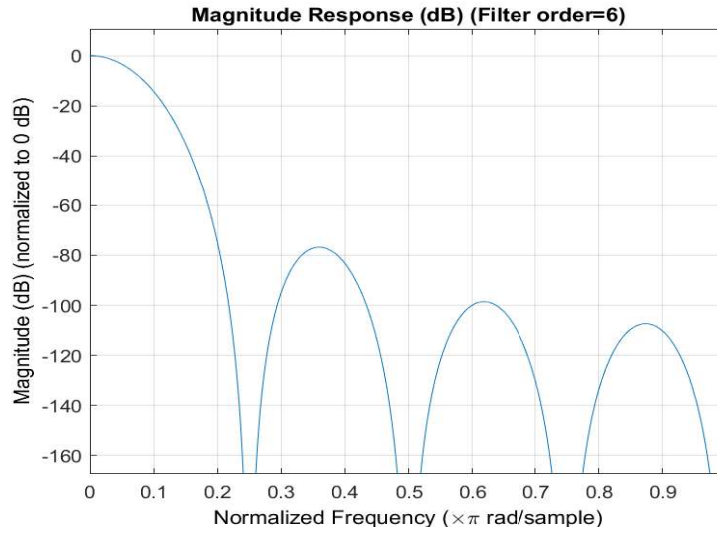


Figure 2.13: Stop-band attenuation of a 6 order CIC filters

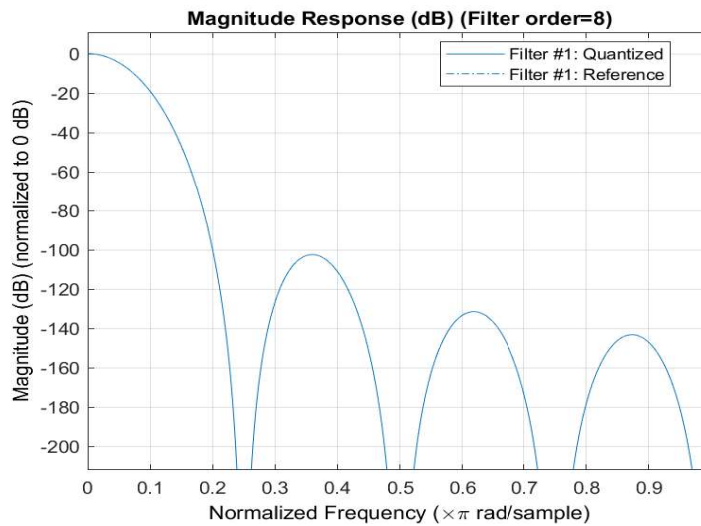


Figure 2.14: Stop-band attenuation of a 8 order CIC filters

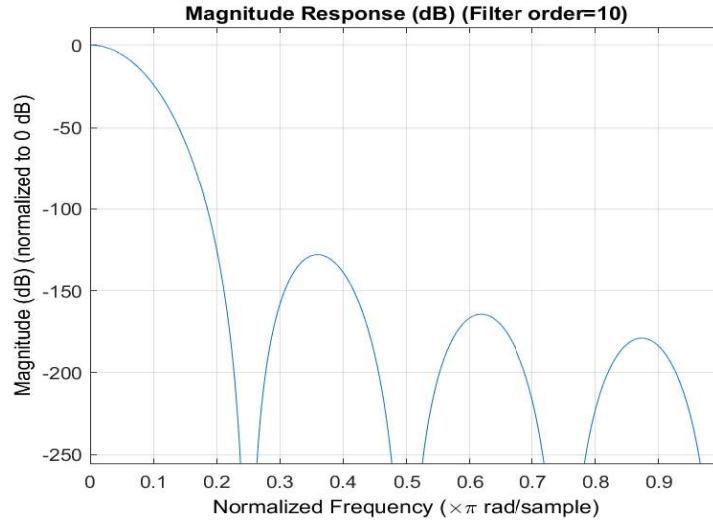


Figure 2.15: Stop-band attenuation of a 10 order CIC filters

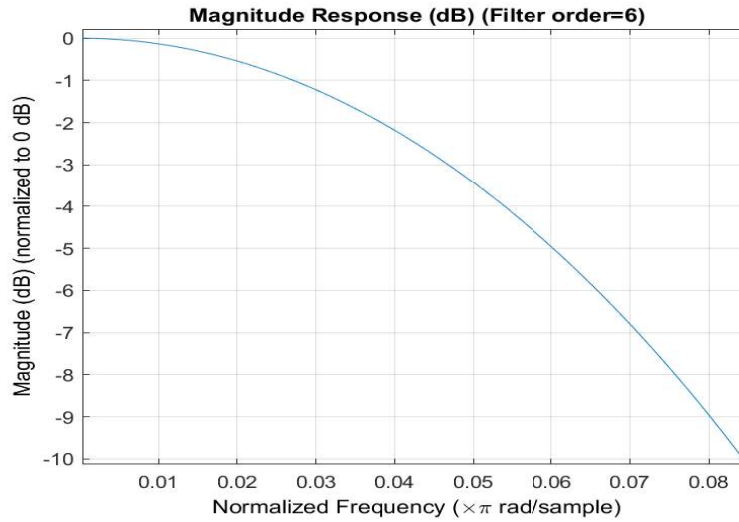
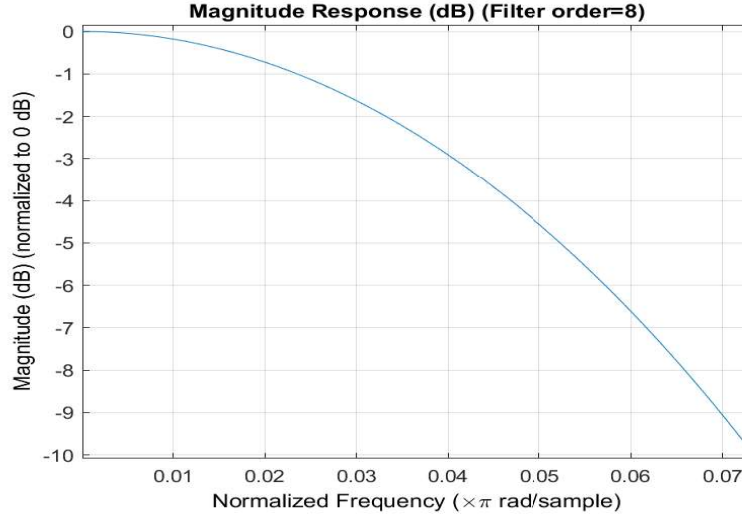
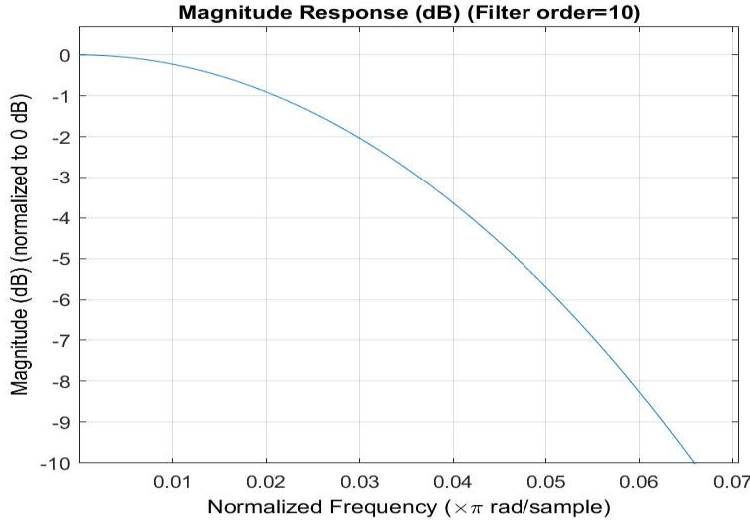


Figure 2.16: Pass-band droop of CIC filters of the 6-th order

The figures 2.13, 2.14, 2.15 and 2.16 2.17, 2.18 refer to CIC filters with decimation factor equal to 8 and order of 6, 8 and 10 respectively.

Typically, it is necessary to improve the frequency response of a filter by increasing the stop-band rejection (loss) and by decreasing the pass-band distortion. This can be done by a compensation filter. Another way to improve the frequency response of a filter is to repeat the use of the filter itself. The most simple idea is to cascade two identical filter sections obtaining stop-band loss increased, but pass-band distortion increased, too. The process to combine the results of several passes through the same

Figure 2.17: Pass-band droop of CIC filters of the 8-*th* orderFigure 2.18: Pass-band droop of CIC filters of the 10-*th* order

filter is called *filter sharpening* [11]. This method is based on the *Amplitude Change Function* (ACF), which has the form

$$H_{in} = f(H_{out}) \quad (2.13)$$

where f is a polynomial relationship between the amplitude of the prototype filter H_{in} (the CIC filter in this case), and the transformed filter H_{out} , which is the resulting filter obtained by using the *filter sharpening* technique. The desired ACF curve passes for (0,0) and (1,1), and the improvements in pass-band ($H_{out} = 1$) and in stop-

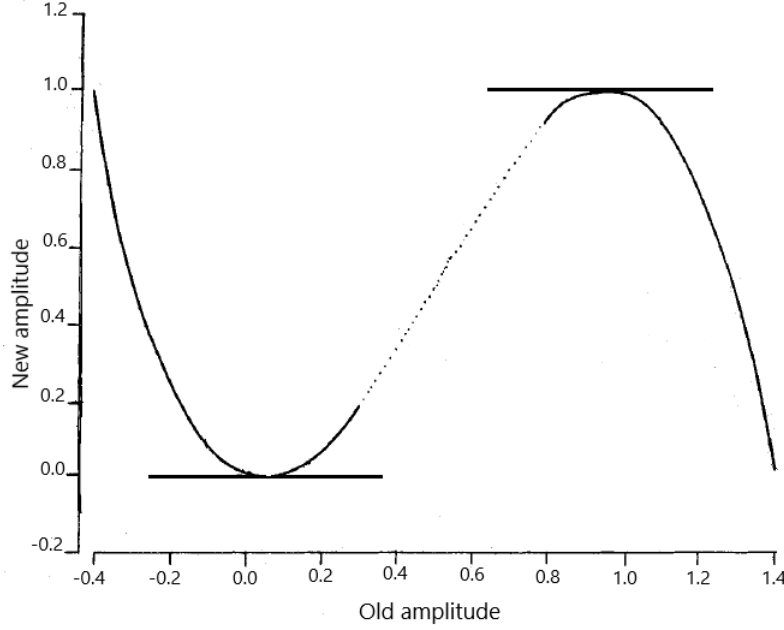


Figure 2.19: The desired ACF curve that represents improvement in stop-band and in pass-band

band ($H_{in} = 0$) are given by the order of tangency of the curve to $H_{out}=1$ and $H_{out}=0$. The desired ACF curve is the one reported in Figure 2.19. The proposed filter which achieve these improvements has as transfer function:

$$H(z) = H(z)^2[3 - 2H(Z)] \quad (2.14)$$

The entire architecture is shown in Figure 2.20 and it consists of 3 copies of a single-stage CIC filter and two multipliers and a delay line to equalize the group delay through the two channels

In Figure 2.21 the comparison between the frequency response of a CIC filter implemented with a standard architecture and the one of a sharpened CIC architecture is shown.

Table reports 2.3 the pass-band distortion according the decimation factor. The Figures 2.22 and 2.23 demonstrate the difference of the pass-band droop between a standard CIC filter implementation and a sharpened CIC filter implementation.

It is clear that the sharpened CIC filter has better performance compared to the

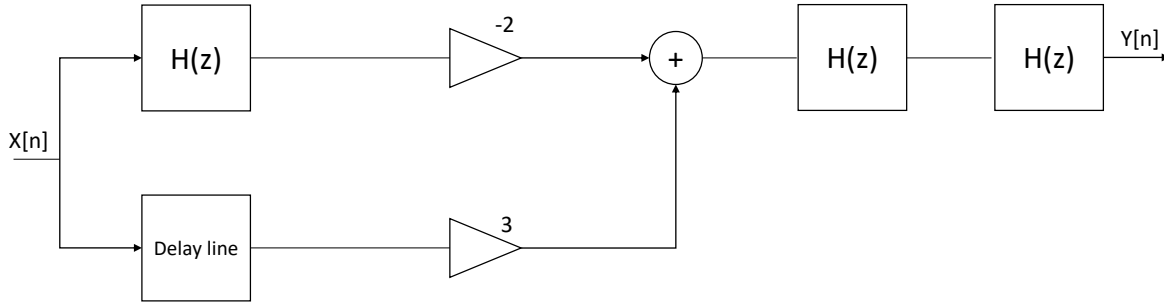


Figure 2.20: Architecture of the sharpened-response CIC filter

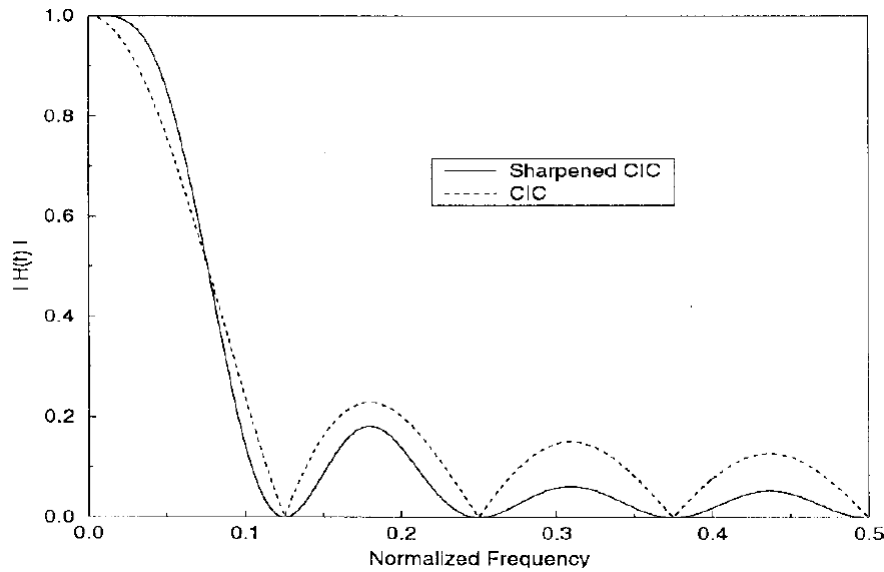


Figure 2.21: Comparison between the standard CIC response and the sharpened CIC response [12]

standard CIC filter. This kind of structure provides a solution for the problems of the necessity of a compensation filter downstream the CIC filter and continues to keep the advantage of the multiplierless architecture of the standard CIC filters.

Moreover it can be used for very-high data throughput rates, for example for wide-band satellite communication systems.

This architecture is also useful for systems requiring *programmable* decimation factors. The compensation filter, which has to reduce the pass-band droop, must be programmable in these systems. That's because the pass-band depends on the decimation factor as discussed in section 2.2. With the architecture proposed in [12]

Pass-band distortion after decimation vs decimation factor [12]

Decimation Factor	Worst-case pass-band distortion (dB)
2	0.00748664
4	0.00469985
8	0.00308263
16	0.00958937
32	0.00604246
64	0.00488694
128	0.00472363
256	0.00438328
512	0.00419868
1024	0.00411545
2048	0.00407759
4096	0.00405978
8192	0.00405779

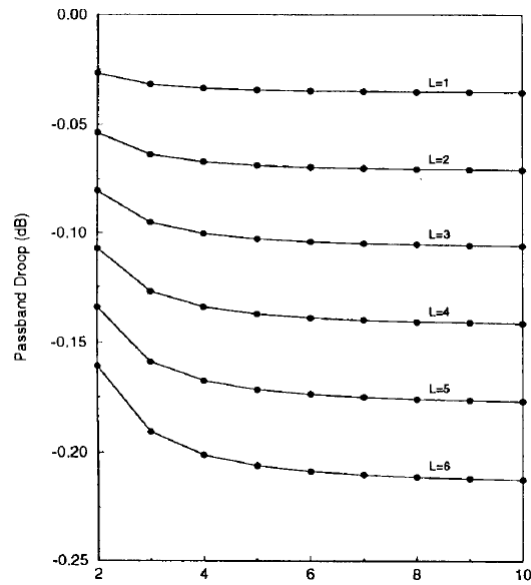


Figure 2.22: CIC filter pass-band droop trend according to the decimation factors and parametrized on the filter order [12]

it is possible to eliminate the necessity of a programmable compensation filters is to

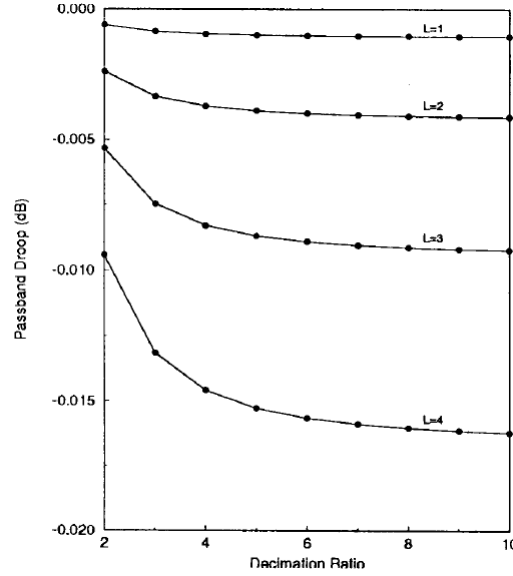


Figure 2.23: Sharpened CIC filter pass-band droop trend according to the decimation factors and parametrized on the filter order [12]

modify the CIC architecture in order to obtain a sharpened response. This architecture reduces the pass-band droop, allowing a lower pass-band distortion and facilitate the design of a compensation filters because it can have constant coefficients, with little extra cost.

2.4.3 CIC filter architecture with optimal performance

The new architectural approach proposed in [14], is represented in Figure 2.24. The analysis in [14] focuses of the comb section of the CIC filter. The proposed architecture allows to reduce the number of subtractors using the accumulation mode to perform the sequential subtraction. The controller is connected to the multiplexer and generates the output enable, according to the filter parameters.

Table 2.4 shows the improvements of the implementation on FPGA of the optimized architecture compared with architecture of the filter produced by MATLAB HDL Coder.

Table 2.5 shows the improvements obtained for ASIC implementation. More in general this architecture improves the power and the area trends for both FPGA and ASIC implementation also varying the filter order. Figures 2.25, 2.26 and 2.27 show the trend of improvements comparing the ASIC implementation (blue) of the filter and

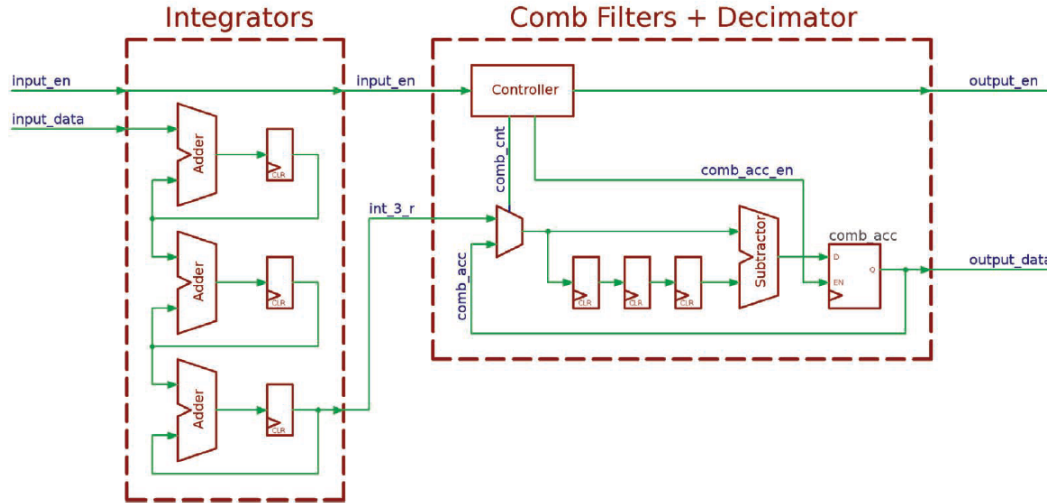


Figure 2.24: CIC filter for decimation operation [14]

Table 2.4: Improvements for FPGA implementation [14]

Decimation Factor	Average Improvements (%)	
	Area	Frequency
8	8.4	78.4
16	15.1	114.5
32	11.5	108.1
63	8.3	85.7
Average	10.9	96.7

Table 2.5: Improvements for ASIC implementation [14]

Decimation Factor	Average Improvements (%)		
	Area	Power	Frequency
8	26.1	35.5	20.9
16	28.7	37.9	17.9
32	28.8	29.9	5.9
64	28.9	34.3	4.3
Average	28.1	34.4	12.2

the results obtained using the HDL code produced by MATLAB (orange).

Figures 2.28 and 2.29 show the difference between the FPGA implementation (blue)

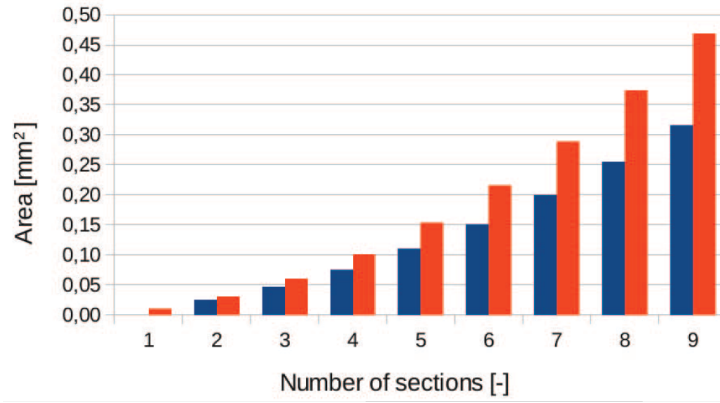


Figure 2.25: Comparison of area between the optimized architecture and the one produced by the MATLAB HDL code for ASIC implementation [14]

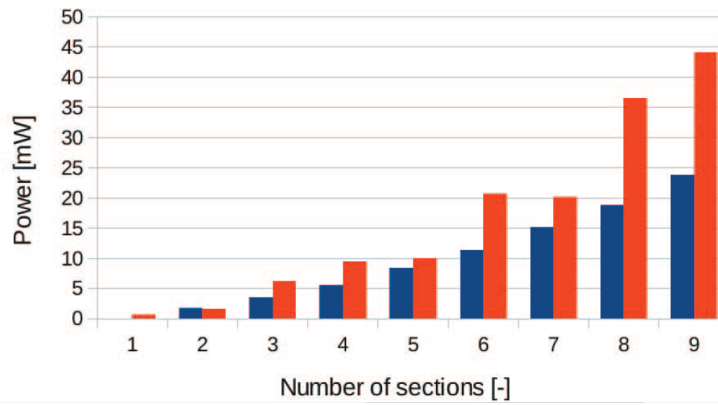


Figure 2.26: Comparison of power between the optimized architecture and the one produced by the MATLAB HDL code for ASIC implementation [14]

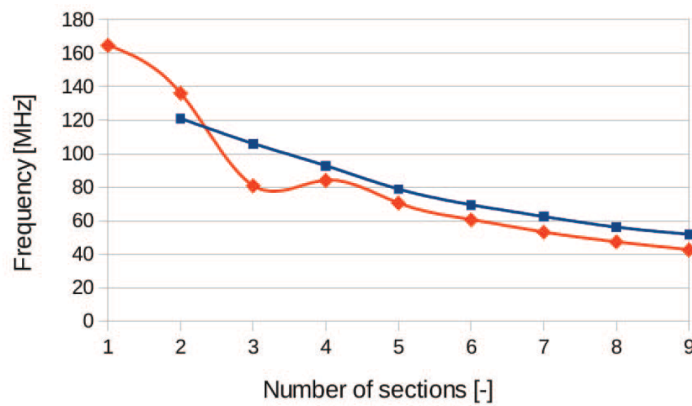


Figure 2.27: Comparison of frequency between the optimized architecture and the one produced by the MATLAB HDL code for ASIC implementation [14]

and the results using the MATLAB function (orange).

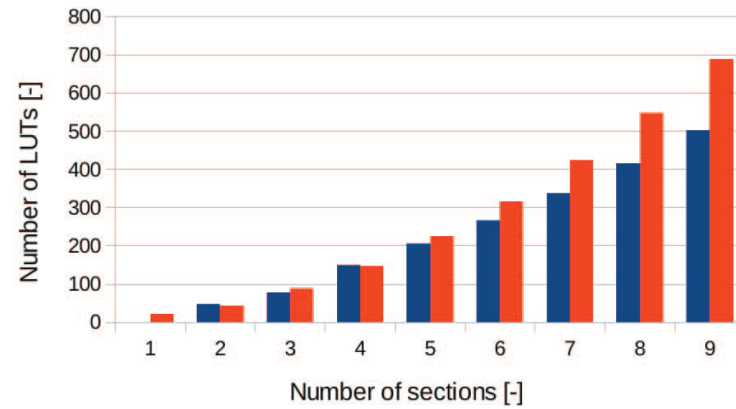


Figure 2.28: Comparison of area between the optimized architecture and the one produced by the MATLAB HDL code for FPGA implementation [14]

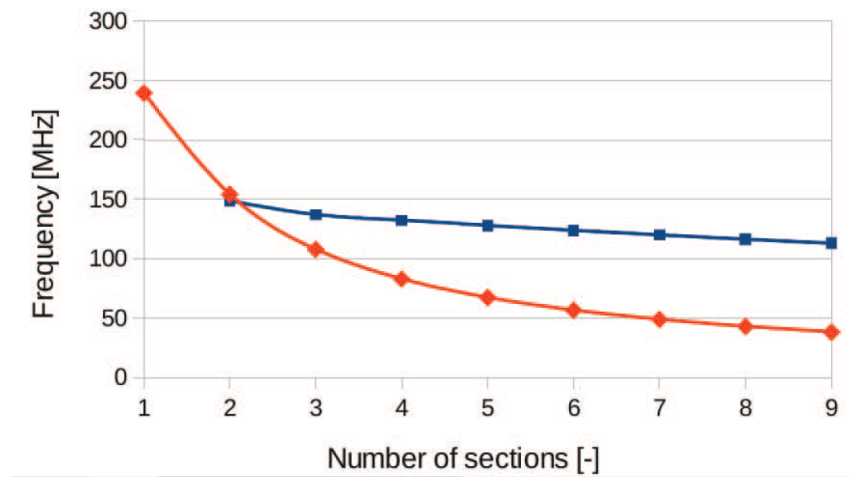


Figure 2.29: Comparison of frequency between the optimized architecture and the one produced by the MATLAB HDL code for FPGA implementation [14]

CHAPTER 3

C++ algorithm

3.1 Reference filter specification

The case study is provided by the company Silicon Mitus, and it is a CIC filter, added in an high-performance DAC designed to process digital stereo streaming. In particular the CIC filter in the DAC must perform the decimation of the input samples. Silicon Mitus provided the MATLAB behavioural description, the System Verilog description of the architecture and the System Verilog testbench of the reference filter implemented with the classical RTL design.

The reference CIC decimation filter has the following specifications:

- f_{dsd} (direct digital interface frequency): possible choice between 2.8224MHz - 5.768 MHz - 11.2896 MHz - 22.5792MHz
- filter order: 6;
- downsampling rate (integer change rate factor): 8;
- Input parallelism: 1 bit;
- Internal parallelism: 19 bits;
- output parallelism: 19 bits.

The Direct Stream Digital interface (DSD) is based on Pulse-Density Modulation (PDM) encoding, and it aims to store/stream a delta-sigma modulated digital audio signal, without any coding. The input data rate can be:

- DSD64: 64 times CD audio sampling rate($64 \times 44.1\text{kHz} = 2.8224\text{MHz}$);
- DSD128: double-rate DSD ($128 \times 44.1\text{kHz} = 5.768\text{MHz}$);
- DSD256 ($256 \times 44.1\text{kHz} = 11.2896$);
- DSD512 ($512 \times 44.1\text{kHz} = 22.5792\text{MHz}$).

The top level entity of the architecture is the one shown in Figure 3.1. The architecture consists of two independent channels, so it has two inputs ports and two outputs ports for data stream, and another port with a signal *trgo* (*trigger out*), which is asserted when the outputs are ready.

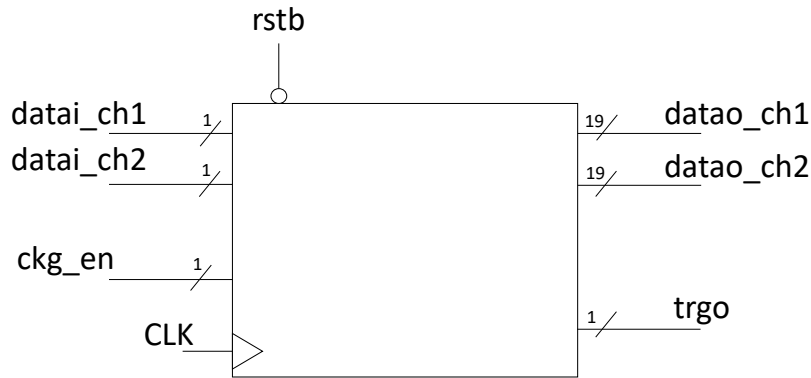


Figure 3.1: Top level entity of the architecture provided by Silicon Mitus

3.2 MATLAB code and algorithm by Silicon Mitus

The MATLAB code contains the discrete model of the CIC filter and the testbench environment for the bittrue verification. The algorithm is developed as depicted in Figure 3.2:

Digital waveform generation

The first step of the MATLAB code is to create the digital input. The function *gen_dig_stim* produces the signals that have to be processed, by specifying the frequency, the amplitude and the offset and the sine waves that have to be generated. The

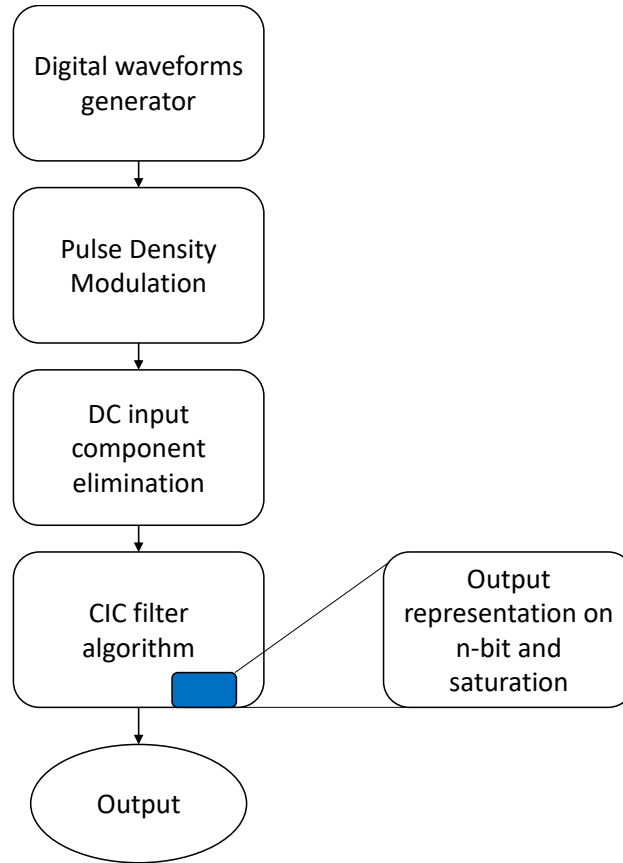


Figure 3.2: Structure of the MATLAB code for one single channel provided by Silicon Mitus

function performing this generation uses also the *dithering*, which is a sample voluntary added noise, in order to reduce the quantization error when samples are quantized.

Pulse Density Modulation

The subsequent step is to perform the Pulse Density Modulation (PDM) on the quantized samples coming from the function described below (*gen_pdm*). Indeed the Direct Stream Digital Interface is based on PDM. The PDM is a modulation to represent an analog signal in binary code. In PDM signals the amplitude is represented by the relative density of the pulses: a high density on 1's implies the maximum value of the amplitude, while a high density of 0's implies the sine curve reaches the minimum amplitude level. An example of Pulse Density modulated signal is shown in Figure 3.3.

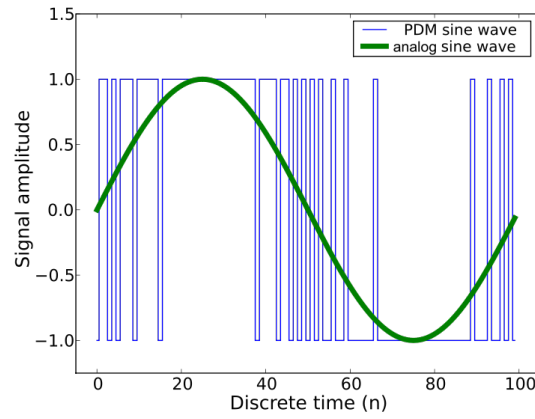


Figure 3.3: Pulse density modulation example

CIC filter algorithm

The implementation of the filter function is the next step. The *dws_cic_bittrue* function is the core of the code and describes the discrete model of the CIC filter. The function is divided into 3 steps: the computation of the output of the integral section, the decimation operation, and the computation of the output of the derivative section corresponding to the final filter output. The output of each sections are represented inside the bit dynamics and eventually wrapped around the upper or the lower value of the binary dynamic limit. The function performing the representation of the output values on 19 bits is *dws_dyn_wa*, which performs also a saturation of the outputs if needed

Golden output generation

The *gen_cic_golden* function is the function encloses the described functions. Since the entire architecture consist of 2 channels, the function performs all of the steps previously described twice. In particular this function generates one input per channel, it performs the Pulse Density Modulation exploiting the *gen_pdm* function. In this way an array containing all the inputs is created by this function. The DC component of the digital input is eliminated using the following equation:

$$input_AC = (input * 2) - 1 \quad (3.1)$$

Finally the input array is passed to the CIC core function *dws_cic_bittrue* and the output array is computed.

3.3 MATLAB code translated in C++

The entire code for the production of the golden output is translated in C++.

3.3.1 The testing environment in C++

The testbench environment in C++ is structured in the same way of the one described in MATLAB. The digital input generation is the first step for the golden output creation, so for the C++ testbench environment. By using the class **vector**, the time vector and the input vector are created. Both are initialized as single element vectors, containing a 0. The following elements are inserted by using the method *push.back*, which exploits the dynamically allocated space in memory. This is necessary since the amount of input data that the filter have to process to produce the golden output is very high ($N_{val} = 282244$). For the same reason, all of the arrays are treated as vectors.

```

1  vector<double> gen_dig_stim(double amp, double f, double offset, double fs,
2  float tend, int nbit){
3      //time vector declaration and initialization
4      vector<double> t (1,0);
5      //input vector declaration and initialization
6      vector<double> vi;
7      int da=0;
8      //output vector declaration and initialization
9      vector<double> vi_int;
10     //time vector creation
11     for(unsigned i=1; i<N_val; ++i){
12         t.push_back(t[i-1]+1/fs);
13     }
14     //input vector creation

```

```

15     for(unsigned i=0; i<N_val; ++i){
16         vi.push_back(pow(10.0,amp/20)*sin(2*pi*f*t[i])+
17             pow(10.0,(offset/20)));
18     }
19     for(unsigned i=0; i<N_val; ++i){
20         vi_int.push_back(round(vi[i]*pow(2.0,(nbit-1))-1));
21     }
22     return vi_int;
23 }

```

The second step is to perform the PDM.

```

1  vector<double> gen_pdm(double amp, double f, double offset,
2  double fs, float tend, int nb, int adddith, string file_name) {

```

The PDM is created by computing some vectors as show is the code above.

```

1  //vectors computation
2  for(unsigned i=1; i<N_val; i++){
3      //x1
4      x1.push_back(b[0]*in[i]-c[0]*y[i-1]-g[0]*int2[i-1]);
5      .
6      .
7      .
8      //u
9      u.push_back(b[4]*in[i]+a[0]*int1[i]+a[1]*int2[i]+a[2]*int3[i]+a[3]*int4[i]);
10     //y
11     int z=0; //this value is 1 if u[w]>=0, 0 otherwise. It's a logic operation
12     if (u[i]>=0){
13         z=1;
14     }
15     else
16         z=0;
17     y.push_back(z*2-1);
18     for(unsigned i=0; i<N_val; i++){

```

```

19     mod_dout.push_back((y[i]+1)/2.0);
20 }
21 return mod_dout;

```

The testbench environment consists also of a function representing the output results on 19 bits.

```
vector<double> dws_dyn_wa(vector<double> vi, int nbit)
```

By calling the function *dws_cic_bittrue*, the golden output are generated. The function parameters are initialized as follows:

```

1 vo_ch1_cic=dws_cic_bittrue(cic_dwsr, vi_cic_ch1, nbdi_cic, nbdo_cic,
2 cic_ord, cic_diffdel, dec_ph);

```

- `int cic_dwsr = 8;`
- `int sig_ch2_a = -8;`
- `int nbdi_cic = 1;`
- `int nbdo_cic = 19;`
- `int cic_ord = 8;`
- `int cic_diffdel = 2;`
- `int dec_ph = 2;`

3.3.2 Filter algorithm and its implementation

The core of the MATLAB code is the *dws_cic_bittrue* function. The function described in C++ follows the same algorithms used by Silicon Mitus in the MATLAB code.

The C++ code exploits the class `std::vector` which allows to create dynamic allocated arrays.

The function declaration is shown below.

```

1 vector<double> dws_cic_bittrue(int dwsr, vector<double> vi, int nbdi,
2                               int nbdo, int ord, int diffdel, int dec_ph)

```


- `int dwsr`: it is an *int* variable which perform decimation operation;
- `vector<double> vi`: it is the input vector;
- `int ndbi`: it is the input parallelism;
- `int ndbo`: it is the output parallelism;
- `int ord`: it is the CIC filter order;
- `int diffdel`: it is the differential delay;
- `int dec_ph`: it is the decimation phase;

In the following lines the C++ code implementing the computation done by the integral section is shown. The matrix `vector<vector<double> > vint` has to be computed.

```

1  vector<vector<double> > vint;
2  vector<vector<double> >::iterator i_vint;
3  //integral loop repeated according to the CIC order
4  vint.push_back(vi);
5  for(unsigned i=1; i<=6; i++){
6      vector <double> tmp;
7      tmp.push_back(vint[i-1][0]);
8      for(unsigned j=1; j<N_val; j++){
9          tmp.push_back(vint[i-1][j]+tmp[j-1]);
10     }
11     tmp=dws_dyn_wa(tmp, num_dyn_bit, 0);
12     vint.push_back(tmp);
13 }
```

In Figure 3.4 the graphical representation of the integral section algorithm is reported. When the whole matrix is computed the last row is extracted and passed as input to the following stage, which is the decimation stage.

The aim is to create the vector *vdws* inserting in it one element every eight elements of the last row of the matrix *vint* computed by the integral section. This operation is

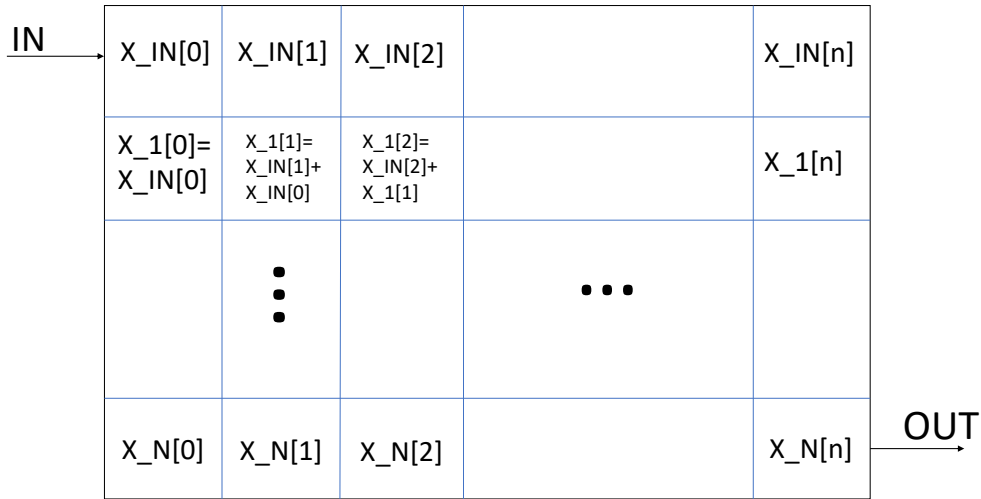


Figure 3.4: Graphical representation of the integral section computation algorithm

performed by the counter *cnt* which increments its value by a *dwsr* value (which is 8 in the case study) as reported in Figure 3.5. This means that the vector *vdws* contains a number of elements decreased by a 8 factor compared to the number of elements in *vint*[6].

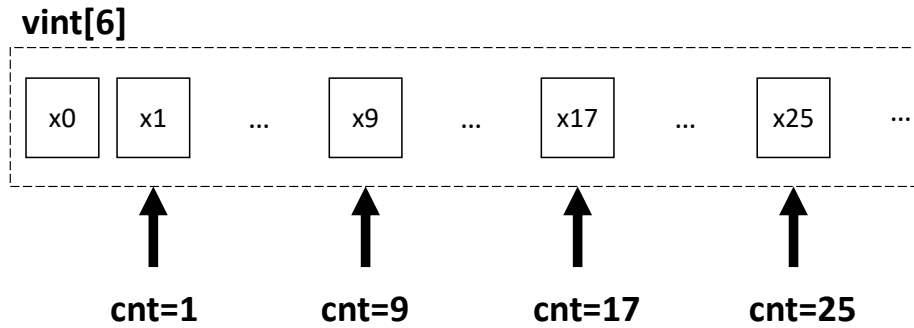


Figure 3.5: Graphical representation of the decimation stage computation algorithm

```

1  vector<double> vdws;
2  //discard downsampling
3  unsigned cnt=1;
4  for(unsigned i=1; i<N_val; i++){
5      if(i==cnt){
6          vdws.push_back(vint[6][i]);

```

```

7         cnt=cnt+dwsr;
8     }
9 }

```

Finally, the output of the filter is computed by the derivative section. The aim is to compute the matrix *vdiff* as done for the integral section following the algorithm in Figure 3.6, which reports the graphical representation of the derivative section computation algorithm. The derivative section code is shown below. Notice that the 6-th

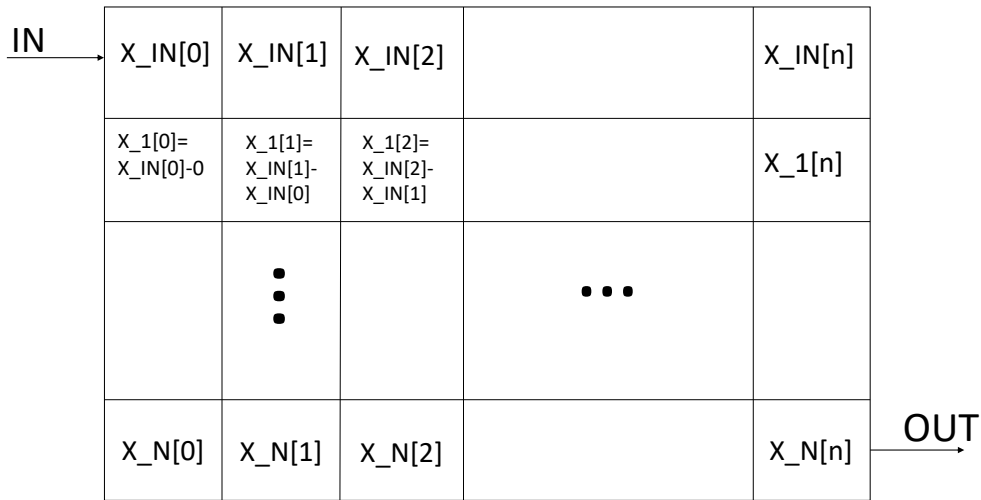


Figure 3.6: Graphical representation of the derivative section computation algorithm

row contains the final output of the filter. All the elements of the *vdiff*[6] are rounded and placed in the output vector *vout*.

```

1  vector<vector<double> > vdiff;
2  vector<vector<double> >::iterator i_vdiff;
3  vector<double> vout; //output vector
4  vdiff.push_back(vdws);
5  unsigned len_vdws=vdws.size();
6  //differential loop repeated according to the CIC order
7  for(unsigned i=1; i<=6; i++){
8      vector<double> tmp1;
9      vector<double> tmp2;

```

```

10     tmp2.push_back(0.0);
11     for(unsigned j=0; j<len_vdws-1; j++){
12         tmp2.push_back(vdiff[i-1][j]);
13     }
14     for(unsigned k=0; k<len_vdws; k++){
15         tmp1.push_back(vdiff[i-1][k]-tmp2[k]);
16     }
17     tmp1=dws_dyn_wa(tmp1, num_dyn_bit, 0);
18     vdiff.push_back(tmp1);
19 }
20 for(unsigned i=0; i<len_vdws; i++){
21     vout.push_back(floor(vdiff[6][i]*pow(2,(nbdo-num_dyn_bit))+0.5));
22 }
23 return vout;
24 }

```

3.4 C++ code to synthesize the CIC filter

Once the whole MATLAB code is translated in C++, the idea is to isolate the core function and to pass it in *Catapult* so that it can be synthesized and the RTL description of the architecture can be produced.

The CIC function implemented as described in the previous section, produces the output with an algorithm which takes into account the number of samples at the input. In order to allow *Catapult* to work, the described function has to get rid of the dependence from the input.

The first step is to re-think about the algorithm.

Integrative section algorithm

In Figure 3.7 the basic principle of the new **integrative section** algorithm is reported. In this case only two arrays are used: *outsum* and *integ*. The number of elements in the array *integ* is 6, as the filter order value is, while the elements in the array *outsum* is 7, so the value of the CIC filter order plus one element which is the incoming input.

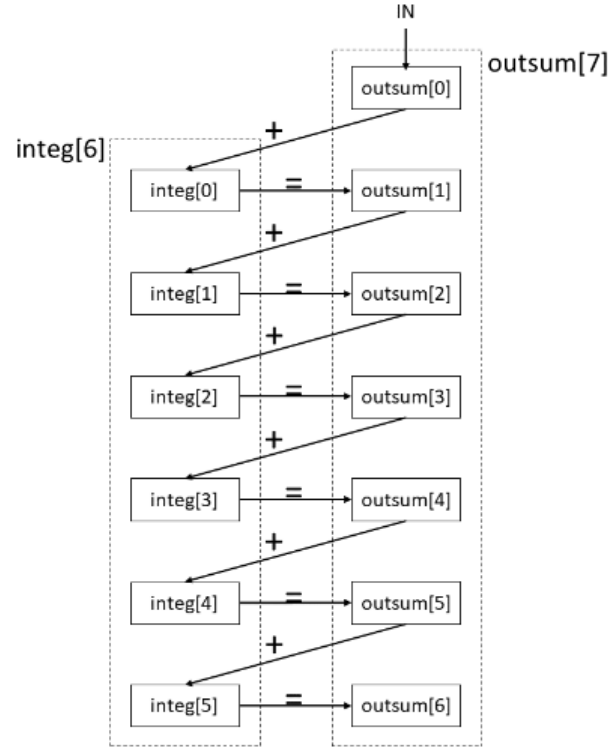


Figure 3.7: The basic principle of the integrative algorithm

Every time an input occurs the function is called and the *outsum* array computed in the previous function call is copied in the array *integ*. Then the array *outsum* is computed by using the array *integ*, where the values of *outsum* computed in the previous function call are stored.

Derivative section algorithm

For the **derivative section** the new algorithm is similar to the one of the integrative section, as reported in Figure 3.8. Also in this case the number of elements in the *outdiff* array is *order* + 1, so 7, while the elements in the *diff* array is *ord*, so 6. That's because the last elements of the array coming from the decimation stage is stored in the array *outdiff*.

The derivative section provides the final output of the filter, which is the last element of the array *outdiff*.

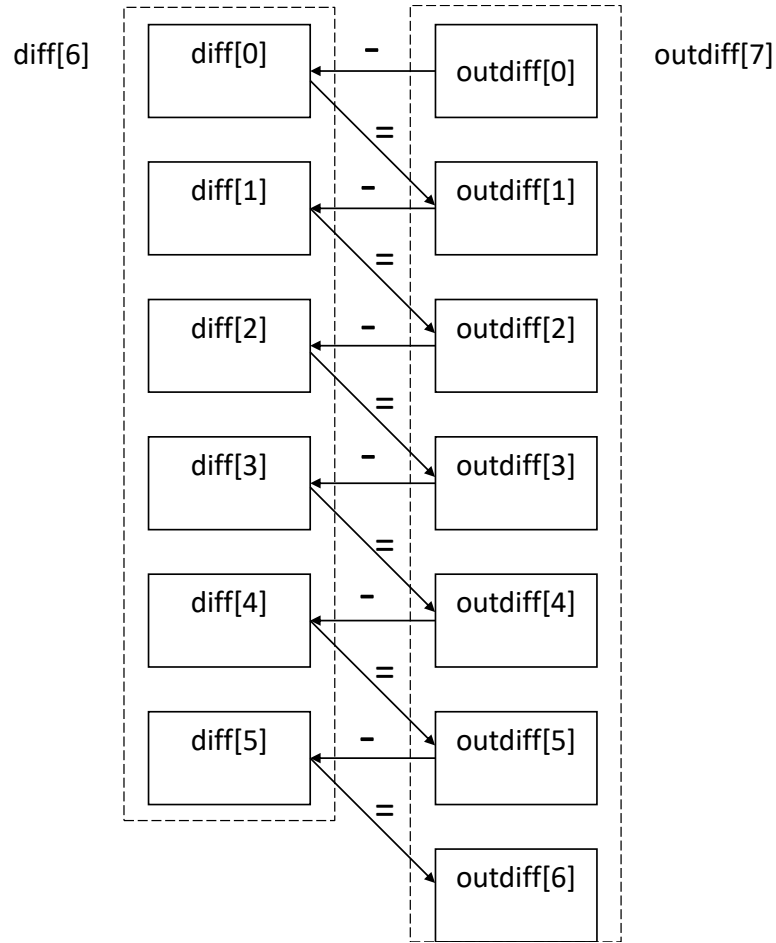


Figure 3.8: The basic principle of the derivative section algorithm

The synthesizable code

In the following lines the implementation of a CIC filter is shown.

```

1  double dws_cic_bittrue(double vi, int ord){
2      static double integ[ord];
3      static double outsum[ord+1];
4      static unsigned in_cnt = 0;
5
6      static double diff[ord];
7      static double outdiff[ord+1];
8
9      INTEGRAL_COPY_LOOP: for( int i=0; i<ord; i++){
10         integ[i]=outsum[i+1];

```

```

11     }
12     outsum[0] = vi;
13     INTEGRAL_LOOP: for (int i=0; i<ord; i++){
14         outsum[i+1]=dws_dyn_wa(outsum[i]+integ[i], 19, 0);
15     }
16     if(in_cnt==1 || (in_cnt-1)%8==0){
17         DERIVATIVE_COPY_LOOP: for(int i=ord-1; i>=0; i--){
18             diff[i] = outdiff[i];
19         }
20         outdiff[0] = outsum[ord];
21         DERIVATIVE_LOOP: for (int i=0; i<ord; i++){
22             outdiff[i+1]=dws_dyn_wa(outdiff[i]-diff[i], 19, 0);
23         }
24     }
25     in_cnt++;
26     return outdiff[ord];
27 }

```

The code shown above implements one filter's channel. For sake of simplicity the part of the code implementing the second channel is missing, because it is exactly identical to the one of the first channel. The entire code is shown in appendix A.1.

The elements of the arrays *outsum*, *outdiff*, *integ*, *diff* are declared as 'double', as done in the previous C++ code in order to compare the output results with the golden output produced by the MATLAB code or by the C++ code. The arrays are also declared as 'static', because the data computed after each function call can be reused when a new input has to be processed. This is useful for the arrays *integ* and *diff*, because their previous content is directly involved in the sum and the subtraction operations in integrative and derivative sections. The arrays *outsum* and *outdiff* are also 'static' because in each function call their content from the previous computation is copied in *integ* and *diff* arrays.

For this code production, the parallelism of the input, intermediate and output data is not used to define the variables, so, in order to compare the results of this code with the one of the previous code it is necessary to use the function to represent the output

values into the binary dynamic (*dws_dyn_wa*).

The code structure is composed by four *for* statements. Each section is described using two independent loops: the first one is dedicated to the *Copy*; the second one is referred to the operation that has to be performed. In the *Copy Loops* the storing in the arrays *integ* and in *diff* of all the elements of the arrays *outsum* and *outdiff* is performed. The *Integral Loop* or the *Derivative Loop* allow the operations (sum for integration and subtraction for derivation).

A counter (*in_cnt*) is also instantiated as '**unsigned**'. It has the function to discard samples processed by the integral section in order to send the only the useful samples to the derivative section. In particular it is necessary to send to the derivative section the second integrated sample and one integrated sample every eight computed by the integrative section. This discard operation is implemented using the *if* statement. When the condition is verified, the derivative section is enabled, so it can work, too.

Optimized synthesizable code

Since Catapult is able to use variables with data types that take into account the parallelism of the data, it is useful to use this declaration of variables exploiting the arbitrary-length bit-accurate integer and fixed-point datatypes. The *ac_int* representation was used, and in particular the following data types are exploited all around the design:

- *IN_TYPE*(*ac_int* < 1, *false* >): the input of the CIC filter are 1-bit unsigned data;
- *CNT_TYPE*(*ac_int* < 3, *false* >): the counter performing decimation is a modulo 8 counter, so it is a 3bit unsigned number;
- *AC_TYPE_s*(*ac_int* < 2, *true* >): the filter requires to work with samples without the DC component. To perform this operation, the input datum equal to 0 has to be represent as -1, while the input datum equal to 1 remains 1. In order to represent correctly this values, a 2bit signed representation is required;
- *OUT_TYPE*(*ac_int* < 19, *false* >): all the value processed by every stage of the integrative and derivative sections and given as output are represent as 19bit unsigned numbers.


```

1  void dws_cic_bittrue(IN_TYPE vi_ch1, IN_TYPE vi_ch2,
2                        OUT_TYPE &out_cic_ch1, OUT_TYPE &out_cic_ch2){
3
4      static OUT_TYPE integ_ch1[ord];
5      static OUT_TYPE outsum_ch1[ord+1];
6      static CNT_TYPE in_cnt_ch1 = 7;
7      static OUT_TYPE diff_ch1[ord];
8      static OUT_TYPE outdiff_ch1[ord+1];
9
10     AC_TYPE_s vi_ac_ch1;
11     vi_ac_ch1 = AC_TYPE_s(vi_ch1)*2 - 1;
12
13     INTEGRAL_COPY_LOOP1: for( int i=0; i<ord; i++){
14         integ_ch1[i]=outsum_ch1[i+1];
15     }
16     outsum_ch1[0] = OUT_TYPE(vi_ac_ch1);
17     INTEGRAL_LOOP1: for (int i=0; i<ord; i++){
18         outsum_ch1[i+1]=outsum_ch1[i]+integ_ch1[i];
19     }
20     if(in_cnt_ch1==0){
21         DIFFERENTIAL_COPY_LOOP1: for(int i=ord-1; i>=0; i--){
22             diff_ch1[i] = outdiff_ch1[i];
23         }
24         outdiff_ch1[0] = outsum_ch1[ord];
25         DIFFERENTIAL_LOOP1: for (int i=0; i<ord; i++){
26             outdiff_ch1[i+1]=outdiff_ch1[i]-diff_ch1[i];
27         }
28     }
29     in_cnt_ch1++;
30     out_cic_ch1 = outdiff_ch1[ord];
31 }

```

Notice the counter (*in_cnt_ch1*) instantiated used to do the decimation operation as

described previously. In this case the initialization of the counter is at the value 7. The code written in this way allows *Catapult* to synthesize the architecture, because the C++ description algorithm is totally independent from the input.

CHAPTER 4

CIC filter development with Catapult

In this chapter, the design of the CIC filter using Catapult is described. From the C++ algorithm description, the RTL code is produced by Catapult and the results obtained using Catapult during the pre-synthesis phase, and the ones produced by Synopsys during the post-synthesis phase are described and compared. In particular the results in terms of area and power consumption are shown and the differences between the explored solutions are reported. The aim of the work is to demonstrate that by using HLS it is possible to obtain high quality implementations. This aim is obtained by comparing the architecture synthesized by using the HLS tool *Catapult*, with the one produced by *Silicon Mitus* which is implemented with the classical hand-written RTL design. Figure 4.1 reports a section of the simulation of the reference architecture, with both the channels. The output sample rate of the architecture is $f_{s_out} = 1/R * f_{s_in}$,

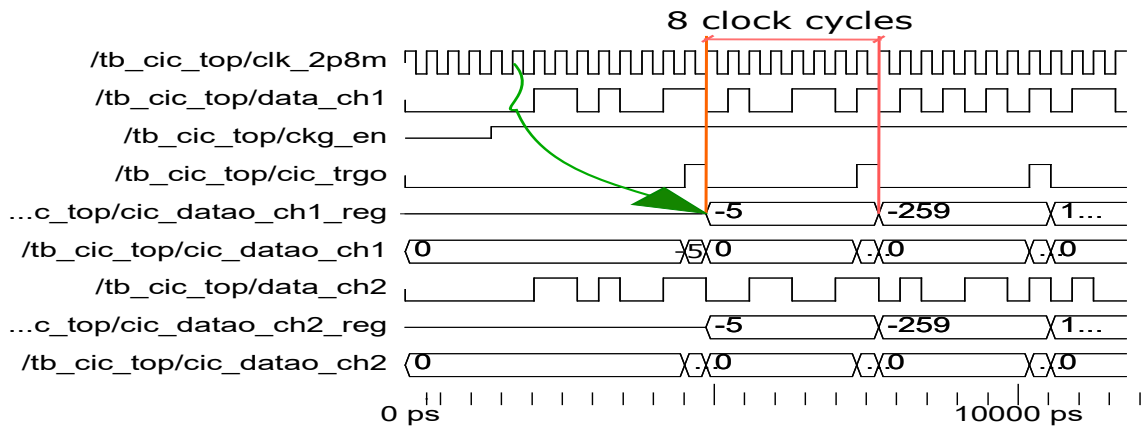


Figure 4.1: ModelSim simulation of the reference architecture by Silicon Mitus

where R is the decimation factor, which is 8 in this case, and f_{s_in} is the input sample rate equal to 2.8224MHz. It means that the output is updated every 8 clock cycles as it is reported in Figure 4.1.

4.1 Correctness verification of the synthesized architecture

The first step is to evaluate if the architecture generated by Catapult provides the corrected output. In order to do this *SCVerify* is enabled. In order to perform this step a testbench in C++ is written. *SCVerify* uses *ModelSim* to simulate the architecture and to check that no output errors occur. The synthesis in this step is done by *Catapult*, without using any specific setting. Once *Catapult* terminates the synthesis and produces the RLT description of the architecture, *SCVerify* creates a *SystemC* wrapper, which tests the architecture, and compare the results with the ones produced by the C++ testbench, as described in Chapter1. In the following lines the testbench written in C++ is reported. The input are taken from a *.txt* file. For sake of simplicity only the management of the file containing the input of the first channel is shown, while the entire code is shown in Appendix A.2.

```

1  CCS_MAIN(int argc, char **argv)    // required for sc verify flow in
2                                     // Catapult
3  {
4      ifstream in_ch1 ("cic_in_ch1.txt", ios::in);
5      vector<IN_TYPE> vi_cic_ch1;
6      int in1; //in1=[0 o 1], in1_bin=[-1 o 1]
7      OUT_TYPE in1_bin;
8      OUT_TYPE vout_cic_ch1;
9      vector<OUT_TYPE> cic_output_ch1;
10     while(!in_ch1.eof()){
11         in_ch1>>in1;
12         vi_cic_ch1.push_back(IN_TYPE(in1));
13     }

```

```

14     in_ch1.close();
15
16     //the same is done for channel 2//
17
18     for (unsigned i=0; i<vi_cic_ch1.size(); i++){
19         CCS_DESIGN(dws_cic_bittrue)(vi_cic_ch1[i], vi_cic_ch2[i],
20                                     vout_cic_ch1, vout_cic_ch2);
21     }
22     CCS_RETURN(0);
23 }

```

The input are stored in a vector containing elements, whose data type is *IN_TYPE*, so 1bit unsigned elements. Every time an input occurs the function is called. The produced output are stored in the vector of *OUT_TYPE* elements (19 bits signed). As shown in the *ModelSim* message below, there are no errors, so no mismatches between the output produced by the architecture, and the one produced by the C++ testbench.

```

# Info: Execution of user-supplied C++ testbench 'main()' has
    completed with exit code = 0
#
# Info: Collecting data completed
#   captured 284 values of vi_ch1
#   captured 284 values of vi_ch2
#   captured 284 values of out_cic_ch1
#   captured 284 values of out_cic_ch2
# Info: scverify_top/user_tb: Simulation completed
#
# Checking results
# 'out_cic_ch1'
#   capture count          = 284
#   comparison count       = 284
#   ignore count           = 0
#   error count            = 0
#   stuck in dut fifo      = 0
#   stuck in golden fifo   = 0
# 'out_cic_ch2'

```

```

# capture count      = 284
# comparison count   = 284
# ignore count       = 0
# error count        = 0
# stuck in dut fifo   = 0
# stuck in golden fifo = 0
#
# Info: scverify_top/user_tb: Simulation PASSED 1083657975 ps

```

The Figure 4.2 shows the *ModelSim* simulation done using *SCVerify*. The signals *out_cic_ch1-ERR#* and *out_cic_ch2-ERR#* counts the output errors, which are 0 in this case, remarking the correct behavior of the architecture. The data *out_cic_ch1-GOLDEN* and *out_cic_ch2-GOLDEN* are the output data produced by the C++ testbench in appendix A.2, while the data *out_cic_ch1-DUT* and *out_cic_ch2-DUT* are produced by the *SystemC* wrapper testbench produced by *SCVerify*.

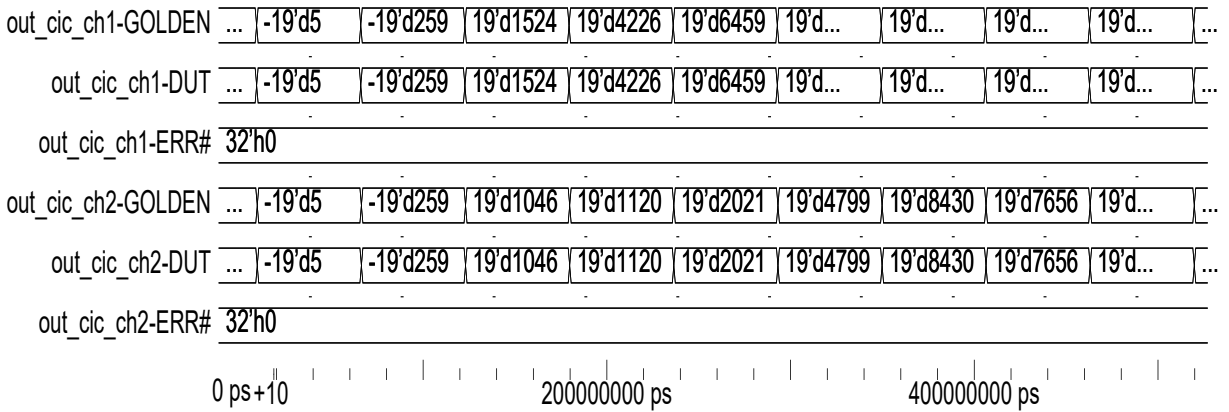


Figure 4.2: ModelSim simulation shows the correct behaviour of the architecture produced by Catapult

4.2 Different architectures of the CIC filter and Catapult results

Once the correctness of the architecture is verified, it is possible to proceed to explore different architectural solutions to evaluate what is the best in terms of area power and timing. This process is done by exploiting the Catapult synthesis first, and then

generating the gate-level code with *Synopsys Design Compiler*, starting from the Verilog RTL code produced by *Catapult*.

Starting from the code described in appendix A.1, the *Catapult* synthesis is performed by using as clock frequency **2.8224MHz** and **45nm** target technology.

The Table 4.1 shows the timing results from *Catapult* synthesis. Note that the different simulations are produced without changing the C++ code, but by simply changing the simulation parameters described in Chapter1. The code is synthesized to create folded architecture (F), first. Then different unfolding grade (U) and initiation intervals (P) are applied.

Architecture solutions	Catapult results		
	Latency cycles	Throughput cycles	Slack(ns)
F	40	41	352.3
P=1 F	36	36	353.28
P=1 U=2	18	18	352.74
P=1 U=3	12	12	352.09
P=1 U=4	16	16	351.56
P=1 U=5	16	16	350.8
P=1 U=6	1	1	337.42

Table 4.1: Catapult results in terms of latency an throughput cycles and slack time

The architecture full-unrolled (U=6) and with an initiation interval 1 (P=1) is the one more interesting because it reflects the timing behavior of the reference architecture. The Figure 4.3 explain the reason why *Catapult* evaluation of the throughput is 1. Every output is written of the bus 8 times. The signal *out_cic_ch1 – TRANS#* and *out_cic_ch2 – TRANS#* counts the number of transition on the output buses, so the number of transactions on the bus is 8, per every output. This means that this behavior is similar to the one of the reference architecture provided by *Silicon Mitus*, shown in Figure 4.1.

The Table 4.2 shows what are the allocated resources in the different architectural solution. Notice that folded architecture has the highest area. That's because the operation of the `INTEGRAL_COPY_LOOP` and the `DERIVATIVE_COPY_LOOP` are implemented

	Allocated resources						Total area μm^2
	Adders		Multiplexers		Registers		
Architectural solutions	Number	Parallelism	Number	Parallelism	Number	Parallelism	
F	1	4bit	3	3bit	11	3bit	21946.45
	4	3bit	102	19bit	121	19bit	
	1	19bit					
P=1 F	2	4bit	12	19bit	12	3bit	8594.17
	14	3bit	6	1bit	1	2bit	
	4	19bit	10	3bit	40	19bit	
					11	1bit	
P=1 U=2	2	3bit	10	2bit	4	3bit	8570.85
	8	2bit	18	19bit	9	2bit	
	8	19bit	6	1bit	40	19bit	
					11	1bit	
P=1 U=3	16	3bit	22	19bit	4	3bit	9603.20
	6	2bit	16	1bit	1	2bit	
	12	19bit	4	3bit	40	19bit	
					23	1bit	
P=1 U=4	2	3bit	14	19bit	4	3bit	10386.4
	16	19bit	10	1bit	1	2bit	
					52	19bit	
					19	1bit	
P=1 U=5	2	4bit	18	19bit	4	3bit	11884.62
	8	3bit	19	1bit	1	2bit	
	2	2bit			52	19bit	
	20	19bit			27	1bit	
P=1 U=6	2	3bit	0	-	2	3bit	5163.6
	24	19bit	0	-	24	19bit	
					2	19bit	
					3	1bit	

Table 4.2: The table shows the resources allocated by Catapult for the different architectural solutions

reference ones. The architecture produced by *Silicon Mitus* is the one reported in Figure 4.5.

The interface signals are:

- *rstb*: it is the asynchronous reset of the architecture, which creates the internal synchronous reset;

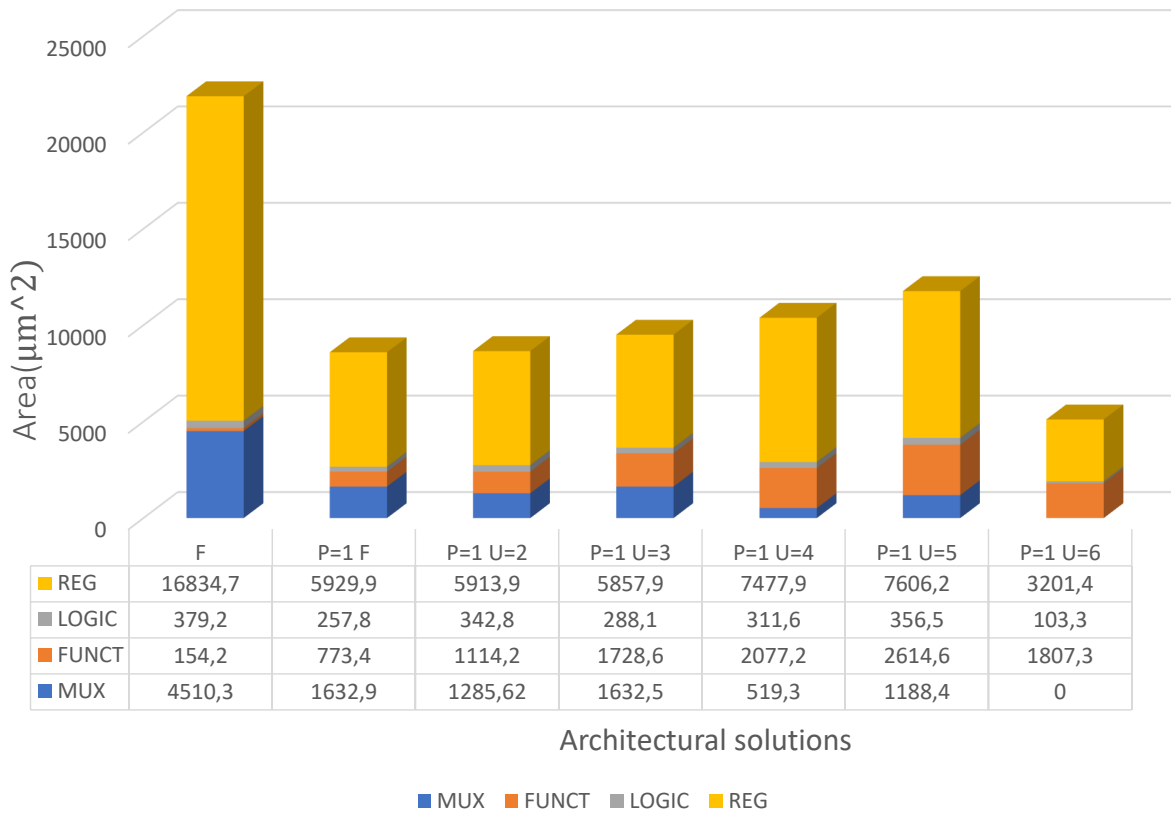


Figure 4.4: How multiplexers, registers, functional units and logic affect the area of the different architectures

Unfolding grade	Area(μm^2)	Power(μW) Dynamic / Leakage	Time(ns) Slack / Arrival time
F	17007.50	47.88 / 388.51	351.05 / 3.13
P=1 F	6563.81	16.20 / 136.85	351.58 / 2.60
P=1 U=2	6517.26	16.15 / 142.46	351.47 / 2.71
P=1 U=3	6738.31	16.27 / 145.34	351.35 / 2.83
P=1 U=4	8154.22	20.24 / 174.02	351.6 / 2.58
P=1 U=5	8843.96	20.64 / 186.78	351.26 / 2.92
P=1 U=6	5163.59	12.52 / 94.77	350.21 / 3.97

Table 4.3: Synopsys results

- *data_ch1* and *data_ch2*: they are the 1bit input data of the two filters;
- *ckg_en*: it is the clock enable to perform the clock gating;

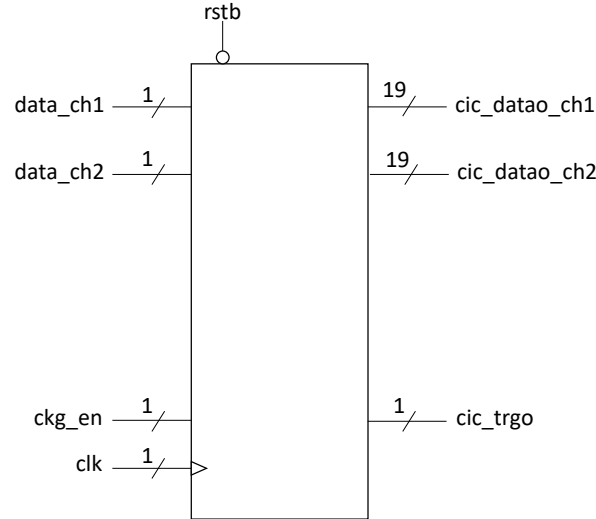


Figure 4.5: Silicon Mitus architecture (top view)

- *clk*: it is the clock. Its frequency is 2.8224MHz;
- *cic_dataao_ch1* and *cic_dataao_ch1*: are the 19bit filters output data;
- *trgo*: it is the signal indicating when the output is ready.

In this case the architecture design with HLS has to include a clock enable and an asynchronous reset. Moreover, the reference architecture, by *Silicon Mitus*, produces internally a synchronous reset starting from the asynchronous reset (*rstb*) and the clock enable (*ckg_en*). The synchronous reset has the aim to reset all the internal registers of both the filters. For the architecture produced with the HLS methodology, enable, clock and reset signals can be added to the architecture without changing the code.

The clock, enable and reset signals are set as follows:

- *clk*: the clock frequency is 2.8224MHz and the data sampling is performed on its rising edge;
- *rst*: the synchronous reset is high-active;
- *arst_n*: the asynchronous reset is low-active;
- *en*: the clock enable is high-active.

The full-unrolled architecture is developed and the *Catapult* results are:

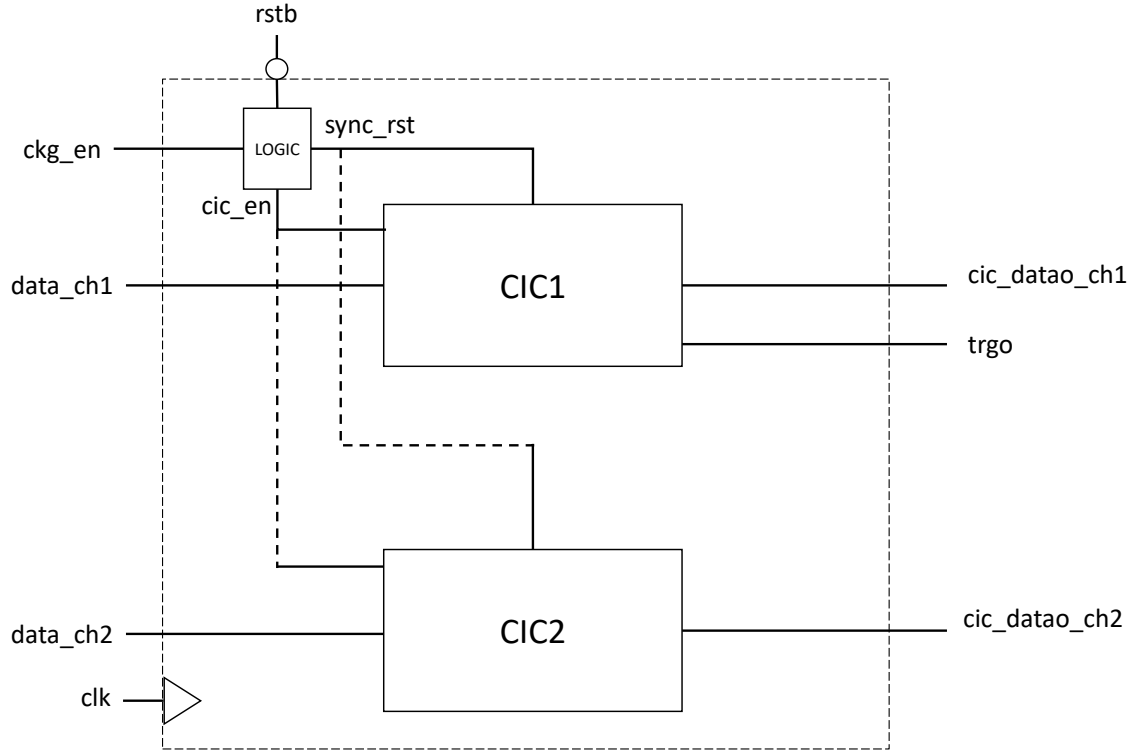


Figure 4.6: Internal structure of the reference architecture bt *Silicon Mitus*

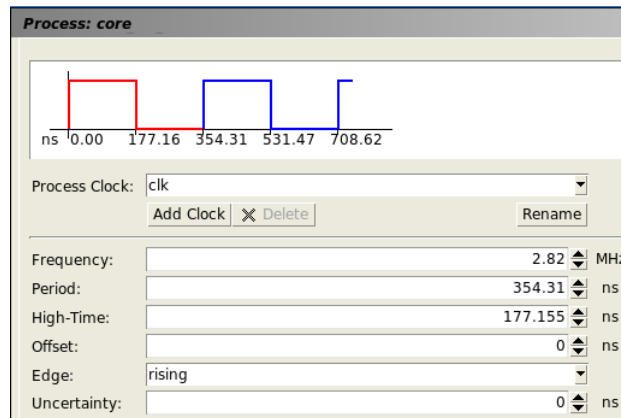


Figure 4.7: Clock setting

- Slack cycle: 1;
- Throughput cycle: 1;
- Area: 6204.05 μm^2 ;
- Slack time: 337.39 ns.

The screenshot shows a configuration window titled "Process: core". It contains three sections for signal settings:

- Synchronous Reset:** A checkbox is checked. The "Signal Name" field contains "rst" and the "Active:" dropdown is set to "high".
- Asynchronous Reset:** A checkbox is checked. The "Signal Name" field contains "arst_n" and the "Active:" dropdown is set to "low".
- Enable:** A checkbox is checked. The "Signal Name" field contains "en" and the "Active:" dropdown is set to "high".

Figure 4.8: Signal setting

Catapult uses *triosy_lz* signals for each C++ variable to indicate the I/O completion of the associated signals. In order to avoid these signals at the architecture interface it is possible to use the interface using *ac_channel* interface. This latter solves the problem to build a streaming interface to guarantee that the data communication is correct, so that data are read and written in the same order they are processed. So, the *ac_channel* interface constructs a FIFO discipline to ensure the correctness of the communication between different blocks.

The C++ code is slightly modified to allow the synthesis using *ac_channel* interface.

```

1  #include <ac_fixed>
2  #include <ac_channel>
3  const unsigned ord = 6;
4  typedef ac_int<1,false> IN_TYPE;
5  typedef ac_int<2,true> AC_TYPE_s;
6  typedef ac_int<19, true> OUT_TYPE;
7  typedef ac_int<1, false> BIT_TYPE;
8
9  void dws_cic_bittrue(ac_channel<IN_TYPE> &, ac_channel<IN_TYPE> &,
10 ac_channel<IN_TYPE> &, ac_channel<OUT_TYPE> &, ac_channel<OUT_TYPE> &,
11 BIT_TYPE &ready_out);

```

Once the directive to synthesize a full-unrolled architecture are set, the *Catapult* results are:

- Slack cycle: 1;
- Throughput cycle: 1;
- Area: 6767.38 μm^2 ;
- Slack time: 337.25 ns.

This architecture is larger than the one implemented without *ac_channel* interface. For this reason the solution without *ac_channel* interface is preferred.

4.3.1 Architecture functioning

The top view of this architecture synthesized by *Catapult* is the one represented in Figure 4.9.

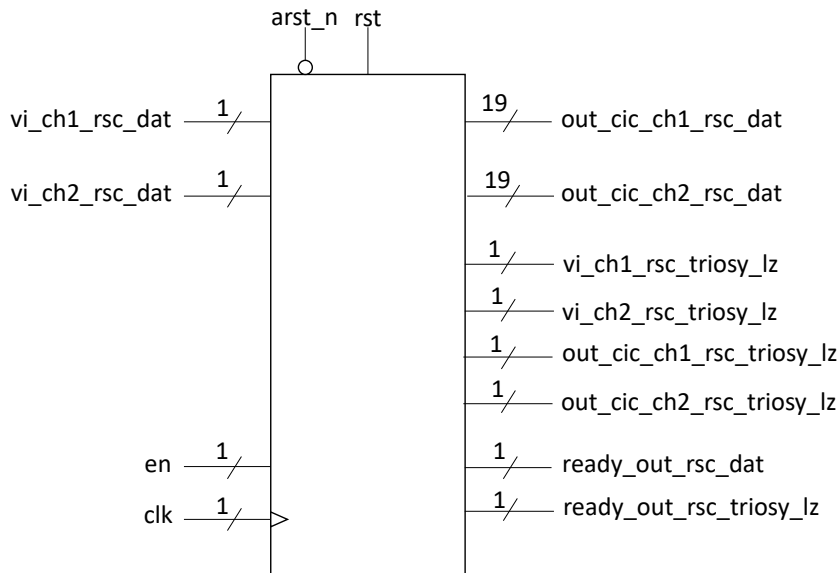


Figure 4.9: Top view designed by Catapult

The *triosy_lz* signals enlarge the total area and make the architecture interface (Figure 4.9) different from the one of the reference architecture (Figure 4.5). So the solution is to eliminate them by hand in the Verilog code produced by *Catapult*, with a very small effort. The resulting architecture is the one reported in Figure 4.10.

Table 4.4 reports that the results evaluated with *Catapult* and *Synopsys* are slightly different but with the same behaviour, as shown in Figure 4.11.

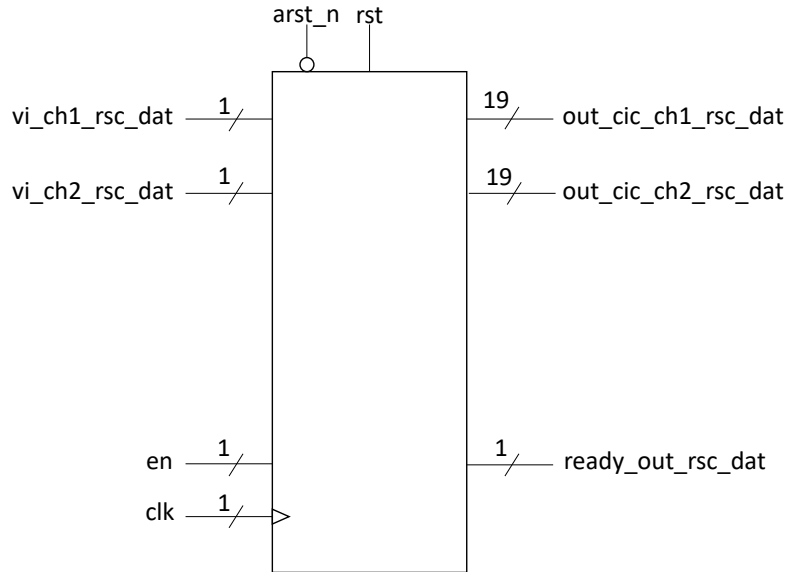


Figure 4.10: Top view of the optimized architecture

CATAPULT VS SYNOPSIS-AREA EVALUATION

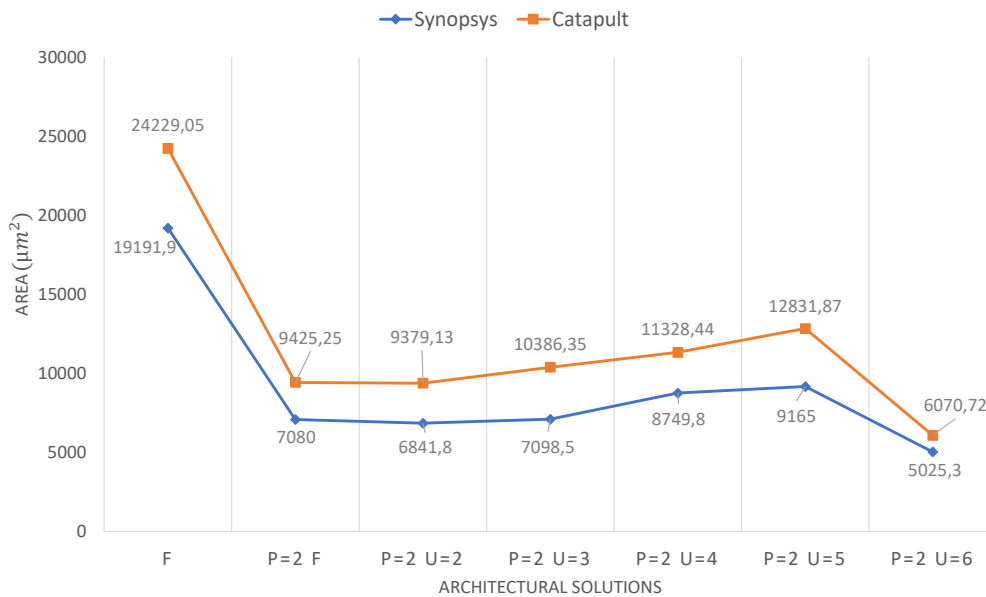


Figure 4.11: Area estimation: Catapult vs Synopsys

Notice that the Table 4.4 reports two full-unrolling solutions. By using the architecture full-unrolled and with an initiation interval equal to 2 the area is lower compared to the full-unrolled architecture with initiation interval 1.

The solution with P=2 can take as input the signals with a sample rate 2.8224MHz,

but it has to use as internal frequency for the processing task 5.768MHz. In the DAC design by Silicon Mitus, it is not possible to use two clock regimes, so this solution is not further developed.

Tables 4.5 and 4.6 shows the difference in percentage between the Catapult architecture and the reference architecture by Silicon Mitus. The architecture selected for the

Unfolding grade	Area by Synopsys(μm^2)	Area by Catapult(μm^2)	Power Dynamic/ Leakage (μW)	Time Slack/ Arrival time by Synopsys (ns)	Time Slack/ Arrival time by Catapult (ns)
F	19191,9	24229,05	50,17/349,45	351,05/3,13	352,29
P=2 F	7080,0	9425,25	17,28/144,96	351,58/2,60	353,26
P=2 U=2	6841,8	9379,13	17,28/140,91	351,47/2,71	352,72
P=2 U=3	7098,5	10386,35	17,25/143,77	351,35/2,83	352,08
P=2 U=4	8749,8	11328,44	21,72/166,61	351,6/2,58	351,54
P=2 U=5	9165,0	12831,87	21,97/154,95	351,26/2,92	350,78
P=2 U=6	5025,3	6070,72	13,64/93,32	350,21/3,97	337,25
P=1 U=6	5402,9	6204,05	12,96/88,53	350,34/3,85	337,39

Table 4.4: Catapult and Synopsys results of the final architecture

comparison with the reference architecture provided by Silicon Mitus, is the full unrolled one, with initiation interval 1 (P=1 U=6). By using *Synopsys Design Compiler* the logic synthesis is performed. The synthesis results differences between the Silicon Mitus architecture and the Catapult architecture are performed by using the *Compile* and the *Compile ultra* directives, and are reported in Table 4.5.

Notice that the with the architecture synthesized with the *Compile ultra* directive the area and the power consumption of the architecture implemented with *Catapult* are lower that the one of the architecture implemented by using the classical RTL design methodology. In Table 4.6 the difference of the results of the logic synthesis between the two architecture are highlighted.

In this way the aim to demonstrate the good quality production of a HLS synthesis is achieved.

	Catapult		Silicon Mitus	
	Compile	Compile Ultra	Compile	Compile Ultra
Area (μm^2)	6002.02	5402.99	5993.78	5564.64
Power Dyn/Stat (μW)	14.07 / 101.93	12.96 / 88.53	12.14 / 102.85	12.04 / 94.1
Time Slack/Arrival (ns)	350.20 / 3.99	350.34 / 3.85	351.11 / 2.62	351.21 / 2.61

Table 4.5: Catapult final architecture evaluated with Synopys

	Catapult	
	Compile	Compile Ultra
Area	+0.14%	-2.9%
Power Dyn/Stat	+0.88%	-4.38%
Time Slack/Arrival (ns)	+1.37	+1.24

Table 4.6: Catapult final architecture comparisons with Silicon Mitus architecture

CHAPTER 5

Conclusion

The thesis work aims to evaluate the quality of the architecture implemented by using the HLS design methodology. The area, timing and power estimation difference between the hand-written RTL reference design and the one developed with HLS is summarized below.

	Catapult
Area	-2.9%
Power Dyn/Stat	-4.38%
Time Slack/Arrival (<i>ns</i>)	+1.24

The performance results in this case study are even better than the one obtained with the hand-written RTL design. This means that from the current generation of HLS, it is possible to consider it as a valid design methodology, with results very close to the ones of the well-optimized classical RTL design.

The great advantage of design implemented with HLS is the very low time consuming to implement different architectural solutions, since it is simply necessary to properly set the constraints in the HLS tool, without changing the HLL description algorithm. In this way, a very high effort can be dedicated to the algorithm optimization, instead of writing HDL code.

Another important aspect of HLS is the highly reduced effort for verification flow. The fast development of the test is another way to improve productivity.

In conclusion, the HLS can represent a very efficient mean for digital architectures

design, which can lead to high quality results, with a small effort from the designer, who can avoid the redundant work of writing HDL code by hand.

APPENDIX A

Code

A.1 Synthesizable code

```
1 void dws_cic_bittrue(IN_TYPE vi_ch1, IN_TYPE vi_ch2,
2                     OUT_TYPE &out_cic_ch1, OUT_TYPE &out_cic_ch2){
3
4     static OUT_TYPE integ_ch1[ord];
5     static OUT_TYPE outsum_ch1[ord+1];
6     static CNT_TYPE in_cnt_ch1 = 7;
7     static OUT_TYPE diff_ch1[ord];
8     static OUT_TYPE outdiff_ch1[ord+1];
9     AC_TYPE_s vi_ac_ch1;
10    vi_ac_ch1 = AC_TYPE_s(vi_ch1)*2 - 1;
11
12    static OUT_TYPE integ_ch2[ord];
13    static OUT_TYPE outsum_ch2[ord+1];
14    static CNT_TYPE in_cnt_ch2 = 7;
15    static OUT_TYPE diff_ch2[ord];
16    static OUT_TYPE outdiff_ch2[ord+1];
17    AC_TYPE_s vi_ac_ch2;
18    vi_ac_ch2 = AC_TYPE_s(vi_ch2)*2 - 1;
19
20    INTEGRAL_COPY_LOOP1: for( int i=0; i<ord; i++){
21        integ_ch1[i]=outsum_ch1[i+1];
```

```

22     }
23     outsum_ch1[0] = OUT_TYPE(vi_ac_ch1);
24     INTEGRAL_LOOP1: for (int i=0; i<ord; i++){
25         outsum_ch1[i+1]=outsum_ch1[i]+integ_ch1[i];
26     }
27     if(in_cnt_ch1==0){
28         DIFFERENTIAL_COPY_LOOP1: for(int i=ord-1; i>=0; i--){
29             diff_ch1[i] = outdiff_ch1[i];
30         }
31         outdiff_ch1[0] = outsum_ch1[ord];
32         DIFFERENTIAL_LOOP1: for (int i=0; i<ord; i++){
33             outdiff_ch1[i+1]=outdiff_ch1[i]-diff_ch1[i];
34         }
35     }
36     in_cnt_ch1++;
37     out_cic_ch1 = outdiff_ch1[ord];
38
39     INTEGRAL_COPY_LOOP1: for( int i=0; i<ord; i++){
40         integ_ch2[i]=outsum_ch2[i+1];
41     }
42     outsum_ch2[0] = OUT_TYPE(vi_ac_ch2);
43     INTEGRAL_LOOP2: for (int i=0; i<ord; i++){
44         outsum_ch2[i+1]=outsum_ch2[i]+integ_ch2[i];
45     }
46     if(in_cnt_ch2==0){
47         DIFFERENTIAL_COPY_LOOP2: for(int i=ord-1; i>=0; i--){
48             diff_ch2[i] = outdiff_ch2[i];
49         }
50         outdiff_ch2[0] = outsum_ch2[ord];
51         DIFFERENTIAL_LOOP2: for (int i=0; i<ord; i++){
52             outdiff_ch2[i+1]=outdiff_ch2[i]-diff_ch2[i];
53         }
54     }
55     in_cnt_ch2++;

```

```

56     out_cic_ch2 = outdiff_ch2[ord];
57
58 }

```

A.2 C++ Testbench

```

1  #include "cic_synt.h"
2  #include <mc_scverify.h>
3  using namespace std;
4
5  CCS_MAIN(int argc, char **argv)    // required for sc verify flow in Catapult
6  {
7      ifstream in_ch1 ("cic_in_ch1.txt", ios::in);
8      if(!in_ch1.is_open()){
9          cout<<"Opening error of the input file on the channel1"<<endl;
10         return -1;
11     }
12     vector<IN_TYPE> vi_cic_ch1;
13     int in1; //in1=[0 o 1], in1_bin=[-1 o 1]
14     OUT_TYPE in1_bin;
15     OUT_TYPE vout_cic_ch1;
16     vector<OUT_TYPE> cic_output_ch1;
17     while(!in_ch1.eof()){
18         in_ch1>>in1;
19         vi_cic_ch1.push_back(IN_TYPE(in1));
20     }
21     in_ch1.close();
22
23     ifstream in_ch2 ("cic_in_ch2.txt", ios::in);
24     if(!in_ch2.is_open()){
25         cout<<"Opening error of the input file of the channel2"<<endl;
26         return -1;
27     }
28     vector<IN_TYPE> vi_cic_ch2;

```

```
29     int in2; //in1=[0 o 1], in1_bin=[-1 o 1]
30     OUT_TYPE in2_bin;
31     OUT_TYPE vout_cic_ch2;
32     vector<OUT_TYPE> cic_output_ch2;
33     while(!in_ch2.eof()){
34         in_ch2>>in2;
35         vi_cic_ch2.push_back(IN_TYPE(in2));
36     }
37     in_ch2.close();
38
39     ofstream out_ch1 ("cic_filter_out_ch1.txt");
40     ofstream out_ch2 ("cic_filter_out_ch2.txt");
41     for (unsigned i=0; i<vi_cic_ch1.size(); i++){
42         CCS_DESIGN(dws_cic_bittrue)(vi_cic_ch1[i], vi_cic_ch2[i],
43             vout_cic_ch1, vout_cic_ch2);
44         if (i==1 || (i-1)%8==0){
45             out_ch1<<vout_cic_ch1<<endl;
46             out_ch2<<vout_cic_ch2<<endl;
47         }
48     }
49     out_ch1.close();
50     out_ch2.close();
51     CCS_RETURN(0);
52 }
```

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