Task models

A task model is a definition of an instanciable task, ie

```
• a name
```

- a list of ports accepting resources from different resource types
- a list of available implementations

```
tg = TaskModel(
'tg',
outfifos = ['output'] )
```

Task implementations

Software Task

A software task implementation is defined by:

- a function to call
- a list of C source files (even if some files are shared between tasks, you must redeclare them in each using task implementation definition)
- a list of defines to be defined later (arg defines = { } on task instanciation) see PerTaskCflags

Hardware Task

An hardware implementation is in fact a corpocessor (which must be implemented in simulator/synthesis context and declared in DSX) doing the same thing as the task.

The following restrictions apply:

- Task must only use MwMr fifos for data exchange
- Task must not be RealTime?

Declaration consists of:

- Coprocessor reference
- Optional coprocessor arguments

Virtual Task

])

If a task follows constraints for having an hardware implementation, it may be virtually implemented in hardware, which means it will be run in simulator's context as if it were a coprocessor, actually using C implementation.

This kind if virtualization is only available for SystemC simulation (ie not VHDL), and you must have defined a software implementation. If your task has a SyntheticTask?() declaration and an HwTask? at the same time, the implementation chosen by DSX for simulation purposes will be unpredictable, you should avoid such situations.

Task Synthesis

Using Ugh, a task may be synthetized, this is not supported at this time.