

## First step

Create your python-based soc description, you'll need dsx and [SocLib](#) modules:

```
from dsx import *
from soclib import *
```

Always import those two modules in this order or you'll experience some strange import failures.

## Task declaration

Then declare some tasks. See [DsxTaskModel](#), [DsxTasks](#), [SrlApi](#)

## Tcg

Now you can create a Task and Control Graph. See [DsxTcg](#).

## Posix Test

Now create a posix version of your application

```
px = Posix()

tcg.generate(px)

TopMakefile(px)
```

## Compile, test, debug

See [DsxPosix](#).

## Create your SoC

See [SocCreation?](#).

## Mapping

See [DsxMapping](#).

## Compile the simulator, ?

```
muteks = Muteks()
caba = Caba()
mapper.generate( muteks, caba )

TopMakefile( muteks, caba )
```

## Run, debug

You may change some flags about [MuteksS](#).

You're on your own, use CabaSimulatorFlags, maybe use GtkWave?.