# First step

Create your python-based soc description, you'll need dsx and <u>SocLib</u> 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 <u>DsxTaskModel</u>, <u>DsxTasks</u>, <u>SrlApi</u>

# Tcg

Now you can create a Task and Control Graph. See <u>DsxTcg</u>.

# Posix Test

Now create a posix version of your application

```
tcg.generate(Posix())
```

# Compile, test, debug

See <u>DsxPosix</u>.

# Create your SoC

See SocCreation?.

# Mapping

See <u>DsxMapping</u>.

# Compile the simulator, ?

```
mapper.generate( MutekS() )
```

or

```
mapper.generate( MutekH() )
```

# Run, debug

You may change some flags about <u>MutekS</u>.

You're on your own, use <u>CabaSimulatorFlags</u>, maybe use GtkWave?.